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| Autore                  | Huang An-Chyau   |
| Titolo                  | Adaptive control of robot manipulators : a unified regressor-free approach // An-Chyau Huang, Ming-Chih Chien  |
| Pubbl/distr/stampa      | Singapore ; ; Hackensack, N.J., : World Scientific Pub., c2010   |
| ISBN                    | 1-282-76380-6<br>9786612763809<br>981-4307-42-4  |
| Edizione                | [1st ed.]  |
| Descrizione fisica      | 1 online resource (276 p.)   |
| Altri autori (Persone)  | ChienMing-Chih   |
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| Soggetti                | Robots - Control systems - Design and construction<br>Robots - Motion - Mathematical models<br>Robots, Industrial - Design and construction  |
| Lingua di pubblicazione | Inglese  |
| Formato                 | Materiale a stampa   |
| Livello bibliografico   | Monografia   |
| Note generali           | Description based upon print version of record.  |
| Nota di bibliografia    | Includes bibliographic references (p. 247-255) and index.  |
| Nota di contenuto       | Preface; Contents; 1 Introduction; 2 Preliminaries; 3 Dynamic Equations for Robot Manipulators; 4 Adaptive Control of Rigid Robots; 5 Adaptive Impedance Control of Rigid Robots; 6 Adaptive Control of Flexible Joint Robots; 7 Adaptive Impedance Control of Flexible Joint Robots; Appendix; References; Symbols, Definitions and Abbreviations; Index  |
| Sommario/riassunto      | This book introduces an unified function approximation approach to the control of uncertain robot manipulators containing general uncertainties. It works for free space tracking control as well as compliant motion control. It is applicable to the rigid robot and the flexible joint robot. Even with actuator dynamics, the unified approach is still feasible. All these features make the book stand out from other existing publications. |