

Research Article

Robust Tracking Control of Robot Manipulators Using Only Joint Position Measurements

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This paper concerns the tracking control of a robot manipulator with unknown uncertainties and disturbances. It presents a new control method that uses only joint position measurements to design a tracking controller. The controller has two parts. One is based on a feedback linearization technique; it makes the nominal model of a manipulator asymptotically track a desired trajectory. The other is based on the idea of equivalent input disturbance (EID); it compensates for uncertainties and disturbances. Together they enable a robot manipulator to precisely track the desired trajectory. The new control algorithm is applied to a two-link robot manipulator, and simulation results demonstrate the validity of this method.

1. Introduction

Robot manipulators are widely used in many fields. They are especially useful in areas where it is impractical or undesirable for a human to go, for example, undersea exploration, radioactive environments, and defusing explosive devices. Interest in the control of robot manipulators has been increasing over the past few years [1–3], and it is now a central issue in robotics.

If an exact dynamic model of a robot manipulator is known, the motion control problem is easy to solve by the computed-torque-control (CTC) method [4]. It uses nonlinear state feedback to cancel the nonlinear terms and a simple PD controller for motion control. Although this method is simple and effective, the requirement of an exact model limits its practicality because it is usually impossible to obtain an exact, or even reasonably accurate, dynamic model in practical applications. For example, an actual plant inevitably contains structured and unstructured uncertainties, and a robot manipulator may be influenced by unpredictable external disturbances when the operating environment changes. Since these uncertainties and disturbances may greatly affect

control performance, it is necessary to consider their effects in the study of the motion control of robot manipulators.

A number of strategies have been developed to solve the problem of controlling the motion of a robot manipulator with uncertainties and disturbances. They include a Lyapunov-based method [5], a neural-network-based method [6, 7], an adaptive neural network H_∞ strategy [8], an adaptive switching learning PD (ASL-PD) method [9], a parameter-dependent nonlinear observer approach [10], and a variable-structure PID control method [11]. However, all of them require measurement of both the displacement and velocity of joints.

Generally speaking, joint displacement can be accurately measured with an encoder. However, velocity is typically measured with a tachometer, and the results usually contain noise, which can affect the control precision and performance of a closed-loop system. So, both practically and theoretically, it is meaningful to devise a motion control method for robot manipulators which relies only on the measurement of joint position. Various strategies have been developed to solve this challenging problem. One is a controller-observer combination strategy. It has a two-step design procedure:

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