1   Intro - lightboard

Everything follows right hand rule
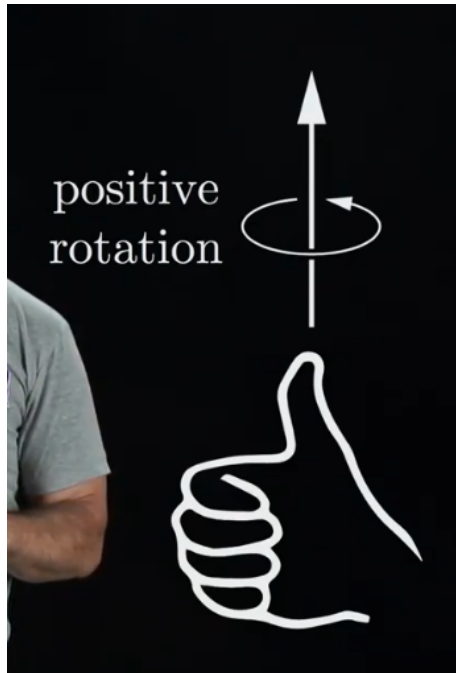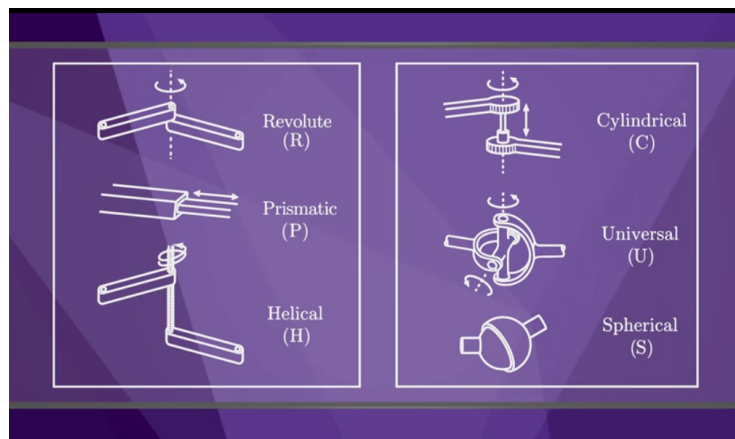

Figuur 1:

2   Foundation of mobile robotics ch-2

2.1   Degrees of freedom rigid body

- **Configuration** - A specific position of the position of all points of robot

- **C-space** - The space of all configuration

- **degrees of freedom** - dimension of c space

- Rigid body has 6 degrees of freedom

- dof - $\sum(freedompoints) - no.of.constrains$

points	dof	no.of.constrains	constrans
point A	2	0	-
point B	2	1	d_{ab}
Point C	2	2	$d_{ac}, d_b c$

- $dof = m(N-1) - \sum_{i=1}^{J} c_i$

1

Figuur 2: