

Publications of Charles W. Wampler

Books

- [1] Bates, D. J., Hauenstein, J. D., Sommese, A. J., and Wampler, C. W., *Numerically Solving Polynomial Systems with Bertini*, SIAM Books, Philadelphia, PA, 2013.
- [2] Sommese, A. J., and Wampler, C. W., *Numerical Solution of Systems of Polynomials Arising in Engineering and Science*, World Scientific, Singapore, 2005.
- [3] Wampler, C. W., *Computer Methods in Manipulator Kinematics, Dynamics, and Control: A Comparative Study*, Ph. D. Thesis, Stanford University, December 1984.

Edited Books

- [1] Bates, D., Besana, G.-M., Di Rocco, S., and Wampler, C., (Eds.), *Interactions of Classical and Numerical Algebraic Geometry*, Contemporary Mathematics 496, Amer. Math. Soc., Providence, R.I., 2009.

Book Chapters

- [1] Wampler, C.W., and Sommese, A.J., “Applying Numerical Algebraic Geometry to Kinematics,” Chapter 5, *21st Century Kinematics*, Springer, 2012, pp. 125–159.
- [2] Sommese, A., Verschelde, J., and Wampler, C., “Introduction to Numerical Algebraic Geometry,” Chapter 8, *Solving Polynomial Equations: Foundations, Algorithms, and Applications*, Algorithms and Computation in Mathematics 14, A.Dickenstein, I.Z.Emiris (Eds.), Springer, 2005, pp. 339–392.
- [3] Wampler, C.W., “Wrist singularities: Theory and practice,” *The Robotics Review 2*, O. Khatib, J. Craig, and T. Lozano-Pérez (Eds.), MIT Press, 1992, pp. 173–189.

Articles

- [1] J.D. Hauenstein, C. Hills, A.J. Sommese, and C.W. Wampler, “Branch points of homotopies: Distribution and probability of failure,” *Applied Math. & Computation*, 493 129273. DOI:10.1016/j.amc.2024.129273
- [2] A. Baskar, M. Plecnik, J.D. Hauenstein, and C.W. Wampler, “A numerical continuation approach using monodromy to solve the forward kinematics of cable-driven parallel robots with sagging cables,” *Mechanism & Machine Theory*, Volume 195, DOI:10.1016/j.mechmachtheory.2024.1056092024.
- [3] A. Baskar, M. Plecnik, J.D. Hauenstein, and C.W. Wampler, “A real-time algorithm for computing the tension force in a suspended elastic sagging cable,” *Proceedings MSR-RoManSy 2024*, May 22-25, 2024 Springer Nature, DOI:10.1007/978-3-031-60618-2.
- [4] M. He, C.W. Wampler, *et al.*, “Revealing the mechanism behind sudden capacity loss in lithium metal batteries,” *J. Electrochem. Soc.*, 170 100528. DOI:10.1149/1945-7111/ad01e7; Erratum: *J. Electrochem. Soc.*, 171 029001. DOI: 10.1149/1945-7111/ad1f36.
- [5] E. Baker, C. Wampler, and D. Baker, “Triply invertible scarf sewing adventures (and instructions),” *J. Mathematics and the Arts*, 2023. DOI:10.1080/17513472.2023.2200897
- [6] R. Fabbri, *et al.*, “Trifocal relative pose from lines at points,” *IEEE Trans. Pattern Analysis Machine Intelligence*, 45:6:7870-7884, 2023.
- [7] S. N. Sherman, J. D. Hauenstein, and C. W. Wampler, “Advances in the theory of planar curve cognates,” *J. Mech. Robotics*, 14:3:2022. DOI:10.1115/1.4052806.
- [8] S. N. Sherman, J. D. Hauenstein, and C. W. Wampler, “A general method for constructing planar cognate mechanisms,” *J. Mech. Robotics*, 13:3:2021. DOI:10.1115/1.4050293.
- [9] S. N. Sherman, J. D. Hauenstein, and C. W. Wampler, “Curve cognate constructions made easy,” *Proc. ASME Design Engineering Tech. Conf.*, (virtual), Aug. 17-19, 2020, DOI:10.1115/DETC2020-22409.
- [10] R. Fabbri, *et al.*, “Trifocal relative pose from lines at points and its efficient solution: expanded version

with supplementary material,” Conf. Computer Vision & Pattern Recognition (CVPR 2020), Seattle, June 16-18, 2020.

