

Master's degree in Computer Engineering for  
Robotics and Smart Industry

**Advanced Control System  
Final Report**

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# 1 First homework: DH table, forward kinematics, inverse kinematics and Jacobian

The robot that we are going to analyze is a 3-DOF robot manipulator with the following parameters:

- $l_1 = 4$  m
- $l_3 = 0.24$  m
- $d_2 = 0.3$  m (from -0.3 to 0)
- $l_b = 0.15$  m

The robot manipulator has three joints:  $\theta_1$ ,  $\theta_2$  and  $\theta_3$ . A figure that shows the robot manipulator is shown in Figure 1.

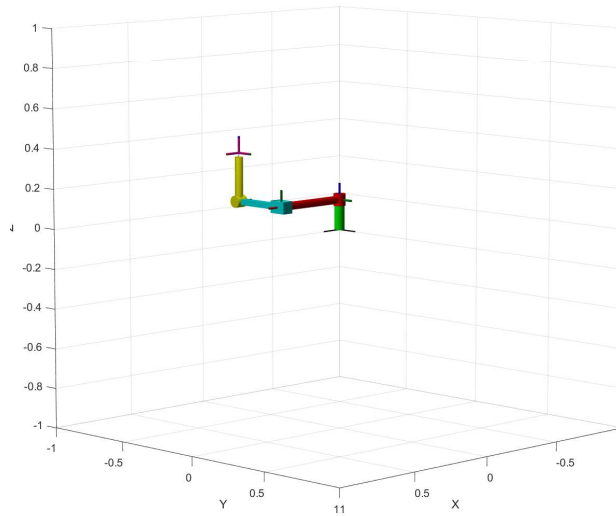


Figure 1: 3-DOF Robot Manipulator

## 1.1 DH table

The Denavit-Hartenberg (DH) parameters are used to describe the kinematics of a robot manipulator. The DH parameters are four values that describe the relationship between two consecutive links in a robot manipulator. The four values are:  $a_i$ ,  $d_i$ ,  $\alpha_i$  and  $\theta_i$ . The  $a_i$  and  $d_i$  values are the lengths of the common normal and the link offset, respectively. The  $\alpha_i$  and  $\theta_i$  values are the twist angle and the joint angle, respectively. The DH table is a matrix that contains the DH parameters for each link in the robot manipulator.

Table 1: DH Table

Frame	Link	$a_i$	$\alpha_i$	$d_i$	$\theta_i$
$b \rightarrow 0$		0	0	$l_b$	0
$0 \rightarrow 1$	1	$l_1$	$\frac{\pi}{2}$	0	$\theta_1$
$1 \rightarrow 2$	2	0	$-\frac{\pi}{2}$	$d_2 + 0.3$	$\frac{\pi}{2}$
$2 \rightarrow 3$	3	$l_3$	0	0	$\theta_3 - \frac{\pi}{2}$
$3 \rightarrow ee$		0	$\frac{\pi}{2}$	0	$\frac{\pi}{2}$

## 1.2 Forward kinematics

The forward kinematics is the process of determining the position and orientation of the end-effector of a robot manipulator given the joint angles. The forward kinematics can be calculated using the DH parameters and the homogeneous transformation matrices. The homogeneous transformation matrix is a 4x4 matrix that describes the relationship between two consecutive links in a robot manipulator.

The homogeneous transformation matrix between two consecutive links  $i$  and  $i + 1$  is given by:

$$T_{i,i+1} = \begin{bmatrix} c_{\theta_i} & -s_{\theta_i}c_{\alpha_i} & s_{\theta_i}s_{\alpha_i} & a_i c_{\theta_i} \\ s_{\theta_i} & c_{\theta_i}c_{\alpha_i} & -c_{\theta_i}s_{\alpha_i} & a_i s_{\theta_i} \\ 0 & s_{\alpha_i} & c_{\alpha_i} & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad (1)$$

The forward kinematics can be calculated by multiplying the homogeneous transformation matrices for each link in the robot manipulator. The forward kinematics can be calculated using the following equation:

$$T_{b,ee} = T_{b,0} \times T_{0,1} \times T_{1,2} \times T_{2,3} \times T_{3,ee} \quad (2)$$

Where  $T_{b,ee}$  is the homogeneous transformation matrix between the base

frame and the end-effector frame (accordingly to the nsa convention):

$$T_{b,ee} = \begin{pmatrix} -\sin(\theta_1) \sin(\theta_3) & -\cos(\theta_1) & \cos(\theta_3) \sin(\theta_1) & \frac{2 \cos(\theta_1)}{5} + \frac{3 \sin(\theta_1)}{10} + \frac{6 \cos(\theta_3) \sin(\theta_1)}{25} + \theta_2 \sin(\theta_1) \\ \cos(\theta_1) \sin(\theta_3) & -\sin(\theta_1) & -\cos(\theta_1) \cos(\theta_3) & \frac{2 \sin(\theta_1)}{5} - \frac{3 \cos(\theta_1)}{10} - \frac{6 \cos(\theta_1) \cos(\theta_3)}{25} - \theta_2 \cos(\theta_1) \\ \cos(\theta_3) & 0 & \sin(\theta_3) & \frac{6 \sin(\theta_3)}{25} + \frac{3}{20} \\ 0 & 0 & 0 & 1 \end{pmatrix} \quad (3)$$

For all the others matrices see the matlab code.

### 1.3 Inverse kinematics

The inverse kinematics is the process of determining the joint angles of a robot manipulator given the position and orientation of the end-effector. The inverse kinematics can be calculated using the DH parameters and the homogeneous transformation matrices, and we can start from the following equation:

$$T_e^b = \begin{bmatrix} \frac{2}{5} \cos \theta_1 + \frac{3}{10} \sin \theta_1 + \frac{6}{25} \cos \theta_3 \sin \theta_1 + \theta_2 \sin \theta_1 \\ \frac{2}{5} \sin \theta_1 - \frac{3}{10} \cos \theta_1 - \frac{6}{25} \cos \theta_3 \cos \theta_1 - \theta_2 \cos \theta_1 \\ \frac{6}{25} \sin \theta_3 + \frac{3}{20} \end{bmatrix} \quad (4)$$

From the last row of the matrix, we can find the value of  $\theta_3$ :

$$\theta_3 = \arcsin \left( \frac{z - 0.15}{0.24} \right) \quad (5)$$

Then, if we apply the technique of summing the squares of the first two rows, we can find the value of  $\theta_2$ :

$$\theta_2 = \frac{-0.6 \pm \sqrt{-0.6^2 - 4(\frac{53}{50} - x^2 - y^2)}}{2} \quad (6)$$

Finally, we can find the value of  $\theta_1$  by substituting the values of  $\theta_2$  and  $\theta_3$  in the first row of the matrix and recalling the Weierstrass substitution formulas:

$$\sin x = \frac{2t}{1+t^2} \quad (7)$$

$$\cos x = \frac{1-t^2}{1+t^2} \quad (8)$$

$$x = \tan \frac{x}{2} \quad (9)$$

$$\theta_1 = \frac{2A \pm \sqrt{4A^2 - 4(x-2)^2}}{2(x-2)} \quad (10)$$

where A is:

$$A = 0.3 + \frac{6}{25} \cos \theta_3 + \theta_2 \quad (11)$$

## 1.4 Geometric Jacobian

The geometric Jacobian matrix is a 6x3 matrix that describes the relationship between the joint velocities and the end-effector velocities of a robot manipulator.

The geometric Jacobian matrix can be calculated using the following equation:

$$J_{geometric} = \begin{pmatrix} \frac{3 \cos(\theta_1)}{10} - \frac{2 \sin(\theta_1)}{5} + \frac{6 \cos(\theta_1) \cos(\theta_3)}{25} + \theta_2 \cos(\theta_1) & \sin(\theta_1) & -\frac{6 \sin(\theta_1) \sin(\theta_3)}{25} \\ \frac{2 \cos(\theta_1)}{5} + \frac{3 \sin(\theta_1)}{10} + \frac{6 \cos(\theta_3) \sin(\theta_1)}{25} + \theta_2 \sin(\theta_1) & -\cos(\theta_1) & \frac{6 \cos(\theta_1) \sin(\theta_3)}{25} \\ 0 & 0 & \frac{6 \cos(\theta_3)}{25} \\ 0 & 0 & -\cos(\theta_1) \\ 0 & 0 & -\sin(\theta_1) \\ 1 & 0 & 0 \end{pmatrix} \quad (12)$$

## 1.5 Analytical Jacobian

The analytical Jacobian matrix is a 6x3 matrix and it's calculated as the derivative of the forward kinematics with respect to the joint angles. The analytical Jacobian matrix can be calculated using the following equation:

$$J_{analytical} = \begin{pmatrix} \frac{3 \cos(\theta_1)}{10} - \frac{2 \sin(\theta_1)}{5} + \frac{6 \cos(\theta_1) \cos(\theta_3)}{25} + \theta_2 \cos(\theta_1) & \sin(\theta_1) & -\frac{6 \sin(\theta_1) \sin(\theta_3)}{25} \\ \frac{2 \cos(\theta_1)}{5} + \frac{3 \sin(\theta_1)}{10} + \frac{6 \cos(\theta_3) \sin(\theta_1)}{25} + \theta_2 \sin(\theta_1) & -\cos(\theta_1) & \frac{6 \cos(\theta_1) \sin(\theta_3)}{25} \\ 0 & 0 & \frac{6 \cos(\theta_3)}{25} \\ 1 & 0 & 0 \\ 0 & 0 & -\frac{\cos(\theta_3)}{|\cos(\theta_3)|} \\ 0 & 0 & 0 \end{pmatrix} \quad (13)$$

# 2 Second homework: Kinetic and potential energy

## 2.1 Kinetic energy

The kinetic energy of a robot manipulator is the energy due to the motion of the robot. Before calculating the kinetic energy, we need to calculate the partial jacobian for every joint, as shown in the following equation:

$$\sum_{i=1}^n \left( m_{\ell_i} \left( J_P^{\ell_i} \right)^T J_P^{\ell_i} + \left( J_O^{\ell_i} \right)^T R_i I_{\ell_i}^i R_i^T J_O^{\ell_i} \right) \quad (14)$$

In particular, the partial jacobian for the end effector is given by:  
positional part:

$$j_{P_j}^{l_i} = \begin{cases} Z_{j-1}, & \text{prismatic joint} \\ Z_{j-1} \times (p_{l_i} - p_{j-1}), & \text{revolute joint} \end{cases} \quad (15)$$

rotational part:

$$j_{O_j}^{l_i} = \begin{cases} 0, & \text{prismatic joint} \\ Z_{j-1}, & \text{revolute joint} \end{cases} \quad (16)$$

where

- $p_{j-1}$  is the position vector of the origin of Frame  $\Sigma_{j-1}$  w.r.t.  $\Sigma_0$
- $z_{j-1}$  is the unit vector of axis  $z$  of Frame  $\Sigma_{j-1}$  w.r.t.  $\Sigma_0$

Now, we need an additional matrix, the inertia matrix for each link, wrt the frame attached to the current link.

To compute this matrix we also use **Steiner's theorem**, which states that the inertia matrix of a body with respect to a point  $P$  is equal to the inertia matrix of the body with respect to its center of mass  $G$  plus the mass of the body times the square of the distance between  $G$  and  $P$  times the identity matrix.

for prismatic joints the inertia matrix wrt to the CoM is the following:

$$I_C = \begin{bmatrix} \frac{1}{12}m(b^2 + c^2) & 0 & 0 \\ 0 & \frac{1}{12}m(a^2 + c^2) & 0 \\ 0 & 0 & \frac{1}{12}m(a^2 + b^2) \end{bmatrix} \quad (17)$$

Remapping the inertia matrix to the frame of the link, we obtain:

$$\begin{aligned} I &= I_C + m \left( \begin{bmatrix} -\frac{a}{2} & 0 & 0 \end{bmatrix} \begin{bmatrix} -\frac{a}{2} \\ 0 \\ 0 \end{bmatrix} I_{3 \times 3} - \begin{bmatrix} -\frac{a}{2} \\ 0 \\ 0 \end{bmatrix} \begin{bmatrix} -\frac{a}{2} & 0 & 0 \end{bmatrix} \right) = \\ &= \begin{bmatrix} 0.0151 & 0 & 0 \\ 0 & 0.0601 & 0 \\ 0 & 0 & 0.0453 \end{bmatrix} \end{aligned} \quad (18)$$

for revolute joints:

$$I_C = \begin{bmatrix} \frac{1}{2}m(a^2 + b^2) & 0 & 0 \\ 0 & \frac{1}{2}m(3(a^2 + b^2)^2 + h^2) & 0 \\ 0 & 0 & \frac{1}{2}m(3(a^2 + b^2)^2 + h^2) \end{bmatrix} \quad (19)$$

Remapping the inertia matrix to the frame of the link, we obtain:

$$\begin{aligned}
I &= I_C + m \left( \begin{bmatrix} -\frac{h}{2} & 0 & 0 \end{bmatrix} \begin{bmatrix} -\frac{h}{2} \\ 0 \\ 0 \end{bmatrix} I_{3 \times 3} - \begin{bmatrix} -\frac{h}{2} \\ 0 \\ 0 \end{bmatrix} \begin{bmatrix} -\frac{h}{2} & 0 & 0 \end{bmatrix} \right) = \\
&= \begin{bmatrix} 0.0004 & 0 & 0 \\ 0 & 0.2400 & 0 \\ 0 & 0 & 0.2400 \end{bmatrix} \text{ and } \begin{bmatrix} 0.0004 & 0 & 0 \\ 0 & 0.0864 & 0 \\ 0 & 0 & 0.0864 \end{bmatrix} \quad (20)
\end{aligned}$$

Finally, we can calculate the kinetic energy of the robot manipulator using the following equation:

All the computations are made with symbolic toolbox in Matlab, and to obtain a numerical value we need to substitute the values for the joints and velocities. In this specific case, we choose the following values:

$$\text{jointValues} = [\frac{\pi}{2}, -0.2, \frac{\pi}{3}]$$

$$\text{velocityValues} = [5, 2, 8]$$

$$\text{accelerationValues} = [4, 1, 2]$$

$$K = \frac{1}{2} \dot{q}^T \left[ \sum_{i=1}^n \left( m_{l_i} (J_P^{l_i})^T J_P^{l_i} + (J_O^{l_i})^T R_i I_{l_i}^i R_i^T J_O^{l_i} \right) \right] \dot{q} = 8.8520J \quad (21)$$

Where the part inside the square brackets is the inertia matrix of the robot, and it's called  $B$ .

