

Task priority assignment with collision avoidance.

Stefano De Filippis & Marco Menchetti

October 2019

Abstract

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In this paper we will face the problem of task priority resolution using a fast computation of the priority matrix (here *Flacco Matrix*) and the resulting joint velocities. In this framework, several degrees of freedom have been saturated assigning task to collision avoidance for finite number of control points.

Introduction

1 Task priority matrix

2 Control algorithm

3 Code

4 Results

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