[11] M. W. Verbrugge, C. W. Wampler, and D. R. Baker, “Smoothing methods for numerical differentiation to identify electrochemical reactions from open-circuit-potential data,” *J. Electrochem. Soc.*, 165:16:A4000-A4011, 2018. DOI:10.1149/2.0951816jes

[12] M. W. Verbrugge and C. W. Wampler, “On the optimal sizing of batteries for electric vehicles and the influence of fast charge,” *J. Power Sources*, 384:312-317, 2018. DOI:10.1016/j.jpowsour.2018.02.064
Corrigendum, 396:831-832, 2018. DOI:10.1016/j.jpowsour.2018.06.076

[13] Hauenstein, J.D., Sherman, S.N., and Wampler, C.W., “Exceptional Stewart-Gough platforms, Segre embeddings, and the special Euclidean group,” *SIAM J. Appl. Algebra Geometry*, 2:1:179–205, 2018. DOI:10.1137/17M1114284

[14] D. A. Brake, D. J. Bates, W. Hao, J. D. Hauenstein, A. J. Sommese, and C. W. Wampler, Algorithm 976: Bertini_real: Numerical Decomposition of Real Algebraic Curves and Surfaces. *ACM Trans. Math. Softw.* 44, 1, Article 10 (July 2017). DOI:10.1145/3056528

[15] D. J. Bates, D. A. Brake, J. D. Hauenstein, A. J. Sommese, and C. W. Wampler, “Homotopies for connected components of algebraic sets with application to computing critical sets,” In: Blömer J., Kotsireas I., Kutsia T., Simos D. (eds) *MACIS 2017. Lecture Notes in Computer Science*, vol 10693. Springer, Cham. DOI:10.1007/978-3-319-72453-9_8

[16] Hauenstein, J.D., and Wampler, C.W., and Pfuner, M., “Synthesis of three-revolute spatial chains for body guidance,” *Mech. Mach. Theory*, 110:61-72, 2017. DOI:10.1016/j.mechmachtheory.2016.12.008

[17] Hauenstein, J.D., and Wampler, C.W., “Unification and extension of intersection algorithms in numerical algebraic geometry,” *Applied Math. Comp.*, 293:226-243, 2017. DOI:10.1016/j.amc.2016.08.023.

[18] Alkestiri, S. M., Myszka, D. H., Murray, A. P., and Wampler, C. W., “Singularity traces of single degree-of-freedom planar linkages that include prismatic and revolute joints,” *ASME J. Mechanism & Robotics*, 8(5):051003-051003-3, 2016. DOI:10.1115/1.4032410

[19] Brake, D. A., Hauenstein, J. D., Murray, A. P., Myszka, D. H., and Wampler, C. W., “The complete solution of Alt-Burmester synthesis problems for four-bar linkages,” *ASME J. Mechanism & Robotics*, 8:4:041018, 2016. DOI:10.1115/1.4033251

[20] Wampler, C.W. “Robotics,” In N.J. Higham, et al, eds., *The Princeton Companion to Applied Mathematics*, pp. 767–769. Princeton University Press, Princeton, NJ, USA, 2015.

[21] Alkestiri, S. M., Myszka, D. H., Murray, A. P., and Wampler, C. W., “Singularity traces of planar linkages that include prismatic and revolute joints,” *DETC2015-47390, Proc. ASME Int. Design Eng. Tech. Conf. (IDETC)*, Boston, MA, August 2–5, 2015.

