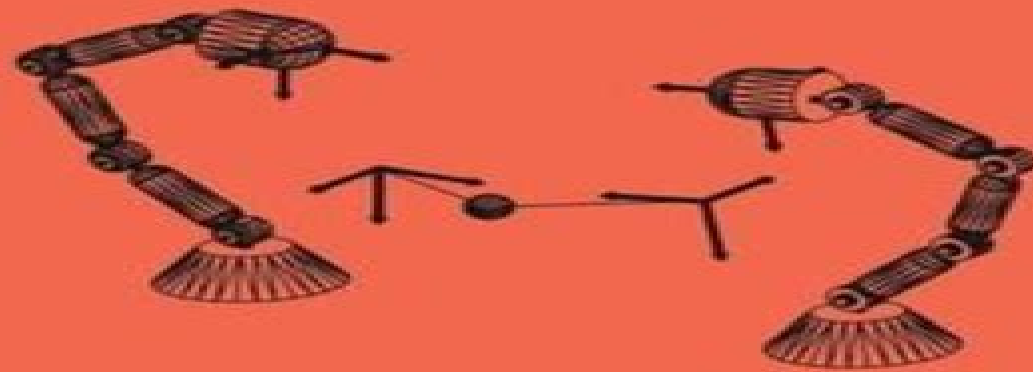


Lecture Notes in Control and Information Sciences 266

Stefano Stramigioli

Modeling and IPC Control of Interactive Mechanical Systems: A Coordinate-free Approach



Springer

Modeling And Ipc Control Of Interactive Mechanical Systems A Coordinatefree Approach

Christian Ott



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Modeling and IPC Control of Interactive Mechanical Systems - A Coordinate-Free Approach Stefano

Stramigioli, 2001-03-23 Robots and more generally mechanical systems are types of a physical system This is why it is important to study and control these systems using information about their particular structure that describes their particular nature In discussing physical systems concepts like energy interconnection and interaction become of substantial importance Furthermore during the modeling and control tasks the results we obtain should be independent from artificial coordinates that people use to analyse the results of their work This has led to the concept of coordinate free description and tensors that have been used a lot in the theory of relativity Throughout this book emphasis is placed on the intrinsic description of the results reported The book describes the modeling and control of robotic systems subject to interaction It covers everything from basic concepts of differential geometry to real robotics Physics and the geometric interconnection of arts play a major role throughout the work

Control of Interactive Robotic Interfaces Cristian Secchi, Stefano

Stramigioli, Cesare Fantuzzi, 2007-04-16 This monograph deals with energy based control of interactive robotic interfaces The port Hamiltonian framework is exploited both for modeling and controlling interactive robotic interfaces The book provides an energy oriented analysis and control synthesis of interactive robotic interfaces from a single robot to multi robot systems for interacting with real and virtual possibly unstructured environments

Modeling and Control of Complex Physical Systems Vincent Duindam, Alessandro Macchelli, Stefano Stramigioli, Herman Bruyninckx, 2009-10-15

Energy exchange is a major foundation of the dynamics of physical systems and hence in the study of complex multi domain systems methodologies that explicitly describe the topology of energy exchanges are instrumental in structuring the modeling and the computation of the system s dynamics and its control This book is the outcome of the European Project Geoplex FP5 IST 2001 34166 that studied and extended such system modeling and control methodologies This unique book starts from the basic concept of port based modeling and extends it to port Hamiltonian systems This generic paradigm is applied to various physical domains showing its power and unifying flexibility for real multi domain systems

Modeling and Control for Efficient Bipedal Walking Robots Vincent Duindam, Stefano Stramigioli, 2009-01-17 By the dawn of the new millennium robotics has undergone a major transformation in scope and dimensions This expansion has been brought about by the maturity of the field and the advances in its related technologies From a largely dominant industrial focus robotics has been rapidly expanding into the challenges of the human world The new generation of robots is expected to safely and dependably co-habitat with humans in homes workplaces and communities providing support in services entertainment education health care manufacturing and assistance Beyond its impact on physical robots the body of knowledge robotics has produced is revealing a much wider range of applications reaching across diverse research areas and scientific disciplines such as biomechanics haptics neurosciences virtual simulation animation surgery and sensor networks among others In return the challenges of the new

emerging areas are providing an abundant source of stimulation and insights for the field of robotics. It is indeed at the intersection of disciplines that the most striking advances happen. The goal of the series of Springer Tracts in Advanced Robotics STAR is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality. It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field.

PID Trajectory Tracking Control for Mechanical Systems Youngjin Choi, Wan Kyun Chung, 2004-01-23 Though PID control has a long history as much as its life force since Ziegler and Nichols published the empirical tuning rules in 1942, surprisingly it has never been changed in the structure itself. The strength of PID control lies in the simplicity, lucid meaning, and clear effect. Though it must be a widely accepted controller for mechanical control systems, it is still short of theoretical bases, e.g., optimality, performance tuning rules, automatic performance tuning method, and output feedback. PID control have not been clearly presented for mechanical control systems. These subjects will be thoroughly discussed in this book. There are many books of PID controller for the purpose of process control, but it is hard to find a book on the characteristics of PID control for mechanical systems. In the first place, when nonlinear optimal control theory is applied to mechanical systems, a class of Hamilton-Jacobi-HJ equations is derived as a result of optimization. There are two methods to solve a class of HJ equations: a direct method using an approximation and an inverse method finding the performance index from a class of HJ equations. Also, there are two control methods according to the objective: the set point regulation control and trajectory tracking control. The trajectory tracking control is basically different from set point regulation, one in that the desired configuration, velocity, and acceleration profiles according to time progress are added to the motion of mechanical system. This book is focusing on an inverse optimization method and the trajectory tracking control system.

