

Complex Robotic Systems: Modeling, Control, and Planning using Dual Quaternion Algebra

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Date: Friday, October 28, 2022 11:00-12:00

**Venue: 31A, 3F Faculty of Engineering Bldg. 2 /
Online (hybrid)**

Abstract:

To manage the complexity of modern robotic systems, the modeling, control, planning, and high-level task descriptions are usually dealt with using different mathematical representations. This results in a theoretical patchwork that might introduce unnecessary mathematical artifacts in the system, making both the analysis and design more difficult. In this talk, I will present our efforts to unify robot modeling, control, and planning using dual quaternion algebra with some applications.



Registration (Venue/Online)
<https://forms.gle/6c8viMSUVH1oPXB69>
Please register by Oct. 24.