[22] Plecnik, M., McCarthy, J.M., and Wampler, C.W., “Kinematic synthesis of a Watt I six-bar linkage for body guidance,” in *Advances in Robot Kinematics*, Springer, pp. 317–325, 2014

[23] Brake, D.A., Bates, D.J., Hao, W., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Bertini_real: Software for one- and two-dimensional real algebraic sets,” *Mathematical Software — ICMS 2014: 4th International Congress, Seoul, South Korea, August 5-9, 2014. Proceedings*, H. Hong & C. Yap, eds., Springer, pp. 175–182, 2014. DOI:10.1007/978-3-662-44199-2_29

[24] Bates, D.J., Brake, D.A., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “On computing a cell decomposition of a real surface containing infinitely many singularities,” *Mathematical Software — ICMS 2014: 4th International Congress, Seoul, South Korea, August 5-9, 2014. Proceedings*, H. Hong & C. Yap, eds., Springer, pp. 246–252, 2014. DOI:10.1007/978-3-662-44199-2_39

[25] Bates, D.J., Decker, W., Hauenstein, J.D., Peterson, C., Pfister, G., Schreyer, F.-O., and Wampler, C.W., “Comparison of probabilistic algorithms for analyzing the components of an affine algebraic variety,” *Applied Math. Comp.*, 231:619–633, 2014.

[26] Myszka, D.H., Murray, A.P., and Wampler, C.W., “Computing the branches, singularity trace, and critical points of single degree-of-freedom, closed-loop linkages,” *ASME J. Mechanism & Robotics*, 6:1:011006-

011006-10, 2013. DOI: 10.1115/1.4025752

[27] Abdallah, M., Wampler, C.W., and Platt, R., “Decoupled torque control of tendon-driven fingers with tension management,” *Int. J. Robotics Research*, 32(2):247-258, 2013.

[28] Hauenstein, J.D., and Wampler, C.W., “Isosingular sets and deflation,” *Found. Comp. Math. (FoCM)*, 13:3:371–403, 2013. DOI:10.1007/s10208-013-9147-y

[29] Besana, G.M., Di Rocco, S., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Cell decomposition of almost smooth real algebraic surfaces,” *Numerical Algorithms*, 63:4:645–678, 2013. DOI:10.1007/s11075-012-9646-y

[30] Hauenstein, J.D., and Wampler, C.W., “Numerically intersecting algebraic varieties via witness sets,” *Applied Math. Computation*, 219:5730–5742, 2013. DOI:10.1016/j.amc.2012.06.034.

[31] Permenter, F., Wampler, C., and Tedrake, R., A numerical algebraic geometry approach to regional stability analysis of polynomial systems. In *American Control Conference (ACC)*, June 2013 (pp. 2127-2132). IEEE.

[32] Myszka, D.H., Murray, A.P., and Wampler, C.W., “Mechanism branches, turning curves, and critical points,” paper DETC2012-70277, *Proc. ASME Int. Design Eng. Tech. Conf. (IDETC)*, Chicago, IL, August 12–15, 2012.

[33] Hauenstein, J., Sommese, A.J., and Wampler, C.W., “Regenerative cascade homotopies for solving polynomial systems,” *Applied Math. Comp.*, 218:4:1240–1246, 2011. DOI:10.1016/j.amc.2011.06.004

[34] Wampler, C.W., and Sommese, A.J., “Numerical Algebraic Geometry and Algebraic Kinematics,” *Acta Numerica*, 20:469–567, 2011. DOI:10.1017/S0962492911000067.

[35] Wampler, C.W., Hauenstein, J.D., and Sommese, A.J., “Mechanism Mobility and a Local Dimension Test,” *Mech. & Machine Theory*, 46:9:1193–1206, 2011. DOI:10.1016/j.mechmachtheory.2011.04.011

[36] Bates, D.J., Peterson, C., Sommese, A.J., and Wampler, C.W., “Numerical computation of the genus of an irreducible curve within an algebraic set,” *J. Pure & Applied Algebra*, 215:8:1844-1851, 2011.

