Telerobotic Applications

Tyler Schilling

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Telerobotic Applications:

Telerobotic Applications Tyler Schilling,2000 Telerobotic Applications provides an overview of recent telerobotic developments and resulting applications particularly suitable for hazardous or inaccessible environments These specially commissioned articles demonstrate a broad range of task complexity and this should reward the reader with insights into the difficulties routinely encountered in remote applications Examples are mainly taken from the nuclear industry and include remote sampling systems tele operated vehicle and manipulator systems and climbing walking robots for operation within hostile environments These systems must negotiate impractically small openings endure unreasonable temperatures and withstand various forms of radiation while performing some difficult tasks BOOK JACKET   Advances in Telerobotics Manuel Ferre,Martin Buss,Rafael Aracil,Claudio Melchiorri,Carlos Balaguer,2007-08-10 A fascinating book that covers in detail all of the most recent advances in Telerobotics A must read for scientists researchers and students in teleoperation it describes everything from methods and experimental results to applications and developments Its three sections cover human system interfaces control and applications   Model-based Collision Avoidance for Tele-robotic Applications Stephen Patrick Strenn,1993   Technology for Large Space Systems ,1990   **Space Station Systems** ,1990   **Development and Application of a Human Grasp Taxonomy to Specify the Robotic End Effector Design for the LLNL DOR Process** Robert Benjamin Addis,1998   **Absolutely Stable Force Control for Telerobotic Applications** John Scot Hart Jr,2010 The objective of bilateral telerobotic control architectures has long been to provide as tight a connection as possible between a human operator and the remote environment Ideally the telerobot would be completely transparent allowing the user to feel as if they were directly touching the remote environment The physical reality of remote manipulation requires the telerobot to consist of a master and a slave robot as well as a control system to connect the two devices Unfortunately all three of these systems have dynamics that limit the transparency of the overall telerobot In particular transparency is severely limited when using large industrial like slave robots The large internal friction forces arising from high gear ratio actuators as well as the large inertial forces arising from the heavy linkages and reflected motor inertia make it very difficult for the user to distinguish between forces arising from contact with the remote environment and forces arising from the natural dynamics of the slave robot To improve transparency of telerobots using industrial like slaves force control can be applied around the slave device in an attempt to ensure the force applied to the environment by the slave tracks the desired force generated by the telerobotic control algorithm Most force control algorithms however are plagued by instability when trying to make and maintain contact with stiff environments resulting in a persistent and potentially dangerous hammering of the environment by the slave known as contact instability The focus of this thesis is to develop a force control algorithm that can be applied to an industrial like slave device to improve the transparency of the overall telerobot without decreasing stability Included in this thesis is an analysis of the dynamic interaction between the slave robot the force control algorithm

the remote environment and the human operator which shows that contact instability is caused by unmodeled yet fundamentally unavoidable lags in the control system such as amplifier roll off or sensor bandwidth limitations The analysis further shows that in order to have guaranteed stability with all possible combinations of human and environment impedances a condition known as absolute stability it is very difficult if not impossible to hide any of the slave s inertia from either the environment or the user Based on this analysis a model based force control algorithm is developed that focuses control effort on rejecting the friction in the system without attempting to hide any of the slave s mass The controller simulates a frictionless model of the robot used to provide the ideal trajectory the robot would take in response to the forces applied by both the user and the environment A velocity controller is then used to make the robot track this idealized trajectory This model based force controller achieves perfect steady state force tracking when in contact and is provably absolutely stable both for linear one degree of freedom DOF robots and nonlinear multi DOF robots This model based force control algorithm represents a significant contribution to the field of telerobotics because it allows control engineers to utilize preexisting and well understood telerobotic control algorithms originally designed for slaves with minimal friction on telerobots using industrial like slaves where friction is clearly a dominate force Analytical and experimental results show that the addition of model based force control around these industrial like slaves improve the transparency of the telerobot regardless of the specific telerobotic control architecture being used without decreasing the overall robustness of the system

Proceedings of the Conference on Remote Systems Technology ,1989 **Telemanipulator Technology and Space Telerobotics** Won S. Kim,1993 Proceedings of the Conference on Hot Laboratories and Equipment ,1988 Depth Cues for Telerobotic Tasks in Virtual Environments Andrew Menching Liu,1992 *Proceedings of the Workshop on Space Telerobotics, Volume 3* ,1987 **Virtual and Mixed Reality in Telerobotics: A Survey** Costas S. Tzafestas,2006 This chapter has reviewed fundamental concepts and technologies of the general interdisciplinary field described usually by a combination of the terms Virtual Augmented or Mixed Reality systems with the emphasis being on their applications in robot teleoperation We have first analysed the basics of VR and AR systems which have shown a great progress of research and development activities during the last decade demonstrating a constantly increasing repertoire of useful practical applications in diverse domains of human activity We have then described application scenarios of such VR technologies in the general field of robotics with the particular focus on telerobotic applications We have started by presenting a brief historical survey of the field of telerobotics and identified the major profits that are related to the integration of VR and AR techniques Virtual environments can be seen as a means to achieve natural intuitive multimodal human computer and generally human machine interaction in this sense a VE can function as an efficient mediator between a human operator and a telerobot with the main objectives being a to enhance human perception of the remote task environment and therefore improve transparency of the telerobotic system by enriching the visual information complemented by other form of sensory

and sensori motor stimuli provided to the user thus conveying complex data in a more natural and easier way b to contribute to the solution of the time delay problem in bilateral teleoperation and improve stability of the telerobotic system by extending the concept of predictive displays and offering a range of control metaphors for both operator assistance and robot autonomy sharing We have presented a number of successful case studies where VR techniques have been effectively applied in telerobotics for the two main robotic systems categories namely i robot manipulators and ii mobile robotic vehicles A long distance parallel telemanipulation experiment was described where an intermediate virtual task representation was used involving direct hand actions by means of a VR glove device The use of telerobotic technologies in a distance training virtual and remote laboratory application has been also demonstrated with very promising results in this important domain As related to the field of mobile service robotics two application scenarios have been described to highlight the benefits that can result from the integration of VR based interfaces for the teleoperation of robotic vehicles for a variety of tasks including service intervention tasks and remote exploration The link with the field of haptics is also **Proceedings of the Workshop on Space Telerobotics, Volume 2** ,1987 **Nuclear Engineering International** ,1994 *Stereoscopic Displays and Virtual Reality Systems* ,1997 Robotics and Manufacturing Mohammad Jamshidi,François Georges Pin,Pierre Dauchez,1996 Proceedings of the May 1996 symposium Topics include experimental results of operational space control on a dual arm robot system design and control of an anthropomorphic servopneumatic finger joint robot control strategy for camera guidance in laparoscopic surgery dense reconstruction using fix **Proceedings of the Workshop on Space Telerobotics, Volume 1** ,1987 **Proceedings of the NASA Conference on Space Telerobotics, Volume 3** ,1989 **Fifth Annual Workshop on Space Operations Applications and Research (SOAR 1991), Volume 1** ,1992

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