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International Conference on Multibody System Dynamics - IMSD2012, Stuttgart, Germany, May29-June1,2012. [6]L. Bencsik and L.L. Kovács, "Stability case study of an underactuated service robot," in Proceedings of 11th Conference on Dynamical Systems - Theory and Applications (DSTA), December5-8,2011,Lodz,Poland,pp.89-94.

Dynamic analysis and tracking control of underactuated

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underactuated systems, defined as systems in which the number of degrees of freedom exceeds the number of inputs. The governing equations of motion can be written in the form of differential-algebraic equations (DAEs) with a mixed set of holonomic and control constraints. The rotationless formulation of multibody dynamics will be considered [1].

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