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including design and computer simulation techniques. The book covers computed-torque, robust control, adoptive control, force control, and advanced topics.

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A control transformation from the task space to the joint space is required to control a robot

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manipulator in the task space. Because the actuators operate in the joint space while the manipulator ...

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manipulator and payload parameters being estimated online. The algorithm is computationally simple, because of an effective exploitation of the structure of manipulator dynamics.

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This dissertation focuses on the kinematics and control of robot manipulators.

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The contribution to kinematics is a fundamental theorem on the design of manipulators with six revolute joints. The theorem states, roughly speaking, that manipulators which have six revolute joints and are modeled after the human arm are optimal and essentially unique.

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Figure 1.1.4: One-layer neural network.

Though the input vector $\vec{x}(t) \in \mathbb{R}^n$ and the vector of weights $\vec{v} \in \mathbb{R}^n$ have been augmented by 1 and v_0 respectively to include the threshold, we may at times loosely say that $\vec{x}(t)$ and \vec{v} are elements of \mathbb{R}^n . These expressions for the neuron output $y(t)$ are referred to as the cell recall mechanism.

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controllers in detail:
proportional derivative;
proportional integral
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torque and some
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Other areas of study
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such as kinematics,...

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A new scheme is
presented for the
accurate tracking
control of robot
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scheme addresses t...

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Introduction Robots

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occupy a privileged place in the modernization of numerous industrial sectors. • The word robot finds its origins in “robota” which means “work” in Slavic languages. • Was introduced by the Czech science fiction writer Karel Čapek.

~~Kinematics and Control
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Robotic Manipulators Introduction. Designing high-performance, low-cost robot manipulators is one of the ultimate challenges for engineers today. Key performance criteria for these robots are: 1) cycling time, 2) accuracy and repeatability, 3) ease of programming, 4) intelligence and 5) safety.

Robot manipulator

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~~control using neural networks: A survey ...~~
control problem of robot manipulators in the task space. Various control schemes are surveyed and classified according to the type of end-effector orientation error; namely ,

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The recurrent neural work has been shown

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successful in the control of robot manipulators. For example, in [80], contact force and position between a manipulator and a surface are controlled by making use of recurrent neural network, which is responsible for simulating the dynamics of manipulators.

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Typically the dynamic control of robotic manipulators is characterized by two levels. The first one requires coordinate transformations to convert the desired path from Cartesian to joint space. The second one requires the computation of generalized torque inputs starting from the knowledge of the

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manipulator dynamic
model.

~~The Robust Control of
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~~Jean-Jacques E...~~

control of assembly
operations of robot
manipulators. The end-
effector configuration
is represented by a set
of m parameters, X_1 ,
 x_z , $* e$, $x_{,,}$, specifying
its position and
orientation in some
reference frame. In
free motion opera-

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tions, the number of end-effector degrees of freedom m is

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Control of robot manipulators in joint space is a counter-fact to most available literature on robotics since it is mostly devoted to robot control, while addressing other topics, such as kinematics,

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mainly through case studies.

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the manipulator moves in a large range although the transpose Jacobian feedback for robot task- space control problem shows excellent stability property (refer to the pioneering work in [13] on the regulation

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problem and to [5], [6]
on the tracking
problem).

~~Neural Network Control
of Robot — UTA~~

Models of robot
manipulators are
important components
of a robot motion con-
trol system. The
control algorithms and
the trajectory
generation algorithms
are two equally
important components.
This thesis deals with

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some aspects of modeling and control of flexible manipulators.

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Without a good control system, a robotic device is useless. The robot arm plus its control system can be encapsulated as a generalized data abstraction; that is, robot-plus-controller is considered a single

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entity, or 'agent', for interaction with the external world. The capabilities of the robotic agent are determined by the mechanical

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