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Control of two manipulation points of a cooperative transportation system with two car-like vehicles following parametric curve paths

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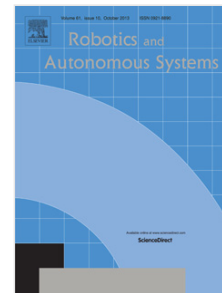
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- This paper presents a new path-following control law of a transportation system.
- The law makes the two manipulation points follow their parametric curve paths.
- It is possible to specify the movement and rotation of the carrier quantitatively.
- Asymptotic stability is guaranteed by Lyapunov's second method.
- The validity of the new control law has been verified experimentally.

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