[37] Arends, F., Ouaknine, J., and Wampler, C.W., “On Searching for Small Kochen-Specker Vector Systems,” *Proc. 37th Intl. Workshop on Graph-Theoretic Concepts in Computer Science (WG’11)*, Teplá Monastery, Czech Republic, June 21–23, 2011.

[38] Platt, R., Abdallah, M.E., and Wampler, C.W., “Multiple-Priority Impedance Control,” *Proc. 2011 IEEE Conf. Robotics & Automation (ICRA)*, Shanghai, May 9–13, 2011.

[39] Abdallah, M.E., and Wampler, C.W., “Torque control of underactuated tendon-driven fingers,” *Mech. Sci.*, 2:1:83-90, 2011. Available at www.mech-sci.net/2/83/2011.

[40] Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Regeneration homotopies for solving systems of polynomials,” *Math. Comp.*, AMS, 80:273:345–377, 2011.

[41] Abdallah, M.E., Platt, R., Wampler, C.W., and Hargrave, B., “Applied joint-space torque and stiffness control of tendon-driven fingers,” *Proc. IEEE-RAS Intl. Conf. Humanoid Robots*, Nashville, TN, Dec. 6–8, 2010.

[42] Abdallah, M.E., Wampler, C.W., and Platt, R., “Object impedance control using a closed-chain task definition,” *Proc. IEEE-RAS Intl. Conf. Humanoid Robots*, Nashville, TN, Dec. 6–8, 2010.

[43] Platt, R., Abdallah, M.E., and Wampler, C.W., “Multi-Priority Cartesian Impedance Control,” *Robotics: Science & Systems Conf. (RSS)*, Zaragoza, Spain, June 27-30, 2010.

[44] Di Rocco, S., Eklund, D., Sommese, A.J., and Wampler, C.W., “Algebraic \mathbb{C}^* -actions and the inverse kinematics of a general 6R manipulator,” *Applied Math. & Comp.*, 216:9: 2512–2524, 2010.

[45] Bates, D.J., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Stepsize control for adaptive multiprecision path tracking,” in *Interactions of Classical and Numerical Algebraic Geometry*, D. Bates, G.-M.

