

1. Record Nr.	UNINA9910782283503321
Titolo	Advanced studies of flexible robotic manipulators [[electronic resource] ] : modeling, design, control, and applications // [edited by] Fei-Yue Wang, Yanqing Gao
Pubbl/distr/stampa	River Edge, NJ, : World Scientific, c2003
ISBN	1-281-95611-2 9786611956110 981-279-672-X
Descrizione fisica	1 online resource (457 p.)
Collana	Series in intelligent control and intelligent automation ; ; vol. 4
Altri autori (Persone)	WangFei-Yue GaoYanqing <1962->
Disciplina	629.892
Soggetti	Robotics Manipulators (Mechanism)
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Contents ; Preface ; Contributing Authors ; 1. Flexible-link Manipulators: Modeling Nonlinear Control and Observer ; 1.1 Introduction ; 1.2 Modeling ; 1.3 Nonlinear Control ; 1.4 Control with Nonlinear Observer ; 1.5 Simulation Results ; 1.6 Conclusion 2. Energy-Based Robust Control of Flexible Link Robots 2.1 Introduction ; 2.2 Dynamics of a Single-link Flexible Robot ; 2.3 Controller Design ; 2.4 Multi-link Flexible Robots ; 2.5 Conclusion 3. Trajectory Planning and Compliant Control for Two Manipulators to Deform Flexible Materials 3.1 Introduction ; 3.2 Efficient Trajectory Planning Using Optimal Bending Model ; 3.3 Compliant Control ; 3.4 Stability Analysis ; ; 3.5 Experimental Study ; 3.6 Conclusions ; References 4. Force Control of Flexible Manipulators

4.1 Introduction Flexible Arm	; 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		
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References	5. Experimental Study on the Control of Flexible Link Robots	; 5.1 SFL
Manipulator (MMFL) Manipulators	; 5.2 Multi-Link/Multi-Axis Flexible Link	; 5.3
Force Control	; References	; 6. Sensor Output
Feedback Control of Flexible Robot Arms		
; 6.1 Introduction		
6.2 Dynamic Models of One-Link Flexible Robot Arms		

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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 education.

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