## 2.2 Potential energy

Regarding the potential energy, it's way easier to compute, since it's just the sum of the potential energy of each link, which is given by:

$$\mathcal{U} = \sum_{i=1}^n \mathcal{U}_i = - \sum_{i=1}^n m_{l_i} g_0^T \rho_{l_i} = 10.8680J \quad (22)$$

Recalling that the gravity vector is  $g_0 = [0, 0, -9.81]$ .

## 3 Third homework: Equations of motion

### 3.1 $\tau$ , with kinetic and potential energy

The lagrangian of a system is defined as the sum between the kinetic energy and the potential energy of the system.

$$\mathcal{L}(q, \dot{q}) = \mathcal{T}(q, \dot{q}) - \mathcal{U}(q) = \frac{1}{2} \dot{q}^T B(q) \dot{q} + \sum_{i=1}^n m_{l_i} g_0^T \rho_{l_i} \quad (23)$$



Now, to obtain the *tau*, the torques to be imparted to the robot's motors, we must calculate the derivative of the Lagrangian, first with respect to *dotq* and then with respect to *q*.

$$\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right)^T = B(q)\dot{q} \quad (24)$$

$$\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right)^T = \frac{1}{2} \left(\frac{\partial}{\partial \dot{q}} (\dot{q}^T B(q) \dot{q})\right)^T - \left(\frac{\partial \mathcal{U}}{\partial q}\right)^T \quad (25)$$

$$\frac{d}{dt} \left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right)^T = B(q)\ddot{q} + \dot{B}(q)\dot{q} \quad (26)$$

If we substitute the values for the joints, elocities and acceleration, we obtain the following values for the torques:

$$\tau = \begin{bmatrix} 4.6117 \\ -15.9957 \\ 3.2947 \end{bmatrix} \quad (27)$$

### 3.2 $\tau$ with Coriolis, centrifugal and gravity terms

If we don't want to compute all this derivatives, we have another way to compute the torques, using the Coriolis and centrifugal matrices and the gravity vector. As we'll see the results for the torques are the same.

$$\sum_{j=1}^n b_{ij}(q)\ddot{q}_j + \sum_{j=1}^n c_{ij}(q, \dot{q})\dot{q}_j + g_i(q) = \tau_i \quad (28)$$

where the gravity vector is given by:

$$\sum_{j=1}^n m_{l_j} g_0^T J_{P_i}^{l_j}(q) \quad (29)$$

and the  $c_{i,j}$  terms is given by:

$$\sum_{j=1}^n \sum_{k=1}^n h_{ijk}(q) \dot{q}_k \dot{q}_j \quad (30)$$

After all the computations in Matlab, that are too long to be written here, we obtain the following values for the torques:

$$\tau = \begin{bmatrix} 4.6117 \\ -15.9957 \\ 3.2947 \end{bmatrix} \quad (31)$$

that are exactly the same as the ones obtained with the derivatives of the Lagrangian.

## 4 Fourth homework: Newton-Euler formulation

The NE formulation is based on the balance of all the forces acting on the generic link of the manipulator. It's divided in two steps: the first one is the forward dynamics, where we compute the linear and angular velocities and accelerations of the links, and the second one is the backward dynamics, where we compute the torques to be imparted to the motors. It's important to remember that the NE formulation is an algorithmic and numerical method, and it's not as precise as the Lagrangian formulation, but it's much faster and easier to compute.

Before starting with the computations, we need to understand what is the augmented link, which is the link that we are studying in the current iteration of the algorithm plus the mass of the motor and the inertia.

### 4.1 Forward dynamics

The forward recursion is performed for propagating link velocities and accelerations from  $i = 0$  to  $i = n$ . For all the code see the Matlab code.

### 4.2 Backward dynamics

The backward recursion for propagating forces from  $i = n$  to  $i = 0$ . For all the code see the Matlab code.

Finally, as expected, torques computed with the NE formulation are the same as the ones computed with the Lagrangian formulation. In particular, we have the following values for the torques:

$$\tau = \begin{bmatrix} 4.6117 \\ -15.9957 \\ 3.2947 \end{bmatrix} \quad (32)$$

when the joint values, velocities and accelerations are the following:

$$\text{jointValues} = [\frac{\pi}{2}, -0.2, \frac{\pi}{3}]$$

$$\text{velocityValues} = [5, 2, 8]$$

$$\text{accelerationValues} = [4, 1, 2]$$

## 5 Control Scheme

### 5.1 PD control law with gravity compensation in joint space

$$\mathbf{B}(q)\ddot{q} + \mathbf{C}(q, \dot{q})\dot{q} + \mathbf{F}\dot{q} + \mathbf{g}(q) = \mathbf{g}(q) + \mathbf{K}_P\tilde{q} - \mathbf{K}_D\dot{q} \quad (33)$$

## GRAVITY COMPENSATION

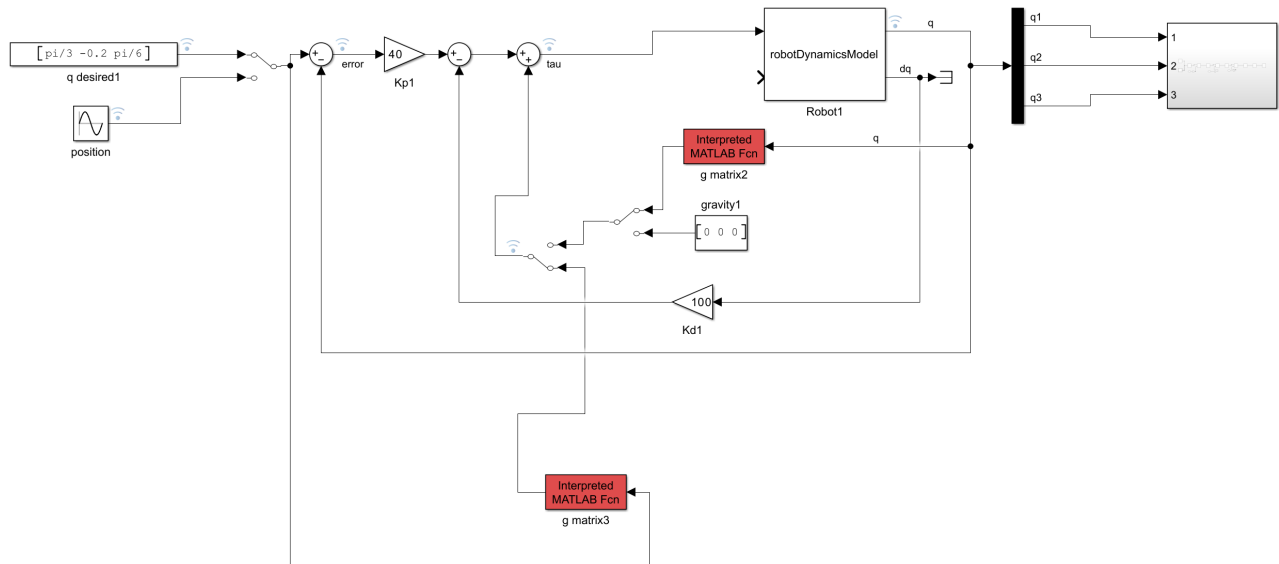


Figure 2: PD control law with gravity compensation in joint space

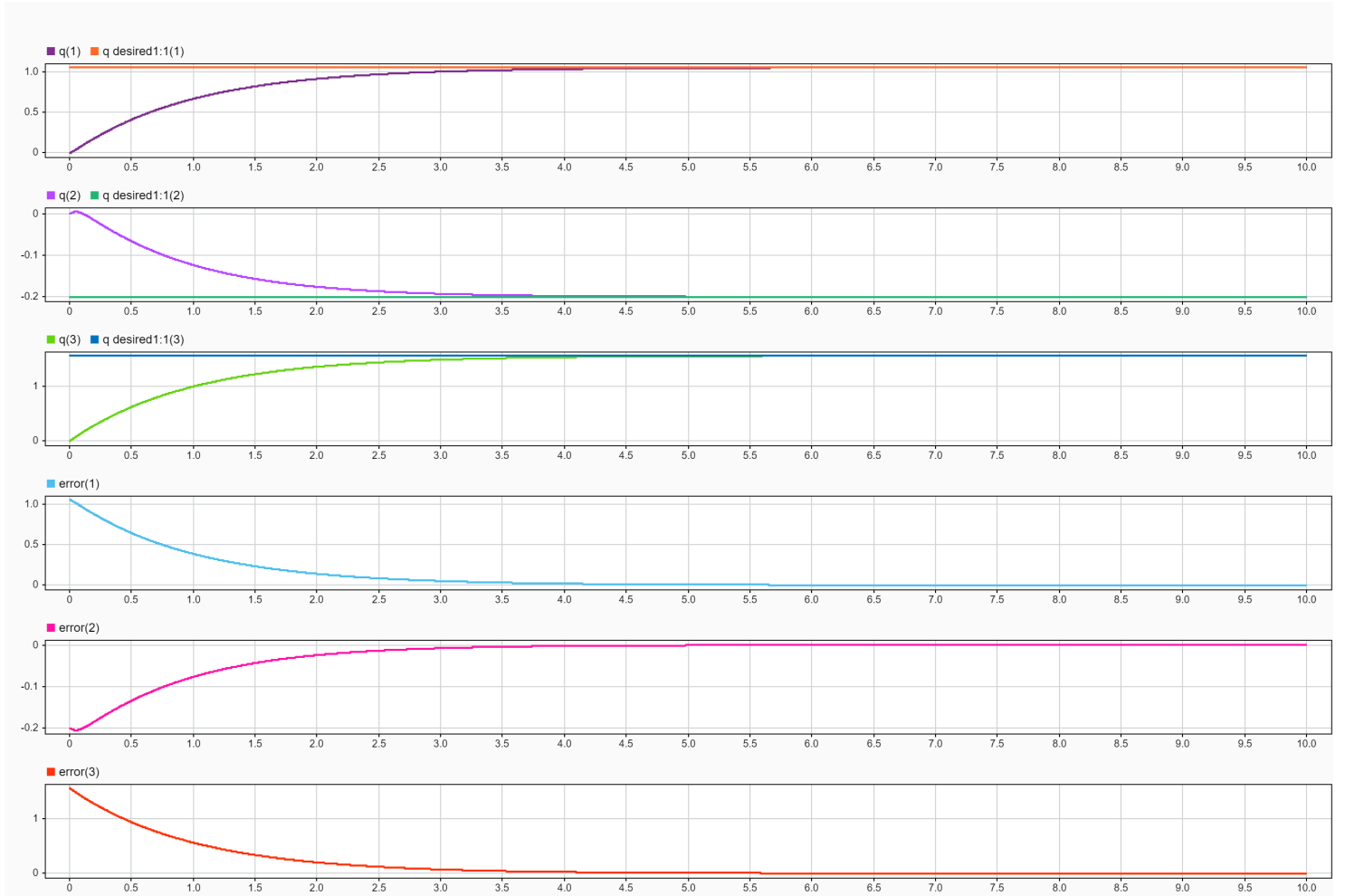


Figure 3: PD control law with gravity compensation in joint space

## 5.2 Inverse dynamic control law in joint space

$$\tau = \mathbf{B}(q)[\ddot{q}_d + K_D(\dot{q}_d - \dot{q}) + K_P(q_d - q)] + n(q, \dot{q}) \quad (34)$$