- Besana, S. Di Rocco, and C. Wampler (Eds.), *Contemporary Mathematics*, Vol. 496, pp. 21–31, Amer. Math. Soc., 2009.
- [46] Gao, D., and Wampler, C.W., “Head Injury Criterion: Assessing the Danger of Robot Impact,” *IEEE Robotics & Automation Magazine*, pp. 71–74, Dec. 2009.
- [47] Bates, D.J., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Adaptive multiprecision path tracking,” *SIAM Journal on Numerical Mathematics*, 46:2:722-746, 2008.
- [48] Sommese, A.J., and Wampler, C.W., “Exceptional sets and fiber products,” *Foundations of Computational Mathematics*, 8:2:171-196, 2008.
- [49] Bates, D.J., Hauenstein, J.D., Sommese, A.J., and Wampler, C.W., “Software for numerical algebraic geometry: a paradigm and progress towards its implementation,” in *Software for Algebraic Geometry*, IMA Volumes in Math. and its Applications, Vol. 148, eds. M. Stillman, N. Takayama, and J. Verschelde, Springer, 2008.
- [50] Sommese, A.J., Verschelde, J., and Wampler, C.W., “Solving polynomial systems equation by equation,” in *Algorithms in Algebraic Geometry*, IMA Volumes in Math. and its Applications, Vol. 146, eds. A. Dickenstein, F.-O. Schreyer, and A.J. Sommese, Springer, 2008.
- [51] Lu, Y., Bates, D.J., Sommese, A.J., and Wampler, C.W., “Finding all real points of a complex curve,” In *Proceedings of the Midwest Algebra, Geometry and Its Interactions Conference*, Contemporary Mathematics, AMS, 448:183–205, 2007.
- [52] Izquierdo, L.E., Shi, J., Hu, S.J., and Wampler, C. W., “Feedforward control of multistage assembly processes using programmable tooling,” *Trans. of the NAMRI/SME, Society of Manufacturing Engineers*, 2007.
- [53] Wampler, C.W., Larson, B.T., Erdman, A.G., “A New Mobility Formula for Spatial Mechanisms,” paper DETC2007-35574, Proc. ASME Design Engineering Technical Conf., Las Vegas, Sept. 4–7, 2007.
- [54] Wampler, C.W., “Numerical algebraic geometry and kinematics,” Proc. 2007 Int. Workshop on Symbolic-Numeric Computation (SNC’07), London, ON, Canada, July 25-27, 2007, J. Verschelde and S. Watt, Eds., Assoc. Computing Machinery, New York.
- [55] Wampler, C., “On a rigid body subject to point-plane constraints,” *ASME J. of Mechanical Design*, 128:1:151–158, Jan. 2006.
- [56] Allgower, E.L., Bates, D.J., Sommese, A.J., and Wampler, C.W., “Solution of polynomial systems derived from differential equations,” *Computing*, Online First, SpringerLink, August 25, 2005; *Computing*, 76:(1-2):1-10, Jan 2006.
- [57] Sommese, A., Verschelde, J., and Wampler, C., “An intrinsic homotopy for intersecting algebraic varieties,” *Journal of Complexity*, Vol. 21, No. 4, 2005, pp. 593–608.
- [58] Wampler, C., “Locating N points of a rigid body on N given planes,” paper DETC2004-57182, Proc. ASME Design Engineering Technical Conf., Salt Lake City, Sept. 28–Oct. 2, 2004.
- [59] Wampler, C., “Singular foci of planar linkages,” *Mechanism Machine Theory*, Vol. 39, No. 11, 2004, pp 1123–1138.
- [60] Wampler, C., “The geometry of singular foci of planar linkages,” *Mechanism Machine Theory*, Vol. 39, No. 11, 2004, pp 1139-1153.
- [61] Sommese, A., Verschelde, J., and Wampler, C., “Homotopies for intersecting solution components of polynomial systems,” *SIAM J. Numerical Analysis*, Vol. 42, No. 4, 2004, pp. 1552–1571.
- [62] Sommese, A., Verschelde, J., and Wampler, C., “Numerical factorization of multivariate complex polynomials,” *Theoretical Computer Science*, Vol. 315, No. 2–3, 2004, pp. 651–669.
- [63] Su, H.-J., Wampler, C., and McCarthy, J.M., “Geometric design of cylindric PRS serial chains,” *ASME J. Mechanical Design*, Vol. 126, No. 2, 2004, pp. 269–277. (Also in: Proc. ASME Design Engineering Technical Conf., Chicago, September 26, 2003.)

