## Trajectory Planning for Automatic Machines and Robots Luigi Biagiotti, Claudio Melchiorri

## Errata

## Changes from first printing to Jenuary 16, 2014

Conventions: each line of text (including figures' captions) and each line of a displayed equation are counted as a line. Negative line numbers mean number of lines from the bottom of the page. First line on page = 1, last line on page = -1.

• Page 48, line -1. (October 23, 2009) In the expression for the computation of  $v_c$  an exponential function is missing. The right expression is

$$\sigma_c = \frac{1}{2\int_0^{\frac{1}{2}} e^{-\sigma f(\tau,\lambda)} d\tau}.$$

• Page 49, line 6. (October 23, 2009) In the expression of the acceleration  $\ddot{q}_N(\tau)$  of the normalized trajectory, the sign d of the derivative is missing. The correct expression is

$$\ddot{q}_{\scriptscriptstyle N}( au) = - \mathtt{v}_c \, \sigma \, rac{df( au, \lambda)}{d au} e^{-\sigma \, f( au, \lambda)}.$$

• Page 89, lines 12-16. (November 3, 2009) The expression of the double S trajectory for  $t \in [T - T_d + T_{j2}, T - T_{j2}]$  can be simplified in the following way

$$\begin{cases} q(t) &= q_1 - \mathbf{v}_1 (T - t) + \frac{\mathbf{a}_{lim_d}}{6} \Big( 3(T - t)^2 - 3T_{j2}(T - t) + T_{j2}^2 \Big) \\ \dot{q}(t) &= \mathbf{v}_1 - \mathbf{a}_{lim_d} \left( T - t - \frac{T_{j2}}{2} \right) \\ \ddot{q}(t) &= -\mathbf{j}_{max} T_{j2} = \mathbf{a}_{lim_d} \\ q^{(3)}(t) &= 0 \end{cases}$$

- Page 91, Fig 3.18. (David Richter, June 25, 2013) The rectangular block with the text: "Compute the trajectory parameters according to (3.26a), (3.26b) and (3.26b)" should say "Compute the trajectory parameters according to (3.26a), (3.26b), and (3.26c)".
- Page 179, Example 4.9 (Philip Freeman, October 22, 2010). The numerical values of matrix A and vectors c and  $\omega$  are wrong. The right expressions result

$$\boldsymbol{A} = \begin{bmatrix} 15 & 2.5 & 0 & 0 & 0 & 0 & 0 \\ 0 & 9 & 2 & 0 & 0 & 0 & 0 \\ 0 & 2 & 6 & 1 & 0 & 0 & 0 \\ 0 & 0 & 1 & 6 & 2 & 0 & 0 \\ 0 & 0 & 0 & 2 & 14 & 5 & 0 \\ 0 & 0 & 0 & 0 & 5 & 13 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 & 9 \end{bmatrix}$$

$$c = \begin{bmatrix} -36, & 15, & 39, & -12, & -10.8, & -5.2, & -20 \end{bmatrix}^T$$

and

- Page 326, line 14. (March 30, 2010) The transfer function  $G(s) = \frac{2s+1}{s^2+2s+100}$  must be changed in  $G(s) = \frac{2s+100}{s^2+2s+100}$ .
- Page 329, line -6. (March 30, 2010) It is necessary to specify the meaning of  $n_i$ . Therefore at the end of the sentence "where the pairs  $(p_i, p_i^*)$  represent the (complex conjugate) poles of G(z)" it is necessary to add "of multiplicity  $n_i$ ".
- Page 329, line -4. (March 30, 2010) Under the first block of the figure it is necessary to replace  $(\omega \psi_{n1}, \delta_1)$  with  $(\omega_{n1}, \delta_1)$ .
- Page 409, line 7. (Pedro Reboredo, July 6, 2009) In the expression of  $a_4 = 5p_0 4p_1 + 6p_2 4p_3 + p_4$ the coefficient of  $p_0$  is 1 and not 5, therefore the right expression is  $a_4 = p_0 - 4p_1 + 6p_2 - 4p_3 + p_4$ .
- Page 411, line -6. (Jenuary 16, 2014) The coefficient c is not equal to zero. Therefore,  $c = -900 |\mathbf{p}_{5,k} \mathbf{p}_{0,k}|^2$ .
- Page 425, line 13. (July 15, 2014) The expression  $q(t_f) = \dots$  should be  $q(t_{max}) = \dots$
- Page 425, line -2. (July 15, 2014) The expression  $q(t_f) = 0$  should be  $q(t_{min}) = 0$ .
- Page 486, line 15. (Pedro Reboredo, July 6, 2009) In the expression of  $a_4 = 5p_0 4p_1 + 6p_2 4p_3 + p_4$ the coefficient of  $p_0$  is 1 and not 5, therefore the right expression is  $a_4 = p_0 - 4p_1 + 6p_2 - 4p_3 + p_4$ .
- Page 467, line 11. (September 6, 2009) The word "coefficient" should be plural.