

CONTROL OF NONLINEAR MECHANICAL SYSTEMS%0A

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Control design methods for some underactuated mechanical systems are presented. A first control algorithm is based on the energy of the system and its passivity properties.

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Control design methods for some underactuated mechanical systems are presented. A first control algorithm is based on the energy of the system and its passivity properties.

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[Model-based Adaptive Control of Mechanical Systems](#)

When the goal of control is given as a desired joint trajectory $\{q_d(t)\}$ together with its velocity and acceleration, real-time estimation of nonlinear terms in the Lagrange equation of motion becomes indispensable.

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The machines become complex, strongly nonlinear and strongly coupled mechanical systems with many degrees of freedom, controlled by sophisticated mathematical programs. The design of such systems needs basic research in Control and System Dynamics, as well as in Decision Making Theory (Dynamic Games), not only in the use of these disciplines, but in their adjustment to the present demand. This

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An input-output approach is presented for sliding mode control of linear and nonlinear switched systems of the differentially flat type. Two sliding mode control design options are presented: (1)

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Nonlinear control is an important area in control, as virtually all physical systems are nonlinear in nature. In case a system does not deviate too much from the nominal set of operating

[Adaptive Robust Control of Mechanical Systems with ...](#)

Adaptive Robust Control of Mechanical Systems with Nonlinear Dynamic Friction Compensation | Li Xu Bin Yao + School of Mechanical Engineering Purdue University West Lafayette, IN 47907, USA + Email: Abstract In this paper, an adaptive robust control (ARC) scheme based friction compensation strategy is presented for a class of

Control of Nonlinear Mechanical Systems | Jan M ...

A modern mechanical structure must work at high speed and with high precision in space and time, in cooperation with other machines and systems. All this requires accurate dynamic modelling, for instance, recognizing Coriolis and centrifugal forces, strong coupling effects, flexibility of links,

NONLINEAR MECHANICAL SYSTEMS (MECHANISMS)

NONLINEAR MECHANICAL SYSTEMS (MECHANISMS) The analogy between dynamic behavior in different energy domains can be useful. Closer inspection reveals that the analogy is not complete. One key distinction of mechanical systems is the role of kinematics the geometry of motion **EXAMPLE:** automobile internal combustion engine, reciprocating translational motion of a piston is converted to **Nonlinear control of mechanical systems with an unactuated ...**

Nonlinear control of mechanical systems with an unactuated cyclic variable Abstract: Numerous robotic tasks associated with underactuation have been studied in the literature. For a large number of these in the plane, the mechanical models have a cyclic variable, the cyclic variable is unactuated, and all shape variables are independently actuated. This paper formulates and solves two control

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particularly important for nonlinear mechanical systems Geometry is fundamental. The choice of coordinates used to represent the geometry and kinematics of a system has a profound effect on the structure and complexity of its describing equations. Transformations of state variables are used extensively to analyze linear state determined systems, e.g., physical variables to diagonal form

Passive Bilateral Control of Nonlinear Mechanical ...

2 Passive Bilateral Control of Nonlinear Mechanical Teleoperators Dongjun Lee and Perry Y. Li Abstract In this paper, a passive bilateral control law is proposed for a teleoperator consisting of a pair of n-DOF

NONLINEAR AND OPTIMAL CONTROL THEORY

A. A. Agrachev A. S. Morse E. D. Sontag H. J. Sussmann
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THEORY** Lectures given at the C.I.M.E. Summer School
Control of Nonlinear Mechanical Systems (eBook, 1991

...

Control of Nonlinear Mechanical Systems, [Janis aw M.
Skowr nski] -- A modern mechanical structure must work
at high speed and with high precision in space and time, in
cooperation with other machines and systems. All this
requires accurate dynamic modelling, for