



Fundamentals for Control of Robotic Manipulators

Antti J. Koivo

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Presents the fundamentals for controlling robot manipulators in a systems theory framework. From the nonlinear models of the manipulator systems, linearized models are obtained, and their basic properties, such as stability and complete controllability, are studied. Gives detailed descriptions of controller design approaches, including PID controllers and adaptive self-tuning controllers. Provides the reader with the basic tools to apply the design methods of system theory to practical applications of robot systems and to achieve competency at the level of research in the area. Features many examples, including digital simulations of manipulator motions, and each chapter contains a set of analytical and computer problems.

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