### Inverse Dynamic Control joint space

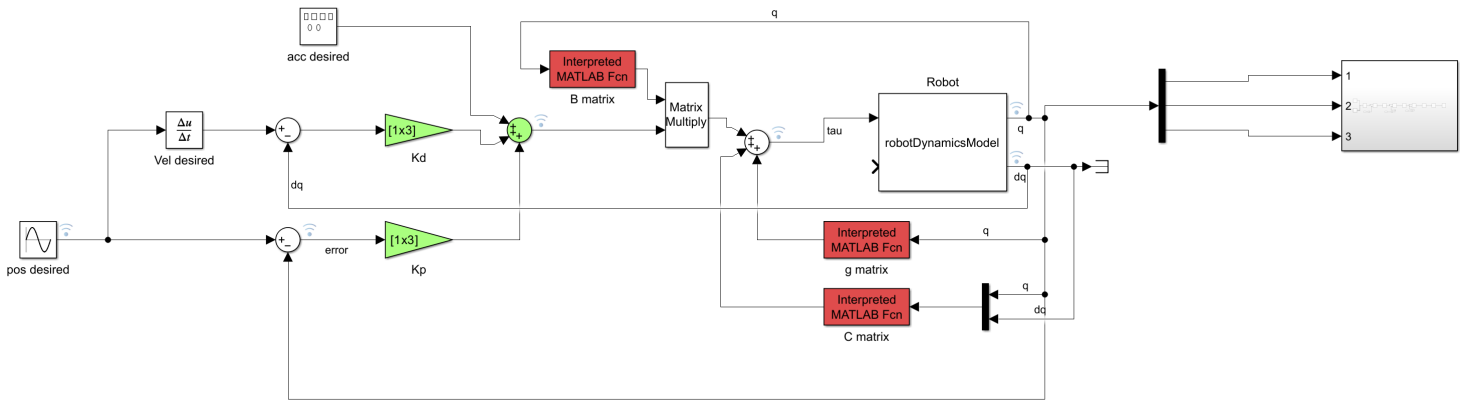


Figure 4: Inverse dynamic control law in joint space

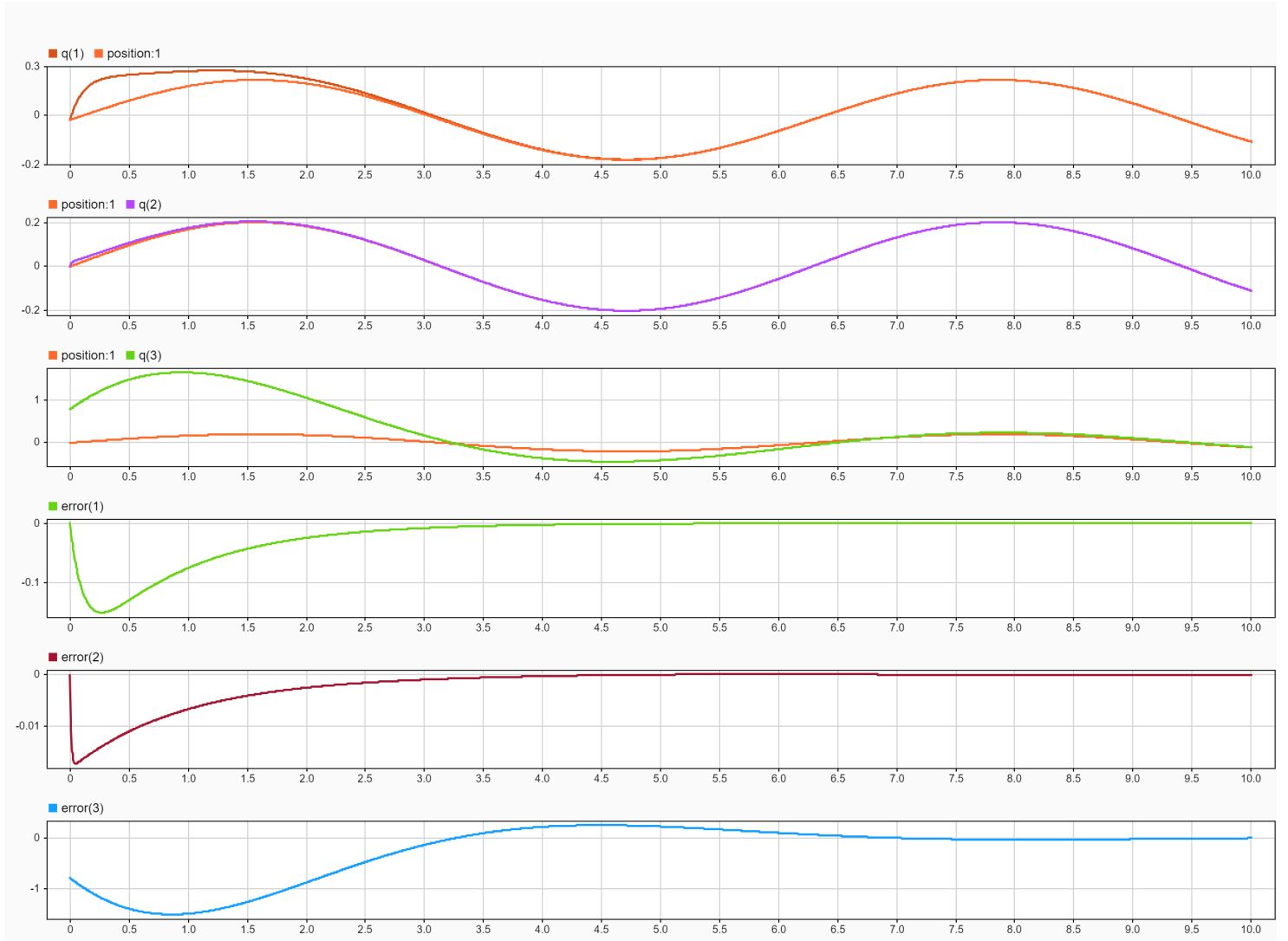


Figure 5: Inverse dynamic control law in joint space

### 5.3 Adaptive Control

Adaptive control represents an advanced control strategy that addresses the challenge of system uncertainty by estimating unknown parameters during operation. This control approach is particularly valuable when dealing with systems whose dynamic parameters are not precisely known or may vary over time.

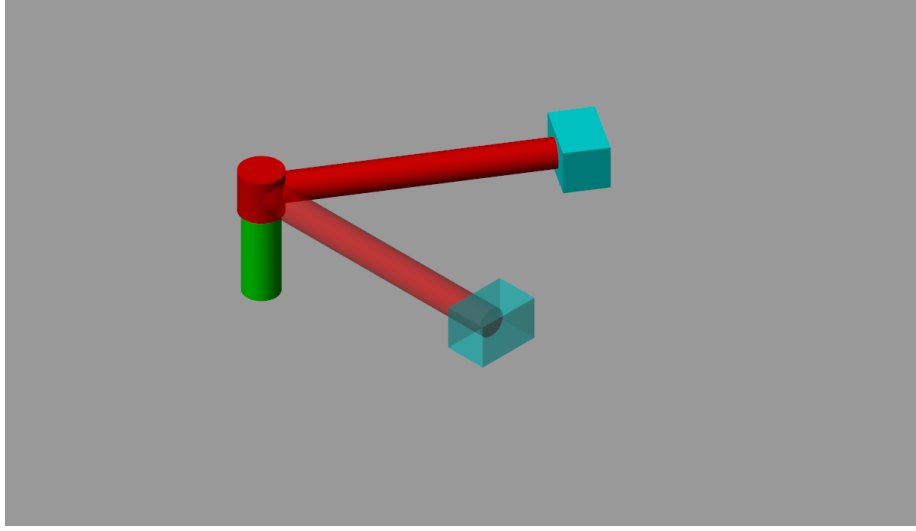


Figure 6: Adaptive control scheme

Traditional control schemes, such as the inverse dynamic control law in joint space:

$$\tau = B(q)\ddot{q}_d + C(q, \dot{q})\dot{q}_d + g(q) + F\dot{q}_d + K_D\dot{\tilde{q}} + K_P\tilde{q} \quad (35)$$

require precise knowledge of the dynamic parameters contained in the matrices  $B(q)$ ,  $C(q, \dot{q})$ , and  $g(q)$ . However, in practice, **these parameters are often uncertain or imperfectly known**, which can significantly degrade control performance.

The fundamental objective of adaptive control is to estimate the unknown dynamic parameters of a system while simultaneously minimizing the tracking error along a desired trajectory. This dual purpose makes adaptive control particularly suited for robotic applications where model uncertainties are common.

#### Parameter Estimation Strategy

Consider the modified control equation where we replace the unknown parameters with their estimates:

$$\tau = \hat{B}(q)\ddot{q}_r + \hat{C}(q, \dot{q})\dot{q}_r + \hat{F}\dot{q}_r + \hat{g}(q) + K_D\sigma = Y(q, \dot{q}, \ddot{q}_r)\hat{\Theta} + K_D\sigma \quad (36)$$

where:

- $\hat{\Theta}$  represents the vector of estimated parameters;

- $Y(q, \dot{q}, \dot{q}_r, \ddot{q}_r)$  is the regressor matrix based on reference trajectories;
- $\sigma = \dot{\tilde{q}} + \Lambda \tilde{q}$  is the composite tracking error;
- $\dot{q}_r = \dot{q}_d + \Lambda \tilde{q}$  is the reference velocity and  $\ddot{q}_r = \ddot{q}_d + \Lambda \dot{\tilde{q}}$  is the reference acceleration.

#### Parameter Update Law

The key innovation in adaptive control lies in the parameter update mechanism. The parameter estimation error is defined as:

$$\tilde{\Theta} = \Theta - \hat{\Theta} \quad (37)$$

where  $\Theta$  represents the true (but unknown) parameter vector.

The adaptive update law is designed to minimize this parameter error while ensuring system stability:

$$\begin{cases} \tau = Y(q, \dot{q}, \dot{q}_r, \ddot{q}_r) \hat{\Theta} + K_D \sigma \\ \dot{\hat{\Theta}} = \Gamma Y^T(q, \dot{q}, \dot{q}_r, \ddot{q}_r) \sigma \end{cases} \quad (38)$$

where  $\Gamma = \Gamma^T \succ 0$  is a positive definite gain matrix that controls the rate of parameter convergence.

The adaptive control law ensures that:

1. The tracking error  $\tilde{q}$  converges to zero as  $t \rightarrow \infty$
2. The parameter estimates  $\hat{\Theta}$  remain bounded
3. The closed-loop system is globally stable

The parameter update law acts as a gradient descent algorithm on the tracking error, effectively adjusting the parameter estimates to minimize the discrepancy between the actual and desired system behavior.

The adaptive control approach provides a systematic framework for handling parameter uncertainty in robotic systems, making it particularly valuable for applications where precise system identification is challenging or where parameters may vary during operation.

To illustrate the concept, we consider a simple example of a 1-DoF arm with the following dynamic equation:

$$I\ddot{q} + F\dot{q} + mgd \sin q = \tau \quad (39)$$

By defining the gravitational parameter constant as  $G = mgd$ , this can be rewritten in the linear regressor form as:

$$\tau = \begin{bmatrix} \ddot{q} & \dot{q} & \sin q \end{bmatrix} \begin{bmatrix} I \\ F \\ G \end{bmatrix} = Y(q, \dot{q}, \ddot{q}) \Theta \quad (40)$$

where  $\Theta = [I, F, G]^T$  is the vector of constant parameters to be estimated.



The adaptive control law replaces the actual coordinates with the reference ones in the regressor matrix and uses the estimated parameters  $\hat{\Theta}$ :

$$\tau = \hat{I}\ddot{q}_r + \hat{F}\dot{q}_r + \hat{G}\sin q + K_D\sigma \quad (41)$$

Consequently, the update law for the parameters  $\dot{\hat{\Theta}} = \Gamma Y^T \sigma$  becomes:

$$\dot{\hat{\Theta}} = \begin{bmatrix} \dot{\hat{I}} \\ \dot{\hat{F}} \\ \dot{\hat{G}} \end{bmatrix} = \Gamma \begin{bmatrix} \ddot{q}_r \\ \dot{q}_r \\ \sin q \end{bmatrix} \sigma \quad (42)$$

In this case, the  $\Theta$  vector is already linear, which simplifies the parameter estimation process. The adaptive control law can directly estimate these physical parameters using the update rule previously described.

Substituting in the equation of the error signal:

$$\tau = I\ddot{q}_r + F\dot{q}_r + mgd\sin q + K_D\sigma \quad (43)$$

where  $G = mgd\sin q$  represents the gravitational term.

For the first experiment, a sinusoidal trajectory was used. The real parameters  $[I, F, G]$  are in order:  $[3, 2, -4.164]$ , starting from an initial estimation (initial condition of the integral)  $[1, 1, -9.81]$ .

