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

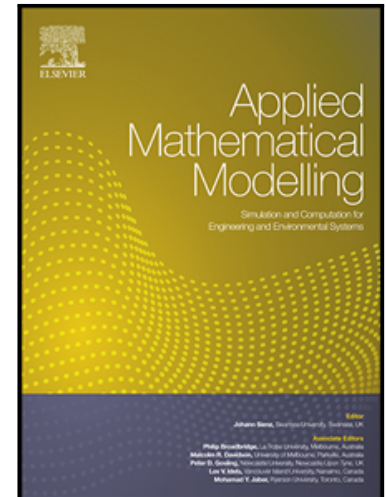
M.H. Korayem , S.F. Dehkordi

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Highlights:

- 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 multiplier.
- The maximum dynamic load carrying capacity has been evaluated for a common object.

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