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Dynamics and Control of Robot Manipulators

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Message from the Guest Editors

Robotic manipulators are becoming increasingly complex systems in order to meet market demands for their safer and more flexible use. Complex robotic systems, such as mobile collaborative robots, aerial robots, parallel robots, cable-driven robots, or continuum robots, are modifying the way robots are perceived and exploited in several areas. In order for these systems to be effective, researchers are faced with new challenges, such as: trajectory planning must account for robot dynamics; control algorithms should adapt to variable robot and/or payload parameters and disturbances; robot-link elastic behavior, resulting in large deflection and/or vibratory phenomena, needs to be evaluated and compensated for; etc.

The aim of this Special Issue is to collect original theoretical results about robot dynamic modeling and control, as well as experimental studies related to their use in real-world applications.



