

SOLVING THE INVERSE KINEMATICAL PROBLEM OF A ROBOT ARM BY USING GROEBNER BASIS

Title	SOLVING THE INVERSE KINEMATICAL PROBLEM OF A ROBOT ARM BY USING GROEBNER BASIS
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Abstract	The inverse kinematical problem of a robot arm is a problem to find some appropriate joint configurations for a pair of position and direction of a robot hand which is represented by a polynomial equations system. The system is solved by employing Groebner basis notion. Thus, the appropriate joint configurations for a pair of position and direction of the robot hand are obtained.
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