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(3.2), namely, $V = f^T f$. The basic
idea of the method is function for this
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*Slotine & Li, Applied Nonlinear Control
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Nonlinear Control” (Slotine and Li, Prentice-Hall, 1991) and is one of the most cited researcher in both systems science and robotics. He was a member of the French National Science Council from 1997 to 2002, and a member of Singapore’s

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