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4.1 Introduction ; 4.2 Force Control of A One-Link Flexible Arm ; 4.3 Dynamic Hybrid Position/ Force Control of Constrained n-Link Flexible Manipulators ; 4.4 Robust Cooperative Control of Two One-link Flexible Arms ; 4.5 Conclusion
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; 6.1 Introduction
6.2 Dynamic Models of One-Link Flexible Robot Arms

Sommario/riassunto

Flexible robotic manipulators pose various challenges in research as compared to rigid robotic manipulators, ranging from system design, structural optimization, and construction to modeling, sensing, and control. Although significant progress has been made in many aspects over the last one-and-a-half decades, many issues are not resolved yet, and simple, effective, and reliable controls of flexible manipulators still remain an open quest. Clearly, further efforts and results in this area will contribute significantly to robotics (particularly automation) as well as its application and educat