- [64] Sommese, A., Verschelde, J., and Wampler, C., "Advances in polynomial continuation for solving problems in kinematics," *ASME J. Mechanical Design*, Vol. 126, No. 2, 2004, pp. 262–268. (Also in: Paper DETC2002/MECH-34254, Proc. ASME Design Engineering Technical Conf. (CDROM), Montreal, Quebec, Sept. 29-Oct. 2, 2002.)
- [65] Wampler, C., "Displacement analysis of spherical mechanisms having three or fewer loops," *ASME J. Mechanical Design*, Vol. 126, No. 1, 2004, pp. 93–100. (Also in: Paper DETC2002/MECH-34326, Proc. ASME Design Engineering Technical Conf. (CDROM), Montreal, Quebec, Sept. 29-Oct. 2, 2002.)
- [66] Fisch, A., Nikitzuk, J., Weinberg, B., Melli-Huber, J., Mavroidis, C., and Wampler, C., "Development of an electro-rheological fluidic actuator and haptic systems for vehicular instrument control," Proc. ASME IMECE Conference, Washington, D.C., Nov. 15–21, 2003.
- [67] Melli-Huber, J., Weinberg, B., Fisch, A., Nikitzuk, J., Mavroidis, C., and Wampler, C., "Electro-rheological fluidic actuators for haptic vehicular instrument controls," Proc. 2003 IEEE Haptics Symposium, Los Angeles, Mar. 22–23, 2003.
- [68] Sommese, A., Verschelde, J., and Wampler, C., "Numerical irreducible decomposition using PHCpack." In *Algebra, Geometry and Software Systems*, ed. M. Joswig and N. Takayama, pp. 109–130, Springer-Verlag 2003.
- [69] Sommese, A., Verschelde, J., and Wampler, C., "Symmetric functions applied to decomposing solution sets of polynomial systems," *SIAM J. Numerical Analysis*, Vol. 40, No. 6, pp. 2026–2046, 2002.
- [70] Sommese, A., Verschelde, J., and Wampler, C., "A method for tracking singular paths with application to the numerical irreducible decomposition," In *Algebraic Geometry, a Volume in Memory of Paolo Francia*, ed. by M.C. Beltrametti, et al., pp. 329–345, W. de Gruyter, 2002.
- [71] Sommese, A., Verschelde, J., and Wampler, C., "Numerical irreducible decomposition using projections from points on the components," In *Symbolic Computation: Solving Equations in Algebra, Geometry, and Engineering*, ed. E.L. Green, et al., Contemporary Mathematics, volume 286, pp. 37–51, AMS, 2001.
- [72] Sommese, A., Verschelde, J., and Wampler, C., "Using monodromy to decompose solution sets of polynomial systems into irreducible components," In *Application of Algebraic Geometry to Coding Theory, Physics, and Computation*, ed. C. Ciliberto, et al., pp. 297–315, Kluwer Academic Publishers, 2001.
- [73] Wampler, C., "Solving the kinematics of planar mechanisms by Dixon determinant and a complex-plane formulation," *ASME J. Mechanical Design*, Vol. 123, No. 3, 2001, pp. 382–387. (Also in Proc. ASME Design Engr. Tech. Conf. (CDROM), Sept. 10–13, 2000, Baltimore, MD.)
- [74] Sommese, A., Verschelde, J., and Wampler, C., "Numerical decomposition of the solution sets of polynomial systems into irreducible components," *SIAM J. Numerical Analysis*, Vol. 38, No. 6, pp. 2022–2046, 2001.
- [75] Wampler, C., "Solving the kinematics of planar mechanisms," *ASME J. Mechanical Design*, Vol. 121, No. 3, 1999, pp. 387–391. (Also in Proc. ASME Design Engr. Tech. Conf. (CDROM), Sept. 13–16, 1998, Atlanta, Ga.)
- [76] Wampler, C., Morgan, A., and Sommese, A., "Complete solution of the nine-point path synthesis problem for four-bar linkages: Author's closure," *ASME J. Mechanical Design*, Vol. 119, No. 1, 1997, pp. 150–152.
- [77] Wampler, C.W., "Forward displacement analysis of general six-in-parallel SPS (Stewart) platform manipulators using soma coordinates," *Mechanism and Machine Theory*, Vol. 31, No. 3, 1996, pp. 331–337.
- [78] Wampler, C.W., "Isotropic coordinates, circularity, and Bezout numbers: Planar kinematics from a new perspective," Proc. ASME Design Engr. Tech. Conf. (CDROM), Aug. 18–22, 1996, Irvine, CA.
- [79] Sommese, A.J., and Wampler, C.W., "Numerical algebraic geometry," *Lectures in Applied Mathematics: The Mathematics of Numerical Analysis*, Vol. 32, American Mathematical Society, Providence, R.I., 1996, pp. 749–763.
- [80] Hollerbach, J.M., and Wampler, C.W., "The calibration index and a taxonomy for robot kinematic

calibration methods," *Int. J. of Robotics Research*, Vol. 15, No. 6, 1996, pp. 573–591.

