A New Parameters Identification Technique for Constrained Robot

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Abstract

This paper presents an identification method for the dynamic parameters of constrained robot manipulator in presence of uncertainties in constraints and robot model. Closed-loop dynamic error equations are derived based on computing input torque and end-effector contact force to survey both desired path and force. The reduced form system equation is adopted for the robot model to prove the proposed identification method. In this work, an ANFIS network has been used and trained based on the presented error component equations to identify the dynamic parameters of two links constrained robot manipulator.

References


**Index Terms**

Computer Science

Automated Systems

**Keywords**

Constrained robot manipulator, Robot Model