Stability Preserving Sensor-Based Control for Robots with Positional Interface

Friedrich Lange and Gerd Hirzinger
Deutsches Zentrum für Luft- und Raumfahrt e. V. (DLR), Germany

- Robot dependent inner positional loop
- Predictive interface that allows ideal tracking of the desired path without delay
- Robot independent computation of the desired path from the sensor pose and (extrapolated) sensor signals
- Applied to force control and visual servoing