After an initial discrepancy, the parameters settle down to an almost steady number, and the position and velocity errors approach zero. Note that the parameters may not converge to the real ones, but are inside the null space of  $Y(q, \dot{q}, \ddot{q}_r, \ddot{q}_r)$ .

It is worth noting that while the gravitational term depends only on the position  $q$ , the inertial and friction terms in the adaptive control law explicitly depend on the reference trajectory  $\dot{q}_r$  and  $\ddot{q}_r$ . The regressor used for the control law is therefore  $Y(q, \dot{q}_r, \ddot{q}_r)$ , ensuring that the parameter adaptation is driven by the tracking requirement.

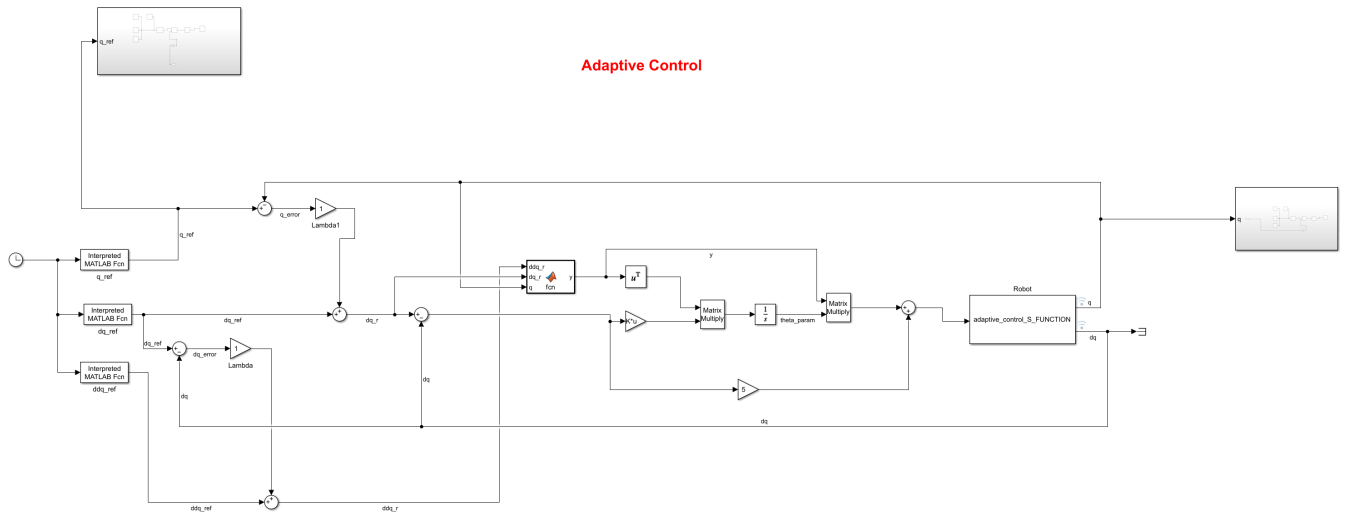


Figure 7: Adaptive control scheme

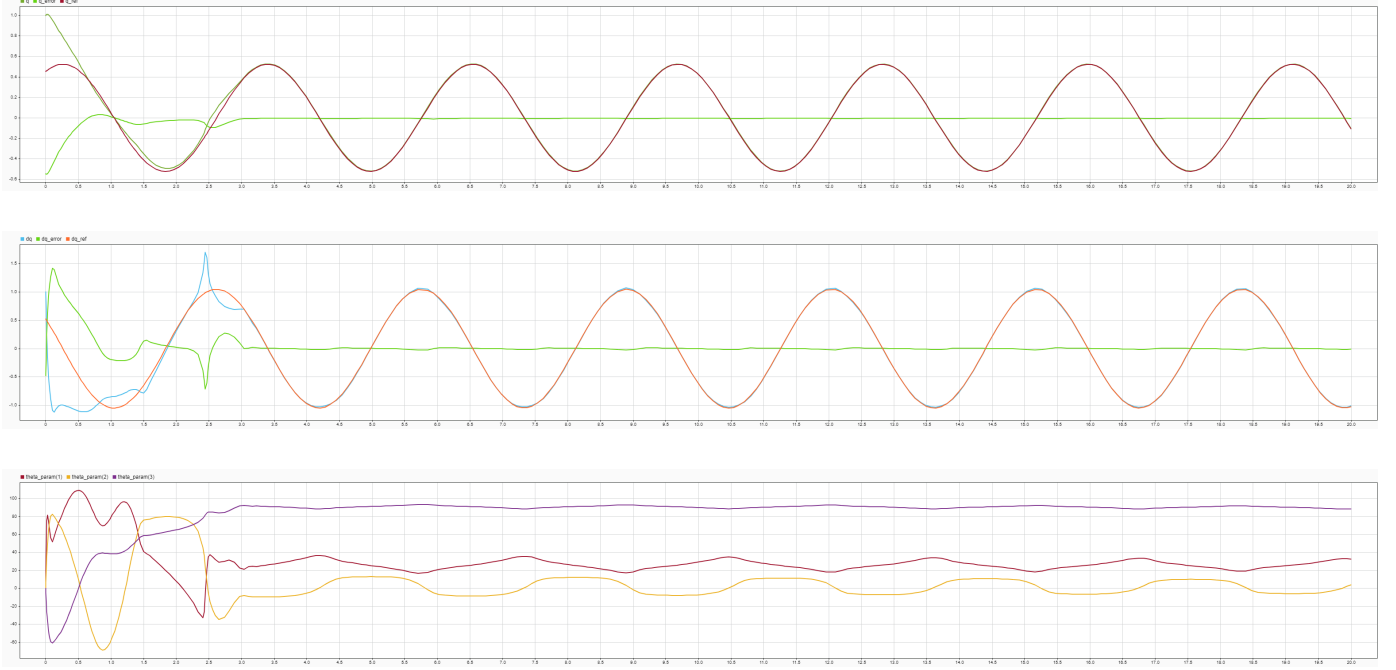


Figure 8: Adaptive control results. From top to bottom: Position tracking ( $q$  vs  $q_d$ ); Velocity tracking ( $\dot{q}$  vs  $\dot{q}_d$ ); Parameter estimation evolution  $\hat{\Theta}(t)$ . Note: In the bottom plot, 'param 1' (blue) corresponds to Inertia  $\hat{I}$ , 'param 2' (red) to Friction  $\hat{F}$ , and 'param 3' (yellow) to Gravity term  $\hat{G}$ . The estimates remain bounded as predicted by the theory.

## 5.4 PD control law with gravity compensation in the operational space

### PD with gravity compensation in the Operational Space

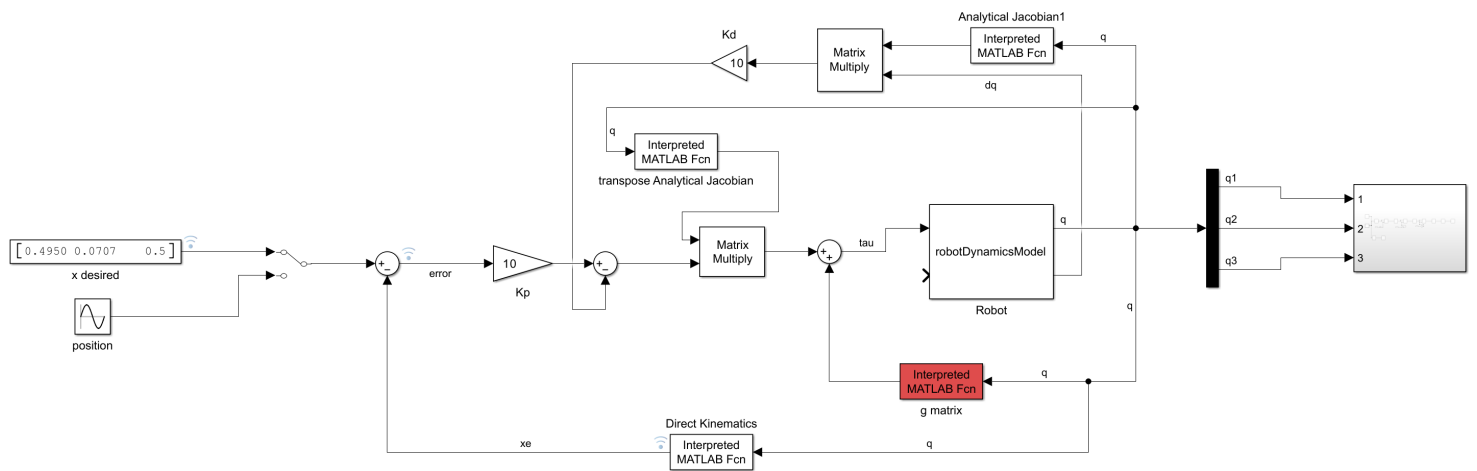


Figure 9: PD control law with gravity compensation in the operational space

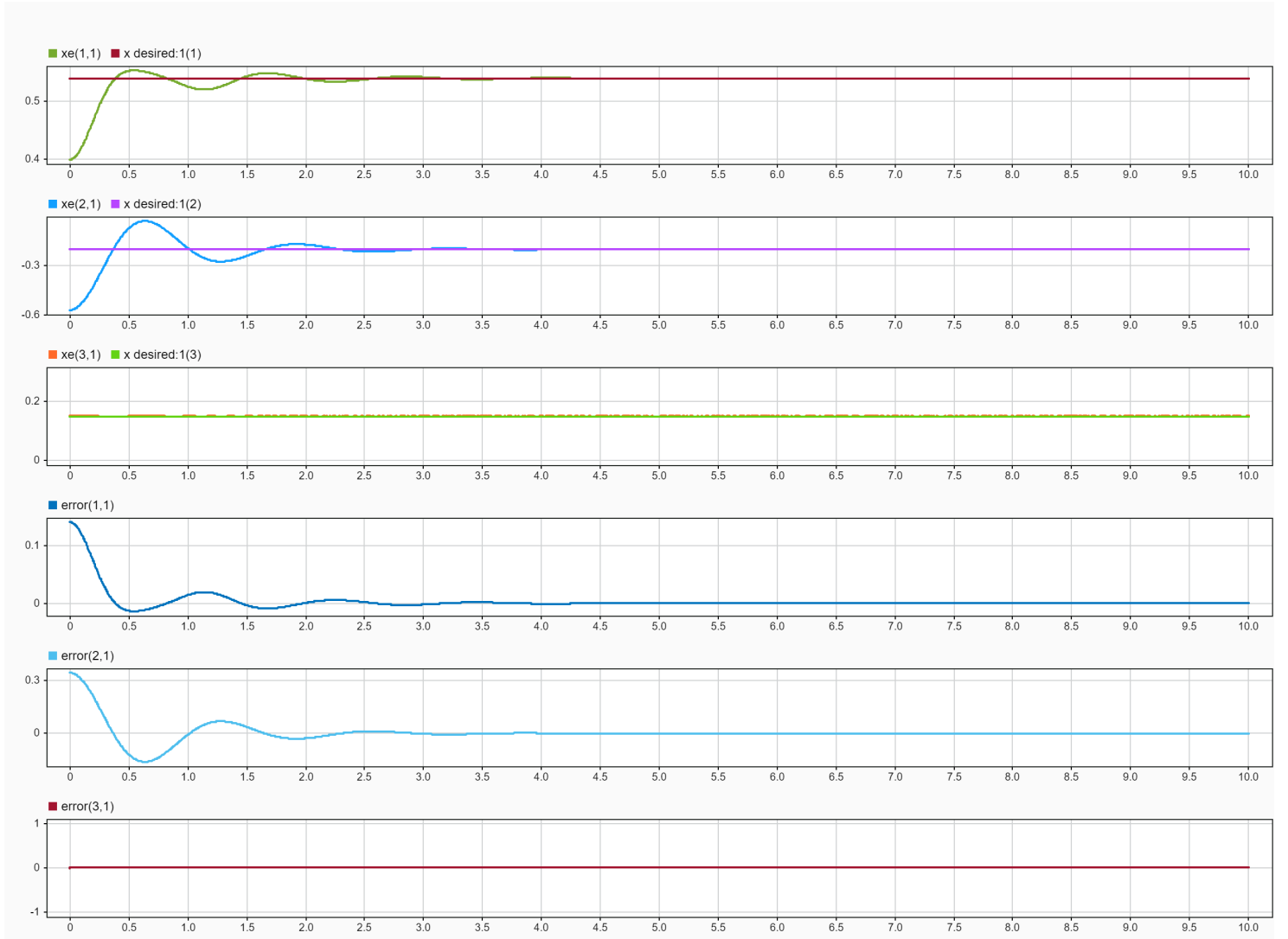


Figure 10: PD control law with gravity compensation in the operational space

## 5.5 Inverse dynamic control law in the operational space

Here I study two different cases: the first one is the case where the robot can reach the configuration, and the second one is the case where the robot cannot reach the configuration.

