
Robotics: Erratum

Chapter 3: Differential Kinematics and Statics

- pag. 109: Replace the phrase “According to the coordinate transformation (3.10), one can write” with the phrase “According to the coordinate transformation (3.12), one can write”.
- pag. 139: In the sentence before Eq. (3.86) replace the phrase “(see Problem 3.19)” with the phrase “(see Problem 3.17)”.
- pag. 160: The correct statement of Problem 3.16 is: “Prove (3.85).”.

Chapter 7: Dynamics

- pag. 265: Replace the phrase “which greatly simplifies computation of the second term in (4.34).” with the phrase “which greatly simplifies computation of the second term in (7.30).”.
- pag. 288: The term $\boldsymbol{\omega}_i^i \times (\bar{\mathbf{I}}_i^i \boldsymbol{\omega}_i^i)$ is added two times to the right-hand side of (7.113). One occurrence must be dropped.

Chapter 10: Visual Servoing

- pag. 453: The correct value of the initial camera pose is

$$\mathbf{x}_c(0) = [1 \quad 1 \quad 0.5 \quad \pi/4]^T.$$

Moreover, operational space vectors $\mathbf{x}_c(0)$, $\mathbf{x}_{c,o}(0)$, and $\mathbf{x}_{d,o}(0)$ include both position and orientation coordinates. Therefore the dimension “m” (meters) is incorrect and must be dropped.

- pag. 466: The correct statement of Problem 10.7 is: “Show that the matrix \mathbf{R} which minimizes (10.57) is the matrix which maximizes the trace of $\mathbf{R}^T \mathbf{K}$.”



<http://www.springer.com/978-1-84628-641-4>

Robotics

Modelling, Planning and Control

Siciliano, B.; Sciavicco, L.; Villani, L.; Oriolo, G.

2009, XXIV, 632 p. 298 illus. With online files/update.,

Hardcover

ISBN: 978-1-84628-641-4