A Working Example of an Adaptive Controller With the Slotine Li Algorithm

Roberto Cadena Vega

Abstract—The abstract goes here.

I. INTRODUCTION

THIS demo file is intended to serve as a "starter file" for IEEE journal papers produced under LATEX using IEEEtran.cls version 1.8a and later. I wish you the best of success.

mds
September 17, 2014

II. CLASSICAL RESULTS

A. Slotine Li Algorithm for Non-linear Robot Manipulators

Subsection text here.

B. Servomechanism Model

Subsection text here.

C. Parameter Identification

Subsection text here.

D. Trajectories generation

Subsection text here.

III. EXPERIMENT PARAMETERS

Subsection text here.

IV. EXPERIMENTAL RESULTS

Subsection text here.

V. CONCLUSIONS

Subsection text here.

VI. CONCLUSION

The conclusion goes here.

APPENDIX A
PROOF OF THE FIRST ZONKLAR EQUATION

Appendix one text here.

APPENDIX B

Appendix two text goes here.

ACKNOWLEDGMENT

The authors would like to thank...

REFERENCES

[1] H. Kopka and P. W. Daly, *A Guide to LATEX*, 3rd ed. Harlow, England: Addison-Wesley, 1999.

R. Cadena Vega is a student of the Department of Automatic Control, CINVESTAV-IPN, México e-mail:(rcadena@ctrl.cinvestav.mx).
Manuscript delivered April 20, 2015