RIGID BODY TIME-STEPPING SCHEMES IN A QUASI-STATIC SETTING

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In [1] a rigid-body time-stepping scheme was used to simulate manipulation tasks in a quasi-static setting. The integration scheme is formulated as a *linear complementarity problem* and it is used in controlling a meso-scale system. In this talk we extend the analysis from [1] and analyze transition changes as well as convergence issues.

REFERENCES

[1] P. Cheng, D. Cappelleri, B. Gavrea, V. Kumar, *Planning and Control of Mesoscale Manipulation Tasks with Uncertainties*, Proceedings of Robotics: Science and Systems (3rd: 2007, Atlanta GA), MIT PRESS, 2008, ISBN 978-026-252-4841