[81] Hollerbach, J.M., and Wampler, C.W., "The calibration index and the role of input noise in robot calibration," *Robotics Research: The Seventh International Symposium*, G. Giralt and G. Hirzinger, eds., Springer-Verlag, London, 1996, pp. 558–568.

[82] Wampler, C.W., Hollerbach, J.M., and Arai, T., "An implicit loop method for kinematic calibration and its application to closed-chain mechanisms," *IEEE Trans. Robotics and Automation*, Vol. 11, No. 5, 1995, pp. 710–724.

[83] Morgan, A.P., Sommese, A.J., and Wampler, C.W., "A product-decomposition theorem for bounding Bezout numbers," *SIAM J. Numer. Anal.*, Vol. 32, No. 4, 1995, pp. 1308–1325.

[84] Wampler, C.W., "An efficient start system for multi-homogeneous polynomial continuation," *Numerische Mathematik*, 66:517–523, 1994.

[85] Wampler, C.W., and Morgan, A.P., "Solving the kinematics of general 6R manipulators using polynomial continuation," *Robotics: Applied Mathematics and Computational Aspects*, K. Warwick, ed., Clarendon Press, Oxford, 1993, pp. 57–69.

[86] Wampler, C.W., "Type synthesis of mechanisms for variable valve actuation," SAE technical paper 930818, March 1993.

[87] Wampler, C.W., Arai, T., "Calibration of robots having kinematic closed loops using non-linear least-squares estimation," *Proc. IFToMM-jc Symposium on Theory of Machines and Mechanisms*, Nagoya, Japan, Sept. 24–26, 1992, Vol. 1, pp. 153–158.

[88] Wampler, C.W., "Bezout number calculations for multi-homogeneous polynomial systems," *Applied Mathematics and Computation*, Vol. 51, 1992, pp. 143–157.

[89] Morgan, A.P., Sommese, A.J., and Wampler, C.W., "A power series method for computing singular solutions to nonlinear analytic systems," *Numerische Mathematik*, Vol. 63, 1992, pp. 391–409.

[90] Morgan, A.P., Sommese, A.J., and Wampler, C.W., "Computing singular solutions to polynomial systems," *Advances in Applied Mathematics*, Vol. 13, 1992, pp. 305–327.

[91] Wampler, C.W., Morgan, A.P. and Sommese, A.J., "Complete solution of the nine-point path synthesis problem for four-bar linkages," *Journal of Mechanical Design*, Vol. 114, No. 1, March 1992, pp. 153–159.

[92] Wampler, C.W., "A new Jacobian formulation for general six-revolute manipulators," *Proc. IEEE Int. Conf. on Robotics and Automation*, Sacramento, CA, April 9–11, 1991, Vol. 2, pp. 1046–1051.

[93] Wampler, C.W., and Morgan, A.P., "Solving the 6R inverse position problem using a generic-case solution methodology," *Mechanism and Machine Theory*, Vol. 26, No. 1, 1991, pp. 91–106.

[94] Morgan, A.P., Sommese, A.J., and Wampler, C.W., "Computing singular solutions to nonlinear analytic systems," *Numerische Mathematik*, Vol. 58, 1991, pp. 669–684.

[95] Wampler, C.W., Morgan, A.P., and Sommese, A.J., "Complete solution of the nine-point path synthesis problem for four-bar linkages," *Mechanism Synthesis and Analysis*, Editor: M. McCarthy, et.al., ASME DE-Vol. 25, Amer. Soc. Mech. Eng., New York, 1990, pp. 361–366.

[96] Morgan, A.P., and Wampler, C.W., "Solving a planar four-bar design problem using continuation," *ASME J. of Mechanical Design*, Vol. 112, No. 4, December 1990, pp. 544–550.

[97] Wampler, C.W., Morgan, A.P., and Sommese, A.J. "Numerical continuation methods for solving polynomial systems arising in kinematics," *ASME J. of Mechanical Design*, Vol. 112, No. 1, March 1990, pp. 59–68.

