ACTIVE CONTROL OF FLUCTUATIONS OF COMPLIANT MEMBERS - FEED FORWARD COMPENSATION

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Fluctuations of compliant members like flexible machine members, robot manipulators, overhead cranes are a limitation to the accurate and speedy working of such systems. To obtain better use of such systems, control methods, either passive or active, are required. This paper describes an active method where fluctuations are controlled within one cycle.

The method is based on feed forward compensation, where the corrective action is given when