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The revised and updated third edition of Introduction to Robotics: Analysis, Control, Applications, offers a guide to the fundamentals of robotics, robot components and subsystems and applications. The author—a noted expert on the topic—covers the mechanics and kinematics of serial and parallel robots, both with the Denavit-Hartenberg approach as well as screw-based mechanics.

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(In the sense of where the links of the robot are situated.) The answer is the robot's configuration: a specification of the positions of all points of the robot. Since the robot's links are rigid and of known shape, only a few numbers are needed to represent the robot's configuration.

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(In the sense of where the links of the robot are situated.) The answer is the robot's configuration: a specification of the positions of all points of the robot. Since the robot's links are rigid and of known shape,1 only a few numbers are needed to represent the robot's configuration.

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