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The aim of the paper is to study the kinematics of the manipulator. The articulated robot with a spherical wrist has been used for this purpose. The Comau NM45 Manipulator has been chosen for the kinematic model study. The manipulator contains six revolution joints. Pieper's approach has been employed to study the kinematics (inverse) of the robot manipulator.

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Review report Corman-Drosten et al. Eurosurveillance 2020

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