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Inverse Dynamics control of a robotic manipulator

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In this paper, the control purpose is to make \mathbf{q} , where \mathbf{q}_d denotes the desired trajectory. 3. Adaptive Tracking Control. We first discuss the controller design of robot manipulators with known model, then design adaptive laws and control law for the robot with uncertain kinematics, dynamics, and actuator model to realize trajectory tracking control.

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