

Force Control of an RPR manipulator
EL 522 Final Project

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Abstract

While positioning of manipulator end effectors is an important task, often applying a particular force to the environment is needed. This paper describes a basic hybrid force control technique and presents simulation results.

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Chapter 1

Introduction

1.1 Concept and Motivation

1.2 Feedback Linearization

1.3 Hybrid Force Control

1.4 Manipulator Model

1.5 Environmental Model

Chapter 2

Results

2.1 Position Error

2.2 Force Error

Chapter 3

Conclusion