[98] Morgan, A.P., Sommese, A.J., and Wampler, C.W., "Polynomial continuation for mechanism design problems," *Lectures in Applied Mathematics*, Vol. 26, *Computational Solution of Nonlinear Systems of Equations*, Editors: E.L. Allgower and K. Georg, Amer. Math. Society, Providence, RI, 1990, pp. 495–517.

[99] Wampler C.W., and Agrawal, S.K., "An implementation of inverse kinematic functions for control of a redundant wrist," *Proc. IEEE Int. Conf. on Robotics and Automation*, Scottsdale, Az., May 14–19, 1989,

Vol. 2, pp. 914–919.

[100] Wampler, C.W., “Inverse kinematic functions for redundant spherical wrists,” *IEEE Trans. on Robotics and Automation*, Vol. 5, No. 1, Feb. 1989, pp. 106–111.

[100] Wampler, C.W., “Winding number analysis of invertible workspaces for redundant manipulators,” *Int. J. of Robotics Research*, Vol. 7, No. 5, Oct. 1988, pp. 22–31. (Reprinted from *Proc. of 26th IEEE Conf. on Decision and Control*, Dec. 9–11, 1987, Los Angeles, Ca., Vol. 1, pp. 564–569.)

[101] Wampler, C.W., “Inverse kinematics of a seven-degree-of-freedom manipulator,” *Proc. of NATO Advanced Research Workshop on Robots with Redundancy*, June 27–July 1, 1988, Salo, Italy.

[102] Wampler, C.W., “The inverse function approach to kinematic control of redundant manipulators,” *Proc. of the American Control Conference*, June 15–17, 1988, Atlanta, Ga., pp. 1364–1369.

[103] Baker, D. R., and Wampler, C. W., “On the inverse kinematics of redundant manipulators,” *Int. J. of Robotics Research*, Vol. 7, No. 2, April 1988, pp. 3–21. (Reprinted in *Robot Control: Dynamics, Motion Planning, and Analysis*, ed. M. Spong, F. Lewis, and C. Abdallah, IEEE Press, New York, 1993, pp. 468–486.) (Reviewed by T. Yoshikawa, *The Robotics Review* 2, MIT Press, 1992, pp. 207–210.)

[104] Wampler, C. W., and Leifer, L.J., “Applications of damped least-squares methods to resolved-rate and resolved-acceleration control of manipulators,” *ASME J. of Dynamic Systems, Measurement and Control*, Vol. 110, No.1, March 1988, pp. 31–38.

[105] Wampler, C.W., “The inverse function approach to sensor-driven kinematic control of redundant manipulators,” *Kinematic and Dynamic Issues in Sensor Based Control*, Editor: G.E. Taylor, NATO ASI Series F, Vol. 57, Springer-Verlag, Berlin, 1990, pp. 45–58.

[106] Baker, D. R., and Wampler, C. W., “Some facts concerning the inverse kinematics of redundant manipulators,” *Proc. of IEEE Int. Conf. on Robotics and Automation*, March 31–April 3, 1987, Raleigh, N.C., Vol. 2, pp. 604–609.

[107] Wampler, C. W., “Inverse kinematic functions for redundant manipulators,” *Proc. of IEEE Int. Conf. on Robotics and Automation*, March 31–April 3, 1987, Raleigh, N.C., Vol. 2, pp. 610–617.

[108] Wampler, C. W., “Manipulator inverse kinematic solutions based on vector formulations and damped least-squares methods,” *IEEE Trans. on Systems, Man, and Cybernetics*, Vol. SMC-16, No. 1, Jan.-Feb. 1986, pp. 93–101.

[109] Wampler, C., Buffinton, K., and Shu-hui, J., “Formulation of equations of motion for systems subject to constraints,” *ASME J. of Applied Mechanics*, Vol. 52, No. 2, June 1985, pp. 465–470.

[110] Wampler, C. W., “Multiprocessor control of a telemanipulator with optical proximity sensors,” *Int. J. of Robotics Research*, Vol. 3, No. 1, Spring 1984, pp. 40–50.