In the first one we have:

## OPERATIONAL SPACE INVERSE DYNAMIC

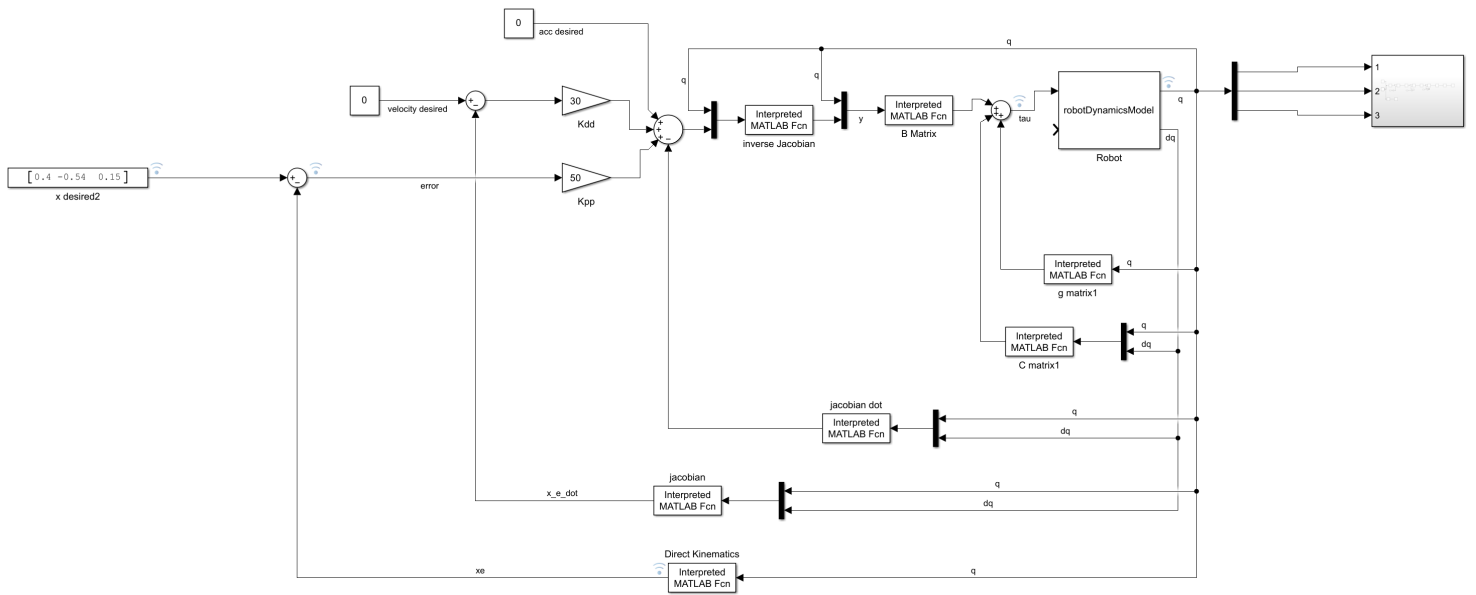


Figure 11: Inverse dynamic control law in the operational space

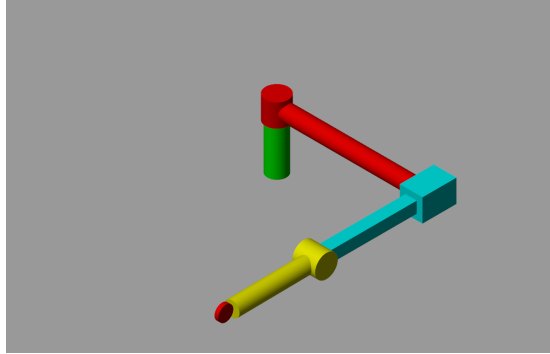


Figure 12: The robot can reach the position

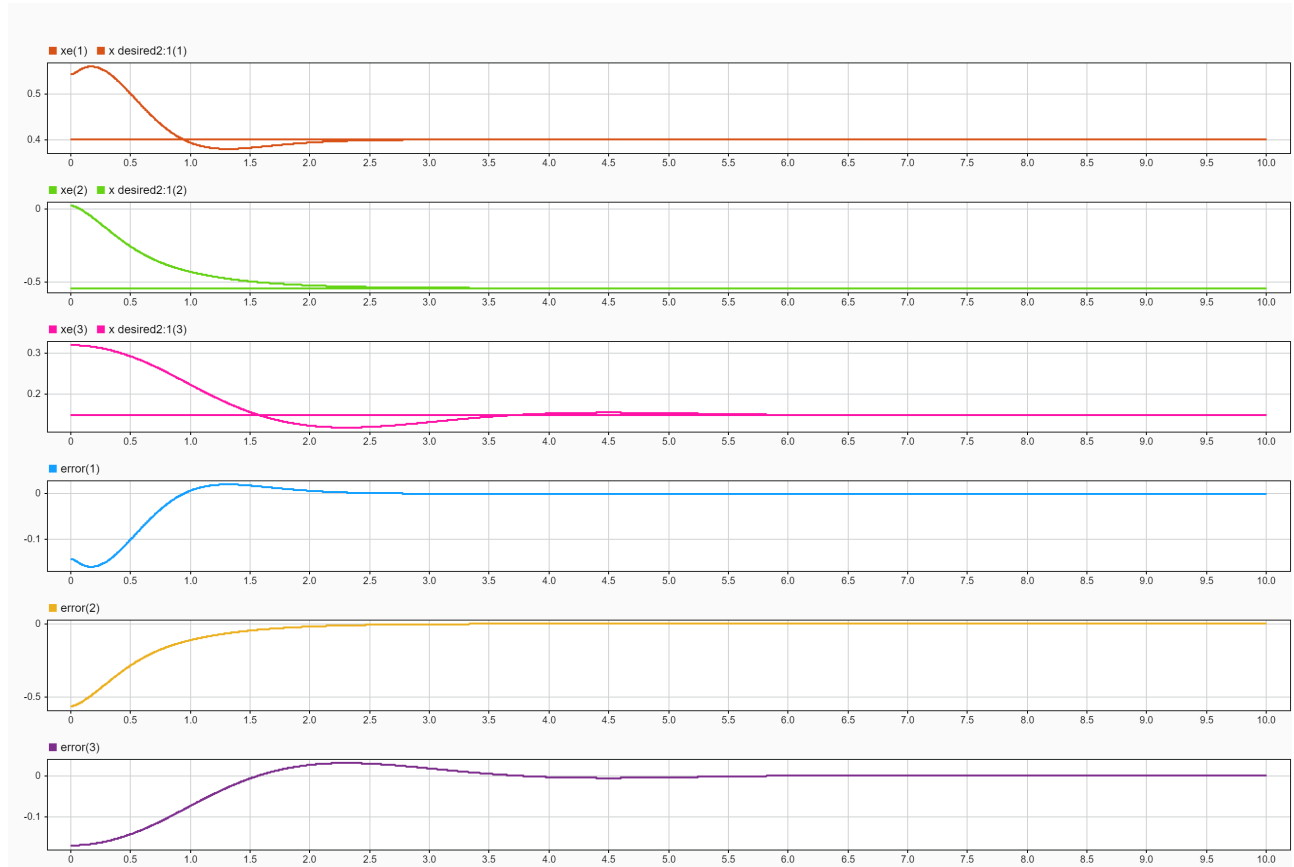


Figure 13: The robot can reach the position and the rror goes to zero

In the second one we have:

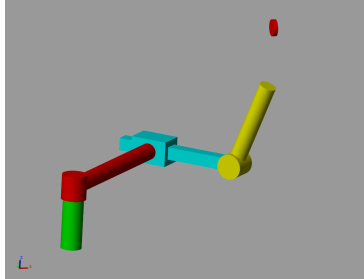


Figure 14: The robot can't reach the position

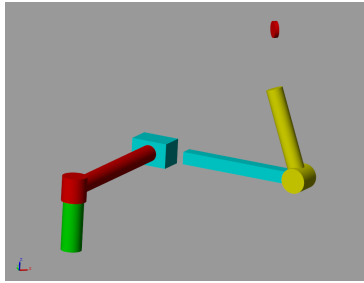


Figure 15: The robot can't reach the position

where we can note that the robot if can't reach the position, it will obscillate but it does not reach the zero steady state error.



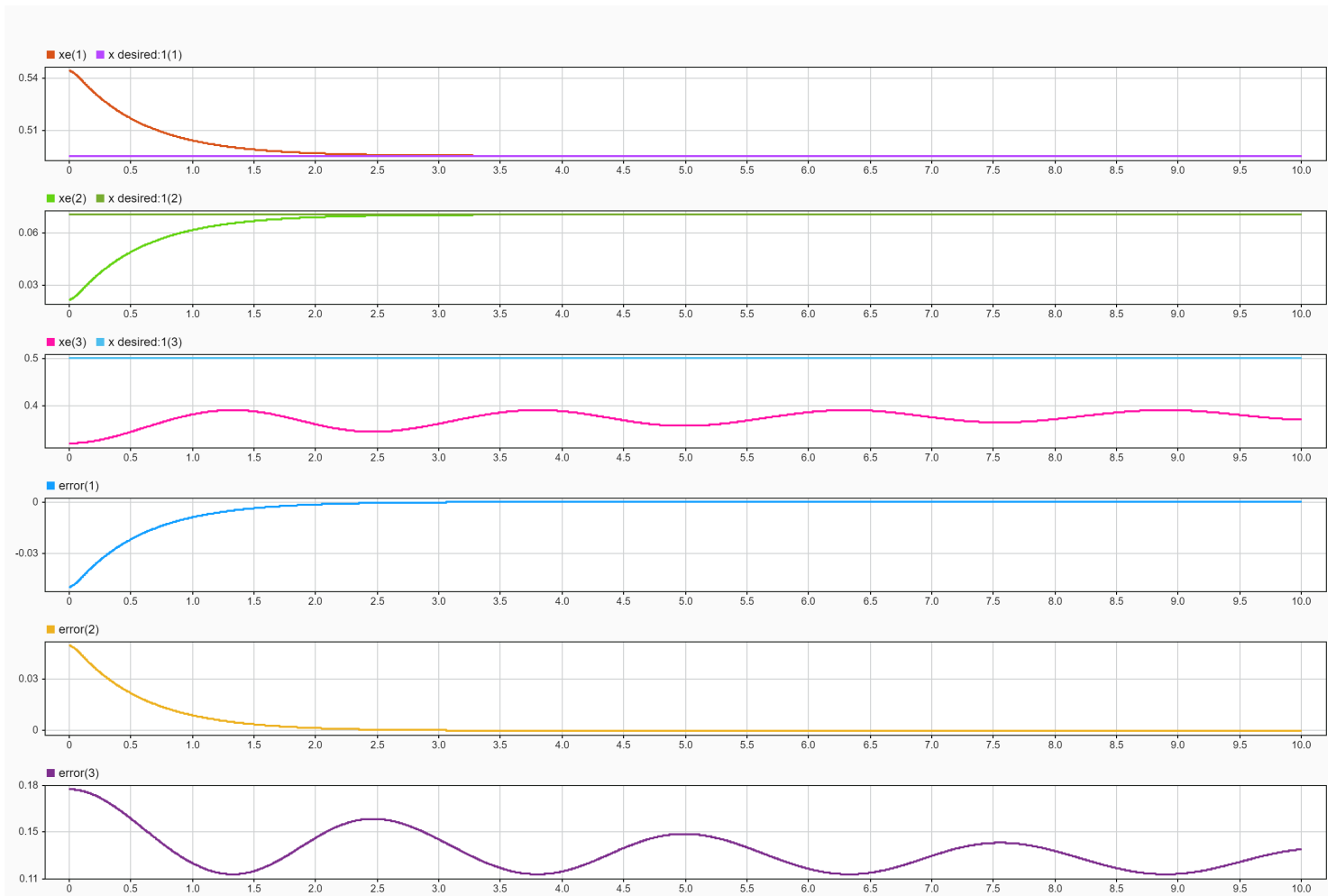


Figure 16: The robot can't reach the position and the error NOT goes to zero

## 5.6 Compliance control

In this control scheme we modify the PD with gravity compensation control scheme.

Also in the compliance control we have 2 distinct cases. The first one is the passive compliance control, where the wall acts like a spring. Of course the robot in both cases will not reach the desired position, due to the wall that is pushing it back.

