Zener Model based Impedance Control for High-precision Force Tracking of Robot-environment Interaction

Xi Wu, Panfeng Huang, Zhengxiong Liu and Zhiqiang Ma School of Astronautics, Northwestern Polytechnical University, China

- Combined the conventional Voigt impedance model and Maxwell impedance model.
- Switching model with parameter changing.
- Force tracking is less affected by the uncertainty of the robot dynamics and environmental force.
- Proving the system is still stable even in the presence of uncertainties in the environment.

