

Advanced Studies of Flexible Robotic Manipulators

Modeling, Design, Control and Applications

Fei-Yue Wang
Yanqing Gao



Series in Intelligent Control and
Intelligent Automation

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Advanced Studies Of Flexible Robotic Manipulators Modeling Design Control And Applications

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Roy, Bidyadhar Subudhi, Santhakumar
Mohan**

Advanced Studies Of Flexible Robotic Manipulators Modeling Design Control And Applications:

Advanced Studies Of Flexible Robotic Manipulators: Modeling, Design, Control And Applications Yanqing Gao, Fei-yue Wang, 2003-08-14 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 in general control engineering To accelerate this process the leading experts in this important area present in this book the state of the art in advanced studies of the design modeling control and applications of flexible manipulators Flexible Manipulators Yanqing Gao, Fei-Yue Wang, Zhi-Quan Zhao, 2012-04-16 The Intelligent Systems Series comprises titles that present state of the art knowledge and the latest advances in intelligent systems Its scope includes theoretical studies design methods and real world implementations and applications Flexible manipulators play a critical role in applications in a diverse range of fields such as construction automation environmental applications and space engineering Due to the complexity of the link deformation and dynamics the research effort on accurate modeling and high performance control of flexible manipulators has increased dramatically in recent years This book presents analysis data and insights that will of particular use for researchers and engineers working on the optimization and control of robotic manipulators and automation systems Government and industry groups have specifically stressed the importance of innovation in robotics manufacturing automation and control systems for maintaining innovation and high value added manufacturing Discusses the latest research on the quantitative effects of size shape mass distribution tip load on the dynamics and operational performance of flexible manipulators Presents unique analyses critical to the effective modeling and optimization of manipulators hard to find data unavailable elsewhere Robust Control Algorithms for Flexible Manipulators Kshetrimayum Lochan, Binoy Krishna Roy, Bidyadhar Subudhi, Santhakumar Mohan, 2024-10-13 Various modelling and control of two link flexible manipulators are presented in this book The lumped parameter modelling method and the assumed modes method modelling are comprehensively reviewed The book also reviews the trajectory tracking problem and tip trajectory tracking problem along with the suppression of tip deflection of the links An exponential time varying signal and a chaotic signal are considered as the desired trajectories The identical non identical slave manipulator is synchronised with the controlled master manipulator so that the slave manipulator indirectly follows the desired manipulator Robot Manipulators Agustin Jimenez, Basil M. Al Hadithi, 2010-03-01 This book presents the most recent research advances in robot manipulators It offers a complete survey to the kinematic and dynamic modelling simulation computer vision software engineering optimization and design of control algorithms applied for robotic systems It is devoted for a large scale of applications such as manufacturing

manipulation medicine and automation Several control methods are included such as optimal adaptive robust force fuzzy and neural network control strategies The trajectory planning is discussed in details for point to point and path motions control The results in obtained in this book are expected to be of great interest for researchers engineers scientists and students in engineering studies and industrial sectors related to robot modelling design control and application The book also details theoretical mathematical and practical requirements for mathematicians and control engineers It surveys recent techniques in modelling computer simulation and implementation of advanced and intelligent controllers

Fractional-order Systems and Controls Concepción A. Monje, YangQuan Chen, Blas M. Vinagre, Dingyu Xue, Vicente Feliu-Batlle, 2010-09-28 Fractional order Systems and Controls details the use of fractional calculus in the description and modeling of systems and in a range of control design and practical applications It is largely self contained covering the fundamentals of fractional calculus together with some analytical and numerical techniques and providing MATLAB codes for the simulation of fractional order control FOC systems Many different FOC schemes are presented for control and dynamic systems problems Practical material relating to a wide variety of applications is also provided All the control schemes and applications are presented in the monograph with either system simulation results or real experimental results or both Fractional order Systems and Controls provides readers with a basic understanding of FOC concepts and methods so they can extend their use of FOC in other industrial system applications thereby expanding their range of disciplines by exploiting this versatile new set of control techniques

ROMANSY 18 - Robot Design, Dynamics and Control Werner Schiehlen, Vincenzo Parenti-Castelli, 2011-01-28 The papers in this volume provide a vision of the evolution of the robotics disciplines and indicate new directions in which these disciplines are foreseen to develop Paper topics include but are not limited to novel robot design and robot modules components service education medical space welfare and rescue robots humanoid robots bio robotics multi robot embodied multi agent systems challenges in control modeling kinematical and dynamical analysis of robotic systems innovations in sensor systems for robots and perception and recent advances in robotics In particular many contributions on humanoid robots from leading Japanese researchers are included

Multibody System Dynamics, Robotics and Control Hubert Gatringer, Johannes Gerstmayr, 2013-01-06 The volume contains 19 contributions by international experts in the field of multibody system dynamics robotics and control The book aims to bridge the gap between the modeling of mechanical systems by means of multibody dynamics formulations and robotics In the classical approach a multibody dynamics model contains a very high level of detail however the application of such models to robotics or control is usually limited The papers aim to connect the different scientific communities in multibody dynamics robotics and control Main topics are flexible multibody systems humanoid robots elastic robots nonlinear control optimal path planning and identification

Design Of Intelligent Control Systems Based On Hierarchical Stochastic Automata Pedro Lima, George N Saridis, 1996-03-20 In recent years works done by most researchers towards building autonomous intelligent controllers frequently mention the need for a

methodology of design and a measure of how successful the final result is This monograph introduces a design methodology for intelligent controllers based on the analytic theory of intelligent machines introduced by Saridis in the 1970s The methodology relies on the existing knowledge about designing the different sub systems composing an intelligent machine Its goal is to provide a performance measure applicable to any of the sub systems and use that measure to learn on line the best among the set of pre designed alternatives given the state of the environment where the machine operates Different designs can be compared using this novel approach

Network-based Distributed Planning Using Coevolutionary Algorithms Raj Subbu, Arthur C. Sanderson, 2004 In this book efficient and scalable coevolutionary algorithms for distributed network based decision making which utilize objective functions are developed in a networked environment where internode communications are a primary factor in system performance A theoretical foundation for this class of coevolutionary algorithms is introduced using techniques from stochastic process theory and mathematical analysis A case study in distributed network based decision making presents an implementation and detailed evaluation of the coevolutionary decision making framework that incorporates distributed evolutionary agents and mobile agents The methodology discussed in this book can have a fundamental impact on the principles and practice of engineering in the distributed network based environment that is emerging within and among corporate enterprise systems In addition the conceptual framework of the approach to distributed decision systems described may have much wider implications for network based systems and applications

Contents Background and Related Work Problem Formulation and Analysis Theory and Analysis of Evolutionary Optimization Theory and Analysis of Distributed Coevolutionary Optimization Performance Evaluation Based on Ideal Objectives Coevolutionary Virtual Design Environment Evaluation and Analysis Readership Researchers and engineers in artificial intelligence evolutionary computation and decision sciences

Multisensor Fusion Rajive Joshi, Arthur C. Sanderson, 1999 The fusion of information from sensors with different physical characteristics such as sight touch sound etc enhances the understanding of our surroundings and provides the basis for planning decision making and control of autonomous and intelligent machines The minimal representation approach to multisensor fusion is based on the use of an information measure as a universal yardstick for fusion Using models of sensor uncertainty the representation size guides the integration of widely varying types of data and maximizes the information contributed to a consistent interpretation In this book the general theory of minimal representation multisensor fusion is developed and applied in a series of experimental studies of sensor based robot manipulation A novel application of differential evolutionary computation is introduced to achieve practical and effective solutions to this difficult computational problem

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