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Modelling and control of space manipulators with flexible links

Sommario/riassunto	This book reports recent and new developments in modeling, simulation and control of flexible robot manipulators. The material is presented in four distinct components: a range of modeling approaches including classical techniques based on the Lagrange equation formulation, parametric approaches based on linear input/output models using system identification techniques and neuro-modeling approaches; numerical modeling/simulation techniques for dynamic characterization of flexible manipulators using the finite difference, finite element, symbolic manipulation and customized software techniques;