## Kinematic control of mobile manipulators subject to physical constraints and noise disturbances

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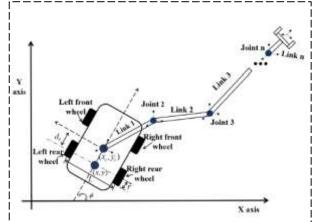
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- Considering the kinematic control of wheeled mobile manipulator subject to physical limits and external noise disturbances.
- Proposing an HMOC scheme incorporating path following and physical constraints' compliance based on the quadratic program.
- Validating efficiency of the HMOC scheme and the designed solver via simulation.



Schematics of the wheeled mobile manipulator used in this study.