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III. PROBLEM STATEMENT AND CONTROLLER FORMULATION The Control Objective Is To Design A Link Position Tracking Controller For The Tendon Driven Robot Manipulator Model Given By (1),(2) And (3) Under The Constraints That Acceleration And Velocity Measurements Of Links And Actuators And May 2th, 2024

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Changing The Base Of The Stream, Taking One Integer Argument Of 10, 8 Or 16 For Decimal, Base 8 Or Base 16 Respectively. Setbase() Is Parameterized Stream Manipulator By Taking Argument, We Have To Include `lomanip.h` Header File. Table 18.5: Stream Base Operator And Function. - Program Example: //using Hex, Mar 1th, 2024

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