A Real-time Model Predictive Control of a Non-linear Robotic system Using a Physics Engine

Michael Shell
School of Electrical and
Computer Engineering
Georgia Institute of Technology
Atlanta, Georgia 30332–0250
Email: http://www.michaelshell.org/contact.html

Homer Simpson
Twentieth Century Fox
Springfield, USA
Email: homer@thesimpsons.com

James Kirk
and Montgomery Scott
Starfleet Academy
San Francisco, California 96678–2391
Telephone: (800) 555–1212
Fax: (888) 555–1212

Abstract—The abstract goes here.

I. INTRODUCTION

Robotic hardware is getting more capable and complex at an enormous rate with the improvement of science and technology. However, with the increased complexity, it is also getting increasingly difficult to design efficient controllers for the robots.

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II. CONCLUSION

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