

عنوان مقاله:

Robot arm inverse kinematics based routing using neural networks

محل انتشار:

همایش ملی مهندسی رایانه و مدیریت فناوری اطلاعات (سال: 1393)

تعداد صفحات اصل مقاله: 11

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خلاصه مقاله:

Planar two and three-link manipulators are often used in Robotics as test beds for various algorithms or theories. In this paper, the case of a three-link planar manipulator is considered. For this type of robot a solution to the inverse kinematics problem, needed for generating desired trajectories in the Cartesian space (2 D) is found by using a feed-forward neural network.

کلمات کلیدی:

robotic arm; planar manipulator; inverse kinematics; trajectory; neural networks

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<https://civilica.com/doc/282613>

