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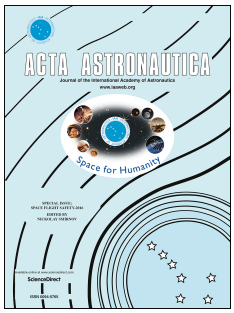

An integrated control scheme for space robot after capturing non-cooperative target

Mingming Wang, Jianjun Luo, Jianping Yuan, Ulrich Walter

PII: S0094-5765(17)31640-5

DOI: 10.1016/j.actaastro.2018.04.016

Reference: AA 6816

To appear in: *Acta Astronautica*

Received Date: 11 November 2017

Revised Date: 22 March 2018

Accepted Date: 10 April 2018

Please cite this article as: M. Wang, J. Luo, J. Yuan, U. Walter, An integrated control scheme for space robot after capturing non-cooperative target, *Acta Astronautica* (2018), doi: 10.1016/j.actaastro.2018.04.016.

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Highlights：

1. Dynamic equations of space robot in operational space were derived.
2. Elementary functions were used to delineate the target's detumbling path.
3. A coordination control scheme was implemented both for base and end-effector.
4. Target mass properties were estimated during detumbling process.

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