

عنوان مقاله:

A Fuzzy Controller for a Flexible Link Manipulator

محل انتشار:

اولین کنفرانس بین المللی دستاوردهای نوین پژوهشی در مهندسی برق و کامپیوتر (سال: 1395)

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خلاصه مقاله:

This paper analyzes and simulates a dual-link robot whose second link is flexible. To extract its dynamic equations, Lagrange method, a common method to obtain equations of dynamical systems, was used. Then, robot was controlled through Feedback Linearization Method. This controller was not sufficiently robust against noise, disturbance and parameter variations. Therefore, fuzzy controller was further designed due to the probable uncertainties in the system. This controller was sufficiently robust against noise and disturbance.

کلمات کلیدی:

Fuzzy control; Flexible link; Robot manipulators

لینک ثابت مقاله در پایگاه سیویلیکا:

<https://civilica.com/doc/497258>

