

# Summary of papers

April 24, 2018

*Kinematic Programming alternatives for redundant manipulators, John Bailieul, 1984*

- Introduces the concept of extended Jacobian which is a redundancy resolution technique that can possibly avoid singularities generated by Pseudo inverse (Moore Penrose inverse) in a hyper-redundant manipulator.

*Real-Time obstacle avoidance for manipulators and mobile robots, Oussama Khatib, 1986*

- Uses artificial repelling potential and force induced by the same in Lagrangian formulation to avoid obstacles.

*A New Geometrical Approach to Solve Inverse kinematics of Hyper Redundant Robots with variable link length, Annisa Jamali, International Conference on Mechatronics, 2011*

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