# PASSIVE COMPLIANCE CONTROL

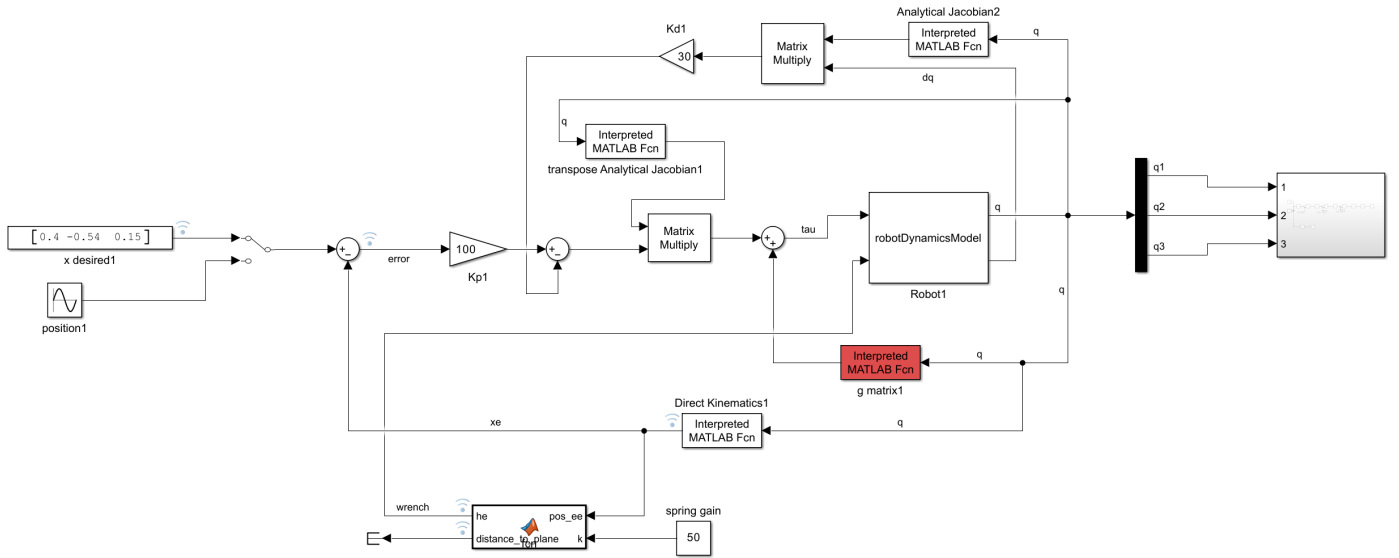


Figure 17: passive compliance control scheme

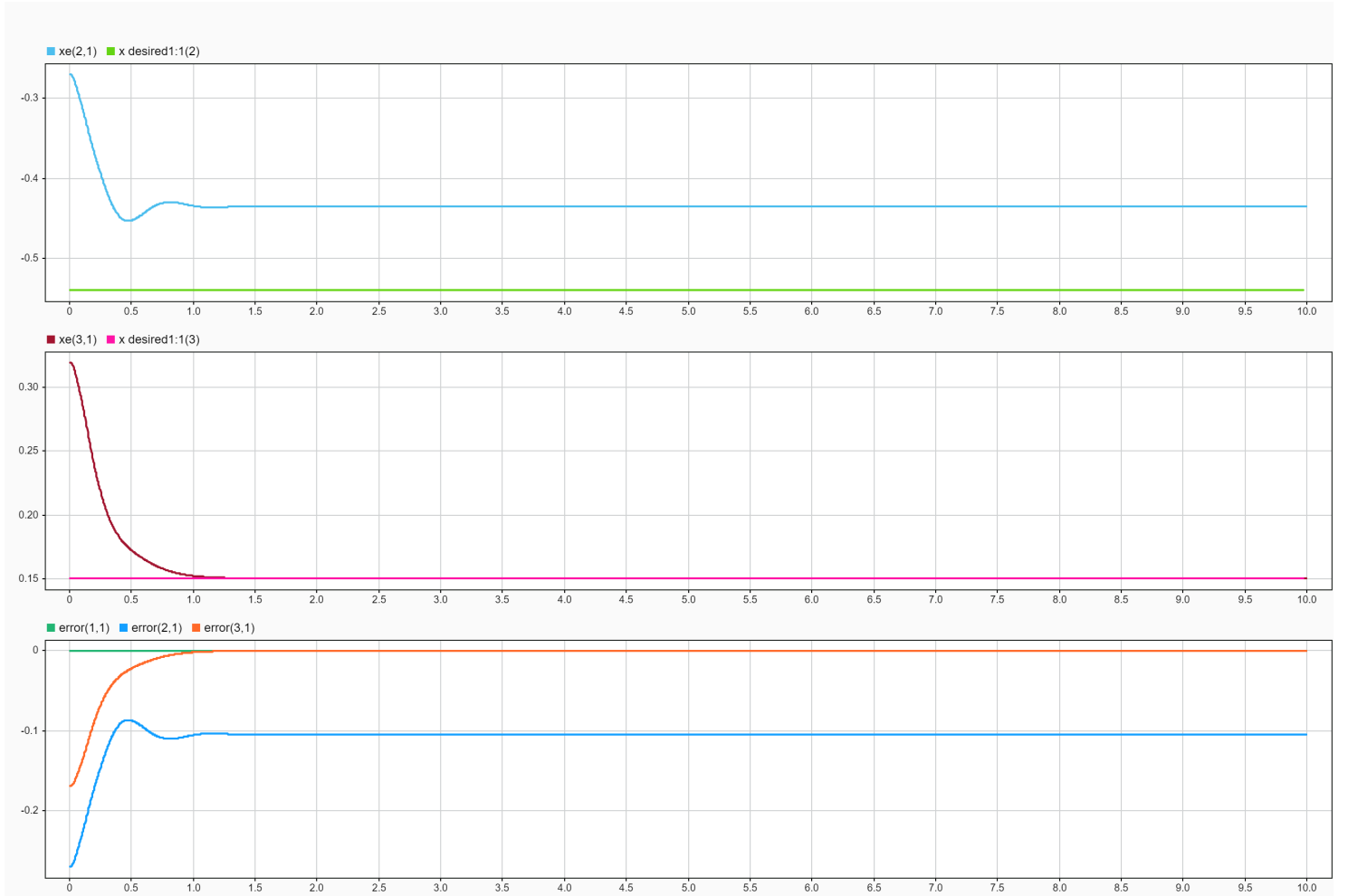


Figure 18: passiveCompliance

in the second case, that is very different from the first one, we have an active compliance control, where, with an s-function, we compute dynamically the error between the desired position and the actual one, and we use this error to compute the torques to be imparted to the motors.

In particular we use this particular Jacobian, derivative from this formula:

$$\dot{\tilde{x}} = -T_A^{-1}(\phi_{d,e}) \begin{bmatrix} R_d^T & O \\ O & R_d^T \end{bmatrix} J(q)\dot{q} = -J_{Ad}(q, \tilde{x})\dot{q} \quad (44)$$

Is super important to understand that the T matrix, is the transformation matrix from the end effector to the desired position, as reported in the matlab code below:

```

Td = [eye(3), desired_position;
      0 0 0 1];

% end effector frame
Te = A_b_ee;

% desired position in the end effector frame
T_D_e = [Td(1:3, 1:3)' * Te(1:3, 1:3), Td(1:3, 1:3)' *
         (Te(1:3, 4) - Td(1:3, 4));
         0 0 0 1];

phi = atan2(T_D_e(2, 3), T_D_e(1, 3));
gamma = acos(T_D_e(3, 3));
% psi = atan2(A_b_ee(3, 2), -A_b_ee(3, 1));

T_zyz = [0, -sin(phi), cos(phi) * sin(gamma);
         0, cos(phi), sin(phi) * sin(gamma);
         1, 0, cos(gamma)];

Ta = blkdiag(eye(3), T_zyz);

Jad = inv(Ta) * blkdiag(Td(1:3, 1:3)', Td(1:3, 1:3)')
      * J_analytical;

block.OutputPort(1).Data = Jad(1:3, 1:3);

```

## ACTIVE COMPLIANCE CONTROL

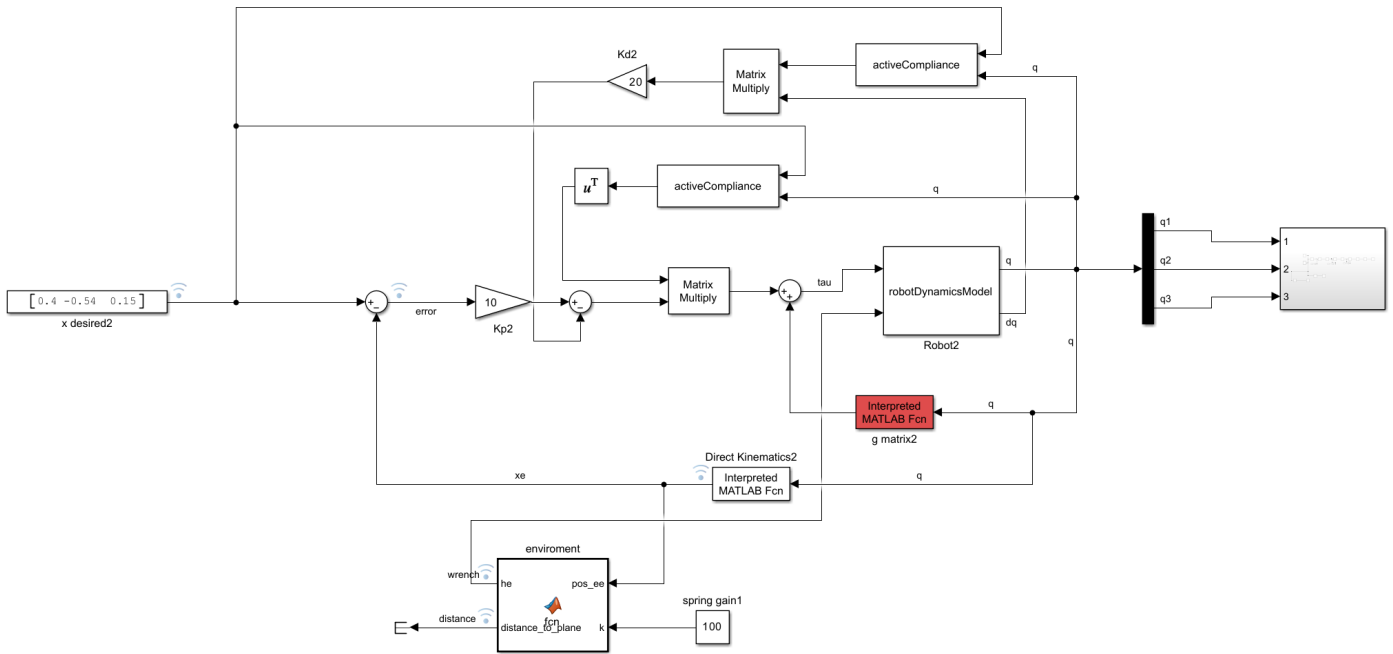


Figure 19: active compliance control scheme

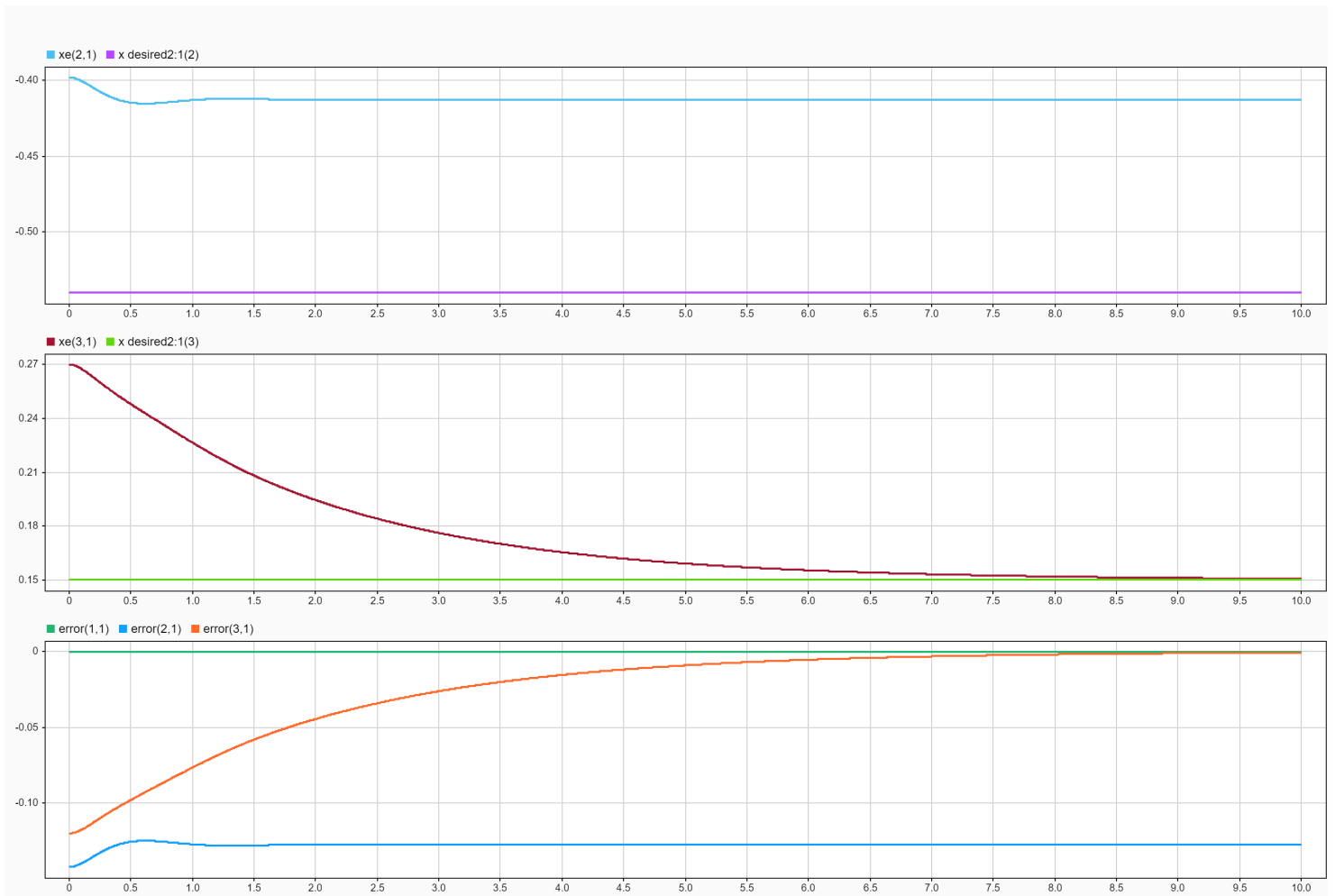


Figure 20: activeCompliance

As expected we have an error on the second joint, where the "spring" of the wall is acting, and the robot is not able to reach the desired position.

