

This book covers the most attractive problem in robot control, dealing with the direct interaction between a robot and a dynamic environment, including the human-robot physical interaction. It provides comprehensive theoretical and experimental coverage of interaction control problems, starting from the mathematical modeling of robots interacting with complex dynamic environments, and proceeding to various concepts for interaction control design and implementation algorithms at different control layers. Focusing on the learning principle, it also shows the application of new and advanced learning algorithms for robotic contact tasks. The ultimate aim is to strike a good balance between the necessary theoretical framework and practical aspects of interactive robots. Contents: Control of Robots in Contact Tasks: A Survey; A Unified Approach to Dynamic Control of Robots; Impedance Control; Practical Synthesis of Impedance Control; Robust Control of Human-Robot Interaction in Haptic Systems; Intelligent Control Techniques for Robotic Contact Tasks.

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