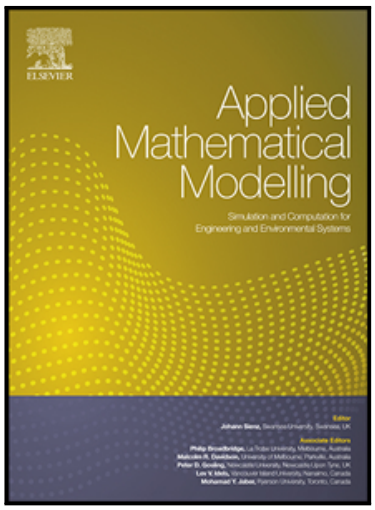

Motion Equations of Cooperative Multi Flexible Mobile Manipulator via Recursive Gibbs-Appell Formulation

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Highligths:

- The model of time-varying multi flexible mobile manipulators is proposed.
- The cooperative mobile manipulator with the closed kinematic chain is illustrated.
- The Gibbs- Appell formulation has been upgraded by using Lagrange multiplayer.
- The maximum dynamic load caring capacity has been evaluates for a common object.