## 5.7 Force control

### 5.7.1 Block scheme of force control with inner position loop

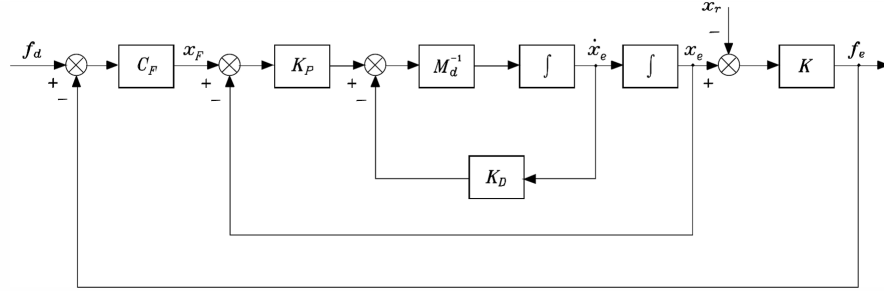


Figure 21: Block scheme of force control with inner position loop.

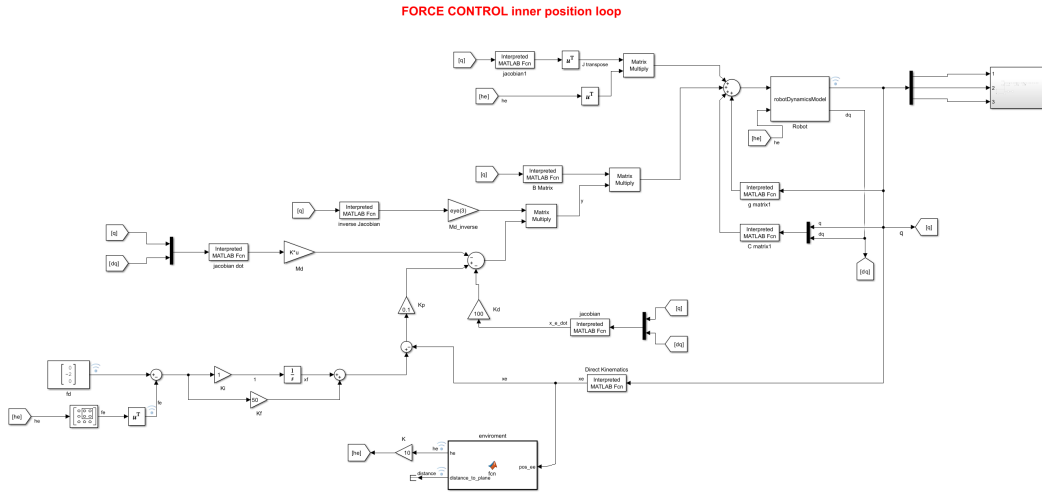


Figure 22: force control inner position

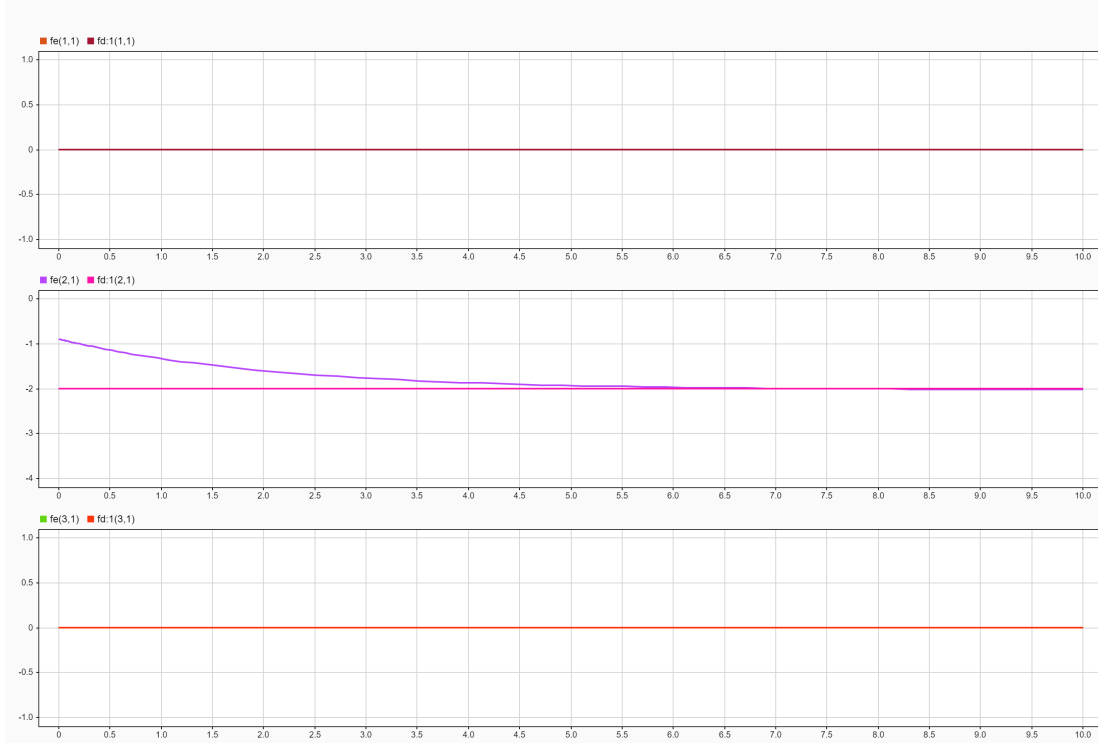


Figure 23: force control inner position

In the control scheme, if we assume  $C_f$  as a constant matrix we cannot reach the zero steady state error. But if we use an integrator, we will have the zero error.

$$C_F(s) = K_F + K_i \frac{1}{s} \quad (45)$$

### 5.7.2 Block scheme of force control with inner velocity loop

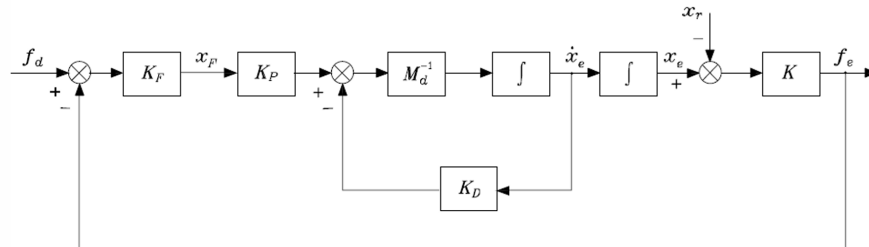


Figure 24: Block scheme of force control with inner velocity loop.



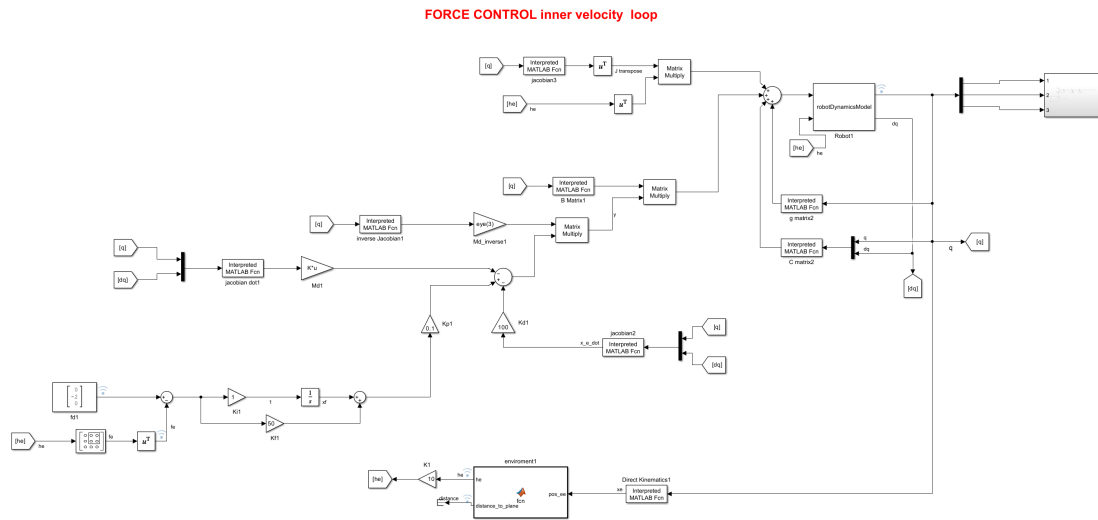


Figure 25: force control inner velocity loop

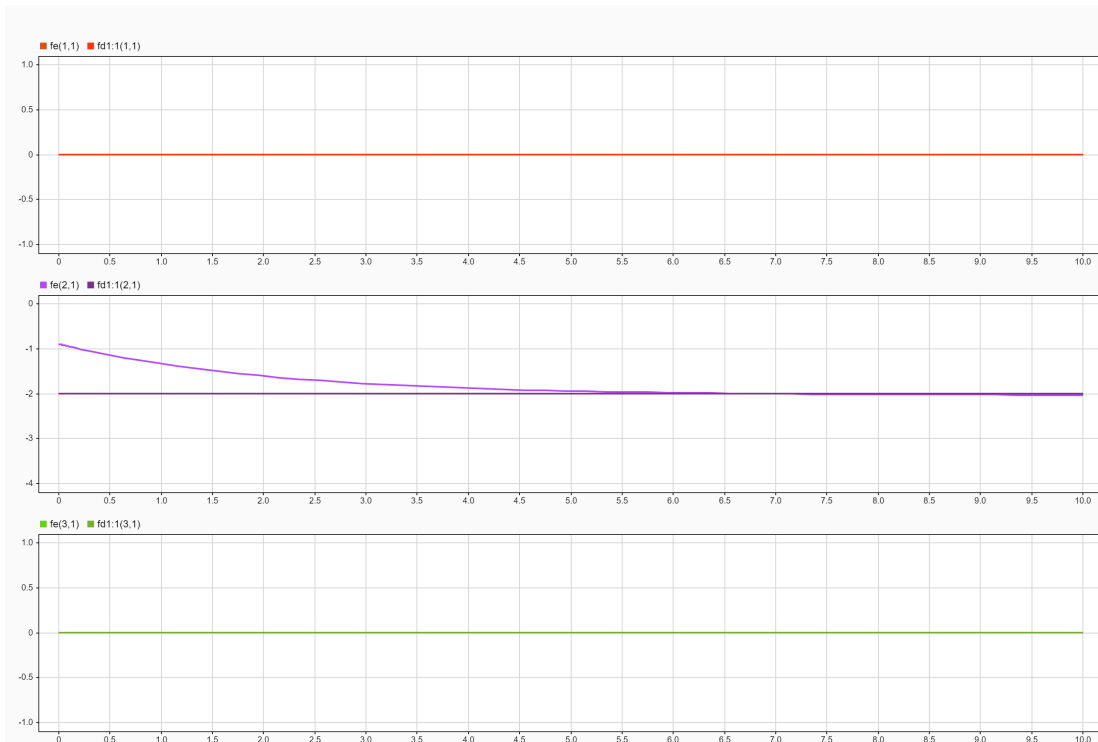


Figure 26: force control inner velocity loop

### 5.7.3 Block scheme of parallel force/position control

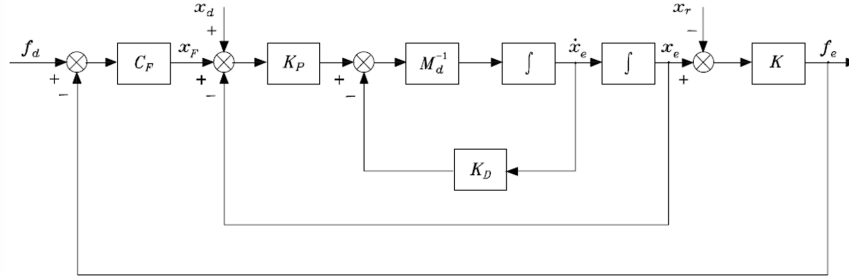


Figure 27: Block scheme of parallel force/position control.

