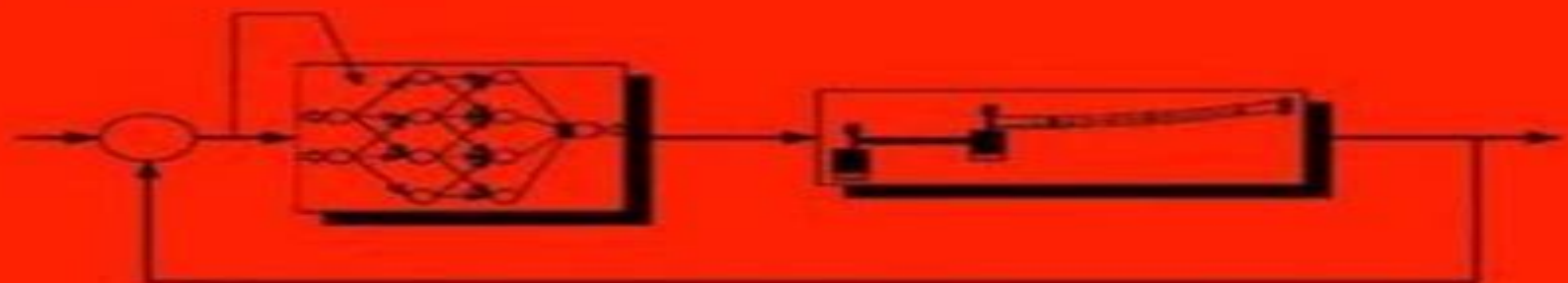


Lecture Notes in Control and Information Sciences 261

H.A. Talebi,
R.V. Patel and K. Khorasani

Control of Flexible-link Manipulators Using Neural Networks



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Control Of Flexiblelink Manipulators Using Neural Networks:

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Control of Flexible link Manipulators Using Neural Networks addresses the difficulties that arise in controlling the end point of a manipulator that has a significant amount of structural flexibility in its links The non minimum phase characteristic coupling effects nonlinearities parameter variations and unmodeled dynamics in such a manipulator all contribute to these difficulties Control strategies that ignore these uncertainties and nonlinearities generally fail to provide satisfactory closed loop performance This monograph develops and experimentally evaluates several intelligent neural network based control techniques to address the problem of controlling the end point of flexible link manipulators in the presence of all the aforementioned difficulties To highlight the main issues a very flexible link manipulator whose hub exhibits a considerable amount of friction is considered for the experimental work Four different neural network schemes are proposed and implemented on the experimental test bed The neural networks are trained and employed as online controllers

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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 *New Trends in Robot Control* Jawhar Ghommam,Nabil Derbel,Quanmin Zhu,2020-02-13 This book presents solutions to control problems in a number of robotic systems and provides a wealth of worked out examples with full analytical and numerical details graphically illustrated to aid in reader comprehension It also presents relevant studies on and applications of robotic system control approaches as well as the latest findings from interdisciplinary theoretical studies Featuring chapters on advanced control fuzzy neural backstepping sliding mode adaptive predictive diagnosis and fault tolerant control the book will equip readers to easily tailor the techniques to their own applications Accordingly it offers a valuable resource for researchers engineers and students in the field of robotic systems *Robot Manipulators* Alex Lazinica,Hiroyuki Kawai,2010-04-01 Robot manipulators are developing more in the direction of industrial robots than of human workers Recently the applications of robot manipulators are spreading their focus for example Da Vinci as a medical robot ASIMO as a humanoid robot and so on There are many research topics within the field of robot manipulators e g motion planning cooperation with a human and fusion with external sensors like vision haptic and force etc Moreover these include both technical problems in the industry and theoretical problems in the academic fields This book is a collection of papers presenting the latest research issues from around the world *A Cse Study in Vision-based Neural Network Control of a Planar, Large Deflection, Flexible Robot Manipulator* Jenny Cutler Larsen,2004 *Proceedings of the ASME Dynamic Systems and Control Division* ,1998 *Nonlinear Control of Wheeled Mobile Robots* Warren E. Dixon,2001-01-29 This book examines the control problem for wheeled mobile robots Several novel control strategies are developed and the stability of each controller is examined utilizing Lyapunov techniques The performance of each controller is either illustrated through simulation results or experimental results The final chapter describes how the control techniques developed for wheeled mobile robots can be applied to solve other problems with similar governing differential equations e g twin rotor helicopters surface vessels Several appendices are included to provide the reader with the mathematical background utilized in the control development and stability analysis Two appendices are also included that provide specific details with regard to the modifications that were done to commercially available mobile robots e g a K2A manufactured by Cybermotion Inc and a Pioneer II manufactured by Activemedia to experimentally demonstrate the performance of the torque input controllers **Applied Mechanics Reviews** ,1993 *Advanced Manufacturing Processes, Systems, and Technologies* M. K. Khan,1996 This volume contains refereed papers accepted for the International Symposium on Advanced Manufacturing Processes Systems and Technologies AMPST 96 which was held at the University of Bradford UK on 26th and 27th March 1996 Pref Organized by University of Bradford and the Institute of

Measurement and Control Includes bibliographical references **Scientia Iranica** ,2008 A Neural Network-based Controller for a Single-link Flexible Manipulator Using the Inverse Dynamics Approach Zhihong Su,2000 This thesis presents an intelligent strategy for controlling the tip position of a flexible link manipulator Motivated by the well known inverse dynamics control approach for rigid link manipulators two multi layer feedforward neural networks are developed to learn the nonlinearities of the system dynamics The re defined output scheme is used by feeding back this output to guarantee the minimum phase behavior of the resulting closed loop system No a priori knowledge about the nonlinearities of the system is needed where the payload mass is also assumed to be unknown The weights of the networks are adjusted using a modified on line error backpropagation algorithm that is based on the propagation of the redefined output error derivative of this error and the tip deflection of the manipulator Numerical simulations as well as real time controller implementation on an experimental setup are carried out The results achieved by the proposed neural network based controller are compared in simulations and experimentally with conventional PD type and inverse dynamics controls to substantiate and demonstrate the advantages and the promising potentials of this scheme International Aerospace Abstracts ,1999 *Advances in Neural Networks--ISNN ...* ,2005 *Experimental Robotics* ,2001 Journal of Dynamic Systems, Measurement, and Control ,2005 *Information, Intelligence and Systems* ,1996 *Sixth Brazilian Symposium on Neural Networks* Carlos H. C. Ribeiro,Felipe M. G. França,2000 With 46 papers from the November 2000 conference in Rio de Janeiro this volume represents the work of computer scientists artificial intelligence researchers and engineers from around the world They address issues like neurosymbolic processing neural computation scalars CDMA and TCMA based neural nets genetic algorithms PARMA modeling hierarchical neural models web text mining inverse kinematics problems in robot control image compression and morphological rules of similarity Also included are abstracts of 24 other papers originally written in Portugese or Spanish Name index only Annotation copyrighted by Book News Inc Portland OR **The Shock and Vibration Digest** ,2002

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