

If  $A$  has  $i$  contacts with possibly moving bodies, then the set of feasible twists for  $A$  is the polyhedral convex set

$$V = \{\mathcal{V}_A \mid \mathcal{F}_i^T(\mathcal{V}_A - \mathcal{V}_{j(i)}) \geq 0 \text{ for all } i\}$$



If  $A$  has  $i$  contacts with stationary bodies, then the set of feasible twists for  $A$  is the polyhedral convex cone

$$V = \{\mathcal{V}_A \mid \mathcal{F}_i^T \mathcal{V}_A \geq 0 \text{ for all } i\}$$