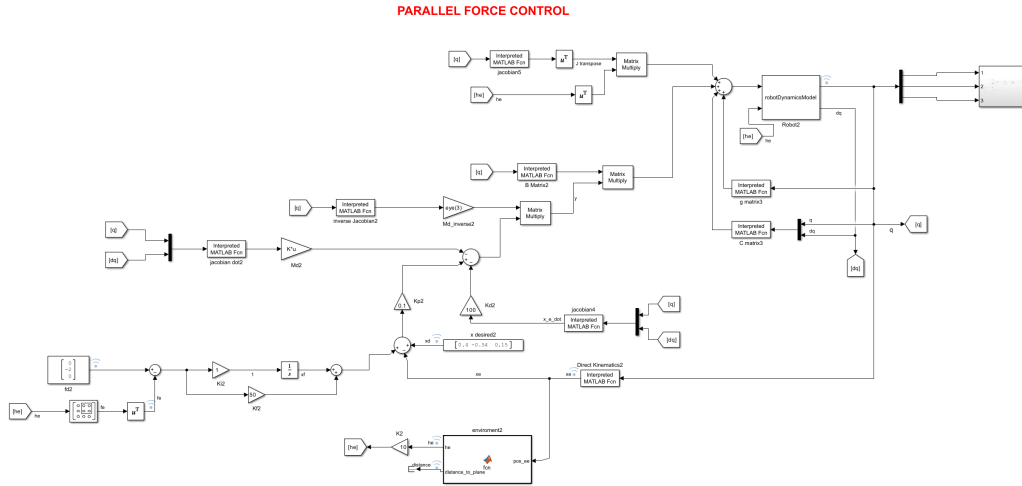


Figure 28: parallel force/position control scheme

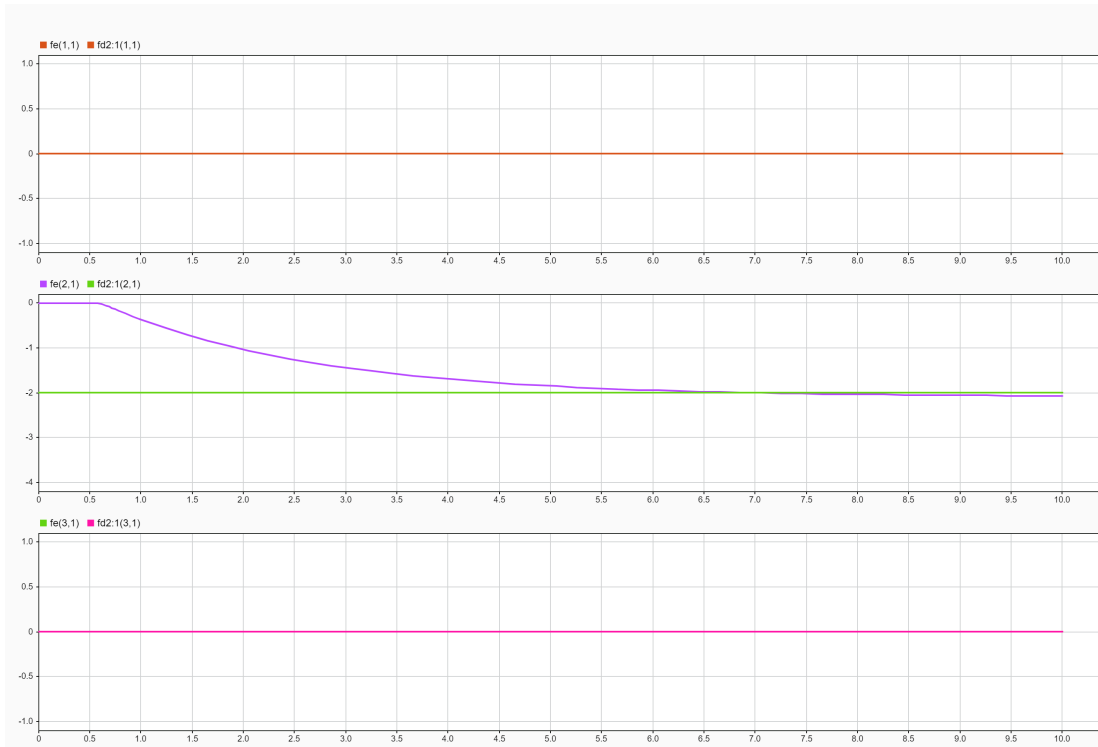


Figure 29: parallel force/position control

## 5.8 Admittance Control

The compliance control is done by solving the mechanical admittance equation (as seen in the slides):

$$M_t \ddot{\tilde{z}} + K_{D_t} \dot{\tilde{z}} + K_{P_t} \tilde{z} = h_e^d \quad (46)$$

where  $M_t, K_{D_t}, K_{P_t}$  are the impedance parameters (Mass, Damping, Stiffness) and the error is defined as the deviation of the compliant frame  $x_t$  from the desired frame  $x_d$ :

$$\tilde{z} = x_d - x_t = \begin{bmatrix} o_{d,t}^d \\ \phi_{d,t} \end{bmatrix} \quad (47)$$

By rearranging the terms, we can compute the acceleration of the compliant frame  $\ddot{x}_t$  needed for the inner motion control loop. Recalling that  $\ddot{\tilde{z}} = \ddot{x}_d - \ddot{x}_t$ :

$$\ddot{x}_t = \ddot{x}_d + M_t^{-1} (h_e^d - K_{D_t} \dot{\tilde{z}} - K_{P_t} \tilde{z}) \quad (48)$$

We then integrate  $\ddot{x}_t$  twice to obtain  $\dot{x}_t$  and  $x_t$ . The kinematic variables of the **compliant** frame  $x_t$  are then sent as reference input to the inverse dynamics motion control.

In the scheme, I highlighted in orange all the signals that differ from the original inverse dynamics control scheme. Regarding the environment interaction, we modeled a spring along the  $x$  axis and a viscous friction effect along the  $y$  and  $z$  axes. The desired trajectory involves drawing a circle on the  $(y, z)$  plane.

The graph shows the desired frame  $x_d$  and the resulting compliant frame  $x_t$ , which is computed based on the force measurements. The manipulator follows the compliant frame  $x_t$ , ensuring a compliant behavior determined by the impedance gains  $K_{pt}, K_{dt}$  and the equivalent mass matrix  $M_t$ .

Furthermore, the control law includes the force vector multiplied by the Jacobian transpose ( $J^T h_e$ ). This term maps the end-effector wrench into joint torques to compensate for the external forces, allowing the robot to accurately track the compliant frame even during contact with the environment.

## ADMITTANCE CONTROL

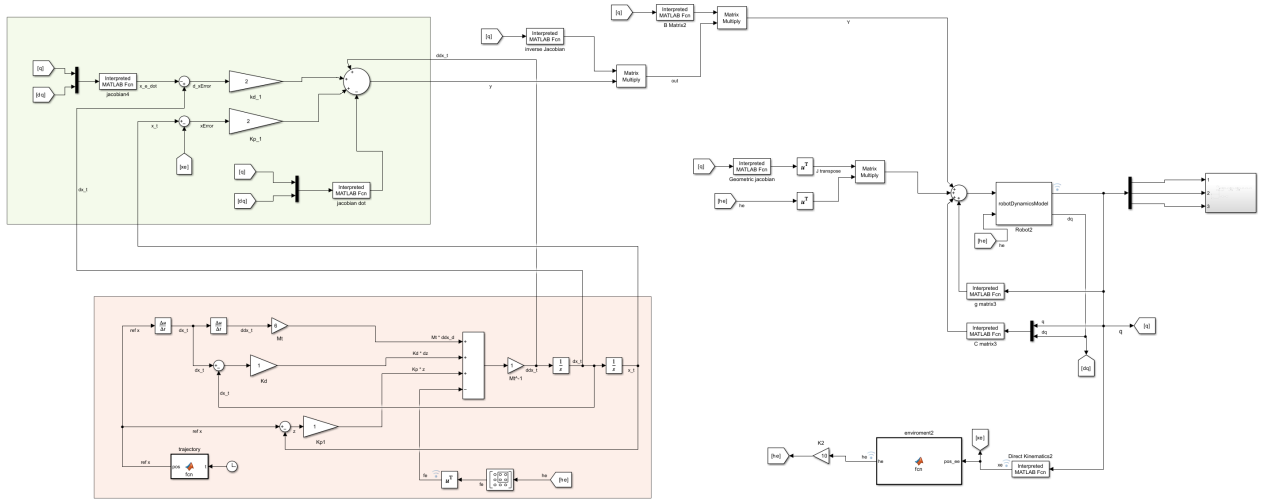


Figure 30: Admittance control scheme

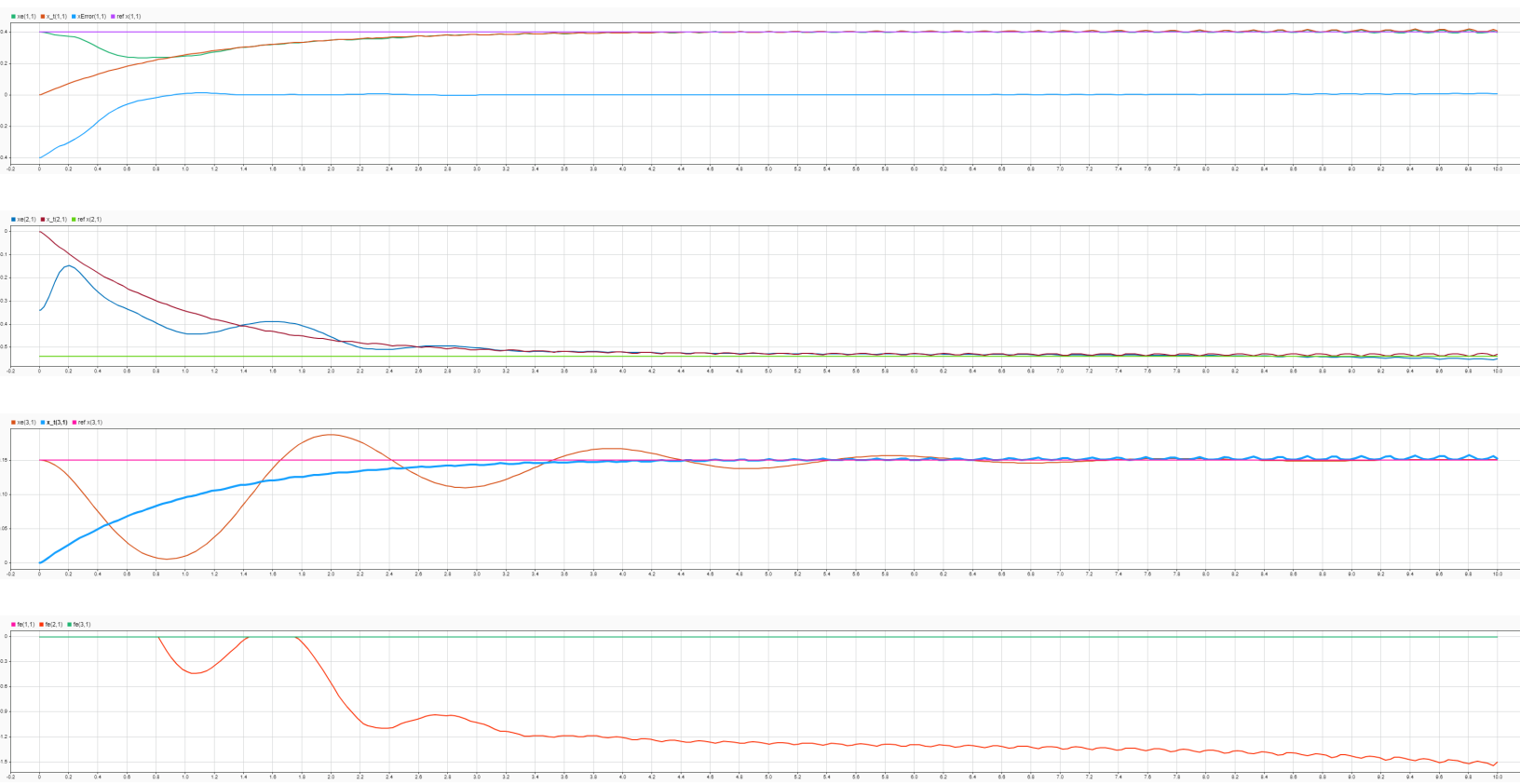


Figure 31: admittance control with environment contact forces