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Collana	House report / 82nd Congress, 1st session. House ; ; no. 645 [United States congressional serial set] ; ; [serial no. 11497]
Altri autori (Persone)	WalterFrancis E <1894-1963> (Francis Eugene), (Democrat (PA))
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Pubbl/distr/stampa	River Edge, NJ, : World Scientific, c2003
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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	; 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
References	5. Experimental Study on the Control of Flexible Link Robots
	; 5.1 SFL Manipulator
	; 5.2 Multi-Link/Multi-Axis Flexible Link (MMFL) Manipulators
	; 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

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.
