



A Sensorless Virtual Slave Control Scheme for Kinematically Dissimilar Master-Slave Teleoperation

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GRIN Verlag Okt 2015, 2015. Taschenbuch. Book Condition: Neu. 210x148x2 mm. This item is printed on demand - Print on Demand Neuware - Scientific Essay from the year 2012 in the subject Engineering - Robotics, Universidad Politécnica de Madrid, language: English, abstract: This paper is organised as follows: section 2 summarises the remote handling issues in the design of control rooms for teleoperating dissimilar master-slave bilateral systems, section 3 covers the radiation tolerance of robotics systems with special attention to force sensors, in section 4 the sensorless virtual slave architecture is explained and the theory behind the sensorless force feedback is discussed. Section 5 details the experimental equipment used in this research while in section 6 we present the results obtained in 1 degree of freedom. Finally in 7 we present the conclusions and future applications of this technique in multiple degrees of freedom. The use of telerobotic systems is essential for remote handling (RH) operations in radioactive areas of scientific facilities that generate high doses of radiation. Recent developments in remote handling technology has seen a great deal of effort being directed towards the design of modular remote handling control rooms equipped with a standard master arm which will...



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