عنوان مقاله:

Position Controller Synthesis for The Redundant Hydraulic Shoulder Manipulator

محل انتشار:

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خلاصه مقاله:

In this paper, position control has been designed for a 3 DOF actuator redundant sphericnl parallel manipulator. A two norm minimization approach has been used to resolve the actuator redundancy problem. Robust stability of the closed loop system is analyzed considering uncertainties inherent in the dynamic model of the manipulator.A simulations tudy is alsop erformedt o show the effectivenesso f the proposed method. Thc results show the applicabilityo f simplea nd conventionacl ontrollerst o control redundants phericapl arallelm anipulators.

کلمات کلیدی:

Index Terms - Parallel manipulator, Robust Position Control, Redundancy, Force Distribulion, Computed Torque

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