

Error Constrained Hybrid Force/Position of a Grinding Robot

Chenglin Zhang, Ning Sun*, Yiheng Chen, Zehao Qiu,
Wenchuang Sang, and Yongchun Fang

Institute of Robotics and Automatic Information Systems,
College of Artificial Intelligence, Nankai University, China

- The contact force model between the environment and the robot is presented.
- A hybrid force/position control method is given and a force controller is proposed.
- By using Lyapunov methods, the stability of the system is proven.
- By numerical simulations, the effectiveness of the presented force controller is verified.

