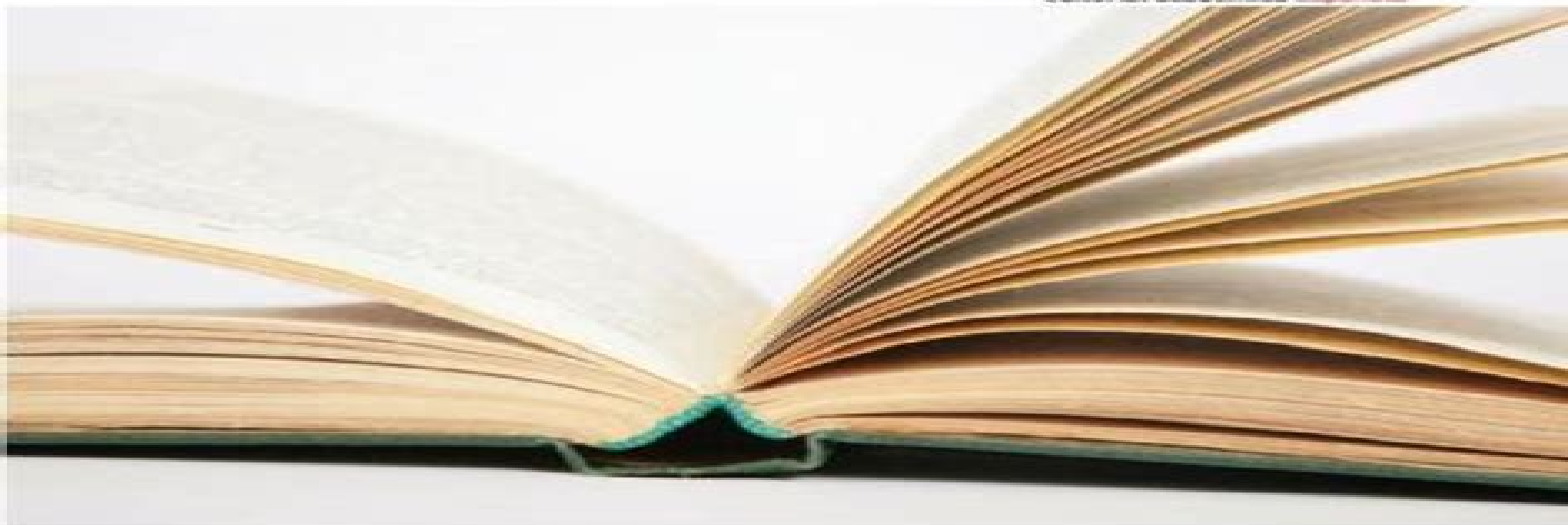




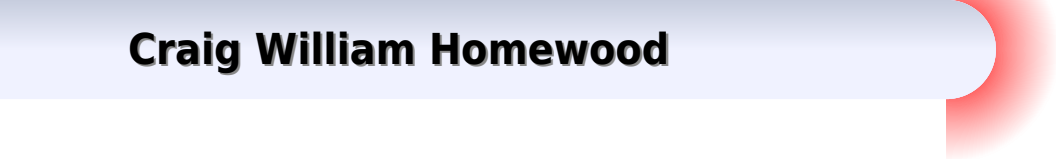
Diana María Díaz Domínguez · Francisco E. López Monteagudo

Técnicas de control adaptable para robots manipuladores

**Algoritmos de control basados en el modelo
dinámico para robots manipuladores**

Tnicas Control Adaptable Robots Manipuladores

Craig William Homewood



Tnicas Control Adaptable Robots Manipuladores:

Non-Adaptive and Adaptive Control of Manipulation Robots M. Vukobratovic, D. Stokic, Nenad Kirćanski, 1985-09-02

The material presented in this monograph is a logical continuation of research results achieved in the control of manipulation robots. This is in a way a synthesis of many year research efforts of the associates of Robotics Department Mihailo Pupin Institute in the field of dynamic control of robotic systems. As in Vol 2 of this Series all results rely on the mathematical models of dynamics of active spatial mechanisms which offer the possibility for adequate dynamic control of manipulation robots. Compared with Vol 2 this monograph has three essential new characteristics and a variety of new tasks arising in the control of robots which have been formulated and solved for the first time. One of these novelties is nonadaptive control synthesized for the case of large variations in payload parameters under the condition that the practical stability of the overall system is satisfied. Such a case of control synthesis meets the actual today's needs in industrial robot applications. The second characteristic of the monograph is the efficient adaptive control algorithm based on decentralized control structure intended for tasks in which parameter variations cannot be specified in advance. To be objective this is not the case in industrial robotics today. Thus nonadaptive control with and without a particular parameter variation is supplemented by adaptive dynamic control algorithms which will certainly be applicable in the future industrial practice when parametric identification of workpieces will be required.

Adaptive Control for Robotic Manipulators Dan Zhang, Bin Wei, 2017
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avance de la tecnología se encuentra en constante crecimiento El desarrollo tecnológico es un aspecto estratégico para todos en v as de crecimiento La trascendencia del desarrollo científico no se limita a sus consecuencias económicas también contribuye a elevar la vida política y social aumenta la reflexión y conocimiento de la sociedad sobre sí misma y por tanto la capacidad del país para dirigir su propio destino Asimismo favorece las posibilidades para que la población obtenga beneficios colectivos de gran importancia entre ellos mejorar la salud y calidad de vida Este es un libro de texto para los cursos de robótica que se imparten en las carreras de ingeniería en mecánica electrónica sistemas e industrial La obra está organizada en cuatro partes Fundamentos de la robótica Modelado Control de robots manipuladores Tópicos selectos de robótica En la primera parte se presenta un panorama general de la robótica su presencia en el desarrollo tecnológico y las bases matemáticas requeridas para analizar y diseñar estrategias de control de robots manipuladores Esta primera parte consta de tres capítulos introducción a la robótica servomotores y sensores y preliminares matemáticos La segunda parte consta de dos capítulos destinados al modelado de robots manipuladores cinemática y dinámica de robots manipuladores La tercera parte cubre el tema de control de robots manipuladores para regulación y control de trayectorias Finalmente en la cuarta parte se exponen dos temas control de fuerza impedancia y robótica móvil Ventajas Competitivas La página Web del libro incluye Videos experimentales que muestran aspectos cualitativos de algoritmos de control Simuladores cuyo propósito general es servir para el estudio y análisis de esquemas de control Código fuente de más de 30 programas para MATLAB relacionados con sistemas dinámicos lineales y no lineales robots manipuladores algoritmos de control y trazo de trayectorias Lecturas complementarias acerca de visual servoing robótica industrial e inteligencia artificial Conozca La clasificación y principios básicos de los servomotores sensores y encoders así como su aplicación en la robótica Los fundamentos matemáticos de los robots manipuladores Los principios básicos de la cinemática y dinámica de los robots manipuladores Los fundamentos físicos y matemáticos del control de los robots manipuladores Aprenda Las técnicas modernas para el control de posición y de trayectoria de los robots manipuladores Los criterios que se utilizan en el modelado de los robots manipuladores Realice Simulaciones de control de posición y trayectoria de robots manipuladores Modificaciones al código fuente de los modelos proporcionados Contenido Robótica Servomotores y sensores Preliminares matemáticos Cinemática de robots manipuladores Dinámica de robots manipuladores Control de posición de robots manipuladores Control de trayectoria de robots manipuladores Control de fuerza impedancia Robótica móvil

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Steinvorth,1991 **Robótica: Control de Robots Manipuladores** Fernando Reyes Cortés,2011-06-01 Es un libro de texto para los cursos de robótica que se imparten en las carreras de ingeniería en mecatrónica electrónica sistemas e industrial. Presenta los fundamentos de la robótica modelado y control de robots manipuladores y los tipos selectos control de fuerza impedancia robótica móvil visual servoing robótica industrial e inteligencia artificial Incluye Videos experimentales que muestran aspectos cualitativos de algoritmos de control Simuladores cuyo propósito general es servir para el estudio y análisis de esquemas de control Codigo fuente toolbox de más de 30 programas para MatLab relacionados con sistemas dinámicos lineales y no lineales robots manipuladores algoritmos de control y trazo de trayectoria **Adaptive Control of Flexible Joint Robot Manipulators** Fathi Ghorbel,1991 The adaptive control of flexible joint robot manipulators using composite control is presented first This slow fast control strategy consists of a slow adaptive controller designed for a rigid robot together with a fast controller to damp the elastic oscillations of the joints The mathematical details and rigorous stability proofs of this algorithm are presented Using the composite Lyapunov theory for singularly perturbed systems sufficient conditions for adaptive trajectory tracking are presented A second approach based on the method of integral manifolds for singularly perturbed systems is presented next The known parameter case is treated and stability analysis is included The method of integral manifolds is then extended to the adaptive case Sufficient conditions for adaptive trajectory tracking are presented for both the general case and a special class of robot manipulators Finally experimental and simulation results are included to illustrate different aspects of the results including adaptive instability mechanisms Análisis comparativo de técnicas de control de robots manipuladores rígidos y flexibles Angel Valera Fernández,1998 **A Global Adaptive Model Following Control in Conjunction with Local Open-loop and Closed-loop Compensations for a Robot Manipulator** Domingo L. Uy,1987 *Control adaptable discreto con esquema de multiestimación en paralelo con incorporación de técnicas de supervisión e inteligencia artificial* ,2006 Direct Model Reference Adaptive Control of Flexible Robotic Manipulator ,198? **Control de pequeños robots manipuladores** Teresa Hernández Sánchez,2009 *Digital Adaptive Control of a Simple Manipulator* Craig William Homewood,1990

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