Geometric Control of Mechanical Systems Francesco Bullo, Andrew D. Lewis, 2019-06-12 The primary emphasis of this book is the modeling, analysis, and control of mechanical systems. The methods and results presented can be applied to a large class of mechanical control systems, including applications in robotics, autonomous vehicle control, and multi-body systems. The book is unique in that it presents a unified rather than an inclusive treatment of control theory for mechanical systems. A distinctive feature of the presentation is its reliance on techniques from differential and Riemannian geometry. The book contains extensive examples and exercises and will be suitable for a growing number of courses in this area. It begins with the detailed mathematical background, proceeding through innovative approaches to physical modeling, analysis, and design techniques. Numerous examples illustrate the proposed methods and results, while the many exercises test basic knowledge and introduce topics not covered in the main body of the text. The audience of this book consists of two groups. The first group is comprised of graduate students in engineering or mathematical sciences who wish to learn the basics of geometric mechanics, nonlinear control theory, and control theory for mechanical systems. Readers will be able to immediately begin exploring the research literature.

on these subjects The second group consists of researchers in mechanics and control theory Nonlinear control theoreticians will find explicit links between concepts in geometric mechanics and nonlinear control theory Researchers in mechanics will find an overview of topics in control theory that have relevance to mechanics

Control Reconfiguration of Dynamical Systems Thomas Steffen, 2005-08-31 Reconfiguration an approach for fault tolerant control involves changing the control structure in response to the fault This monograph extends this idea to actuator faults and studies in detail the so called virtual actuator approach Control Reconfiguration of Dynamical Systems also introduces structural analysis as a tool for reconfiguration Because a fault changes the structure of the system the reconfiguration solution is sought on a structural level Novel algorithms are presented to test for reconfigurability and to find a reconfiguration solution A MATLAB toolbox is supplied which contains the main algorithms and examples The book addresses advanced engineering students developers and researchers that have a specific interest in control reconfiguration

Vehicle-Manipulator Systems Pål Johan From, Jan Tommy Gravdahl, Kristin Ytterstad Pettersen, 2013-10-02 Furthering the aim of reducing human exposure to hazardous environments this monograph presents a detailed study of the modeling and control of vehicle manipulator systems The text shows how complex interactions can be performed at remote locations using systems that combine the manipulability of robotic manipulators with the ability of mobile robots to locomote over large areas The first part studies the kinematics and dynamics of rigid bodies and standard robotic manipulators and can be used as an introduction to robotics focussing on robust mathematical modeling The monograph then moves on to study vehicle manipulator systems in great detail with emphasis on combining two different configuration spaces in a mathematically sound way Robustness of these systems is extremely important and Modeling and Control of Vehicle manipulator Systems effectively represents the dynamic equations using a mathematically robust framework Several tools from Lie theory and differential geometry are used to obtain globally valid representations of the dynamic equations of vehicle manipulator systems The specific characteristics of several different types of vehicle manipulator systems are included and the various application areas of these systems are discussed in detail For underwater robots buoyancy and gravity drag forces added mass properties and ocean currents are considered For space robotics the effects of free fall environments and the strong dynamic coupling between the spacecraft and the manipulator are discussed For wheeled robots wheel kinematics and non holonomic motion is treated and finally the inertial forces are included for robots mounted on a forced moving base Modeling and Control of Vehicle manipulator Systems will be of interest to researchers and engineers studying and working on many applications of robotics underwater space personal assistance and mobile manipulation in general all of which have similarities in the equations required for modeling and control

Cartesian Impedance Control of Redundant and Flexible-Joint Robots Christian Ott, 2008-07-22 By the dawn of the new millennium robotics has undergone a major transformation in scope and dimensions This expansion has been brought about by the maturity of the field and the advances in its related technologies From a largely dominant industrial

focus robotics has been rapidly expanding into the challenges of the human world. The new generation of robots is expected to safely and dependably co-habitat with humans in homes, workplaces and communities providing support in services, entertainment, education, healthcare, manufacturing and assistance. Beyond its impact on physical robots, the body of knowledge robotics has produced is revealing a much wider range of applications reaching across diverse research areas and scientific disciplines such as biomechanics, haptics, neuroscience, virtual simulation, animation, surgery and sensor networks among others. In return, the challenges of the new emerging areas are proving an abundant source of stimulation and insights for the field of robotics. It is indeed at the intersection of disciplines that the most striking advances happen. The goal of the series of Springer Tracts in Advanced Robotics (STAR) is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality. It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field.

Advanced Topics in Control Systems Theory Françoise Lamnabhi-Lagarigue, 2005-02-11. Advanced Topics in Control Systems Theory contains selected contributions written by lecturers at the second annual Formation d'Automatique de Paris (FAP) Graduate Control School in Paris. It is addressed to graduate students and researchers in control theory with topics touching on a variety of areas of interest to the control community such as cascaded systems, flatness, optimal control and Hamiltonian and infinite dimensional systems. The reader is provided with a well integrated synthesis of the latest thinking in these subjects without the need for an exhaustive literature review. The internationally known contributors to this volume represent many of the most reputable control centers in Europe. Advanced Topics in Control Systems Theory can be used to support either a one-term general advanced course on nonlinear control theory devoting a few lectures to each chapter or for more focused and intensive courses at graduate level. The book's concise but pedagogical manner will give an ideal start to researchers wishing to broaden their knowledge in aspects of modern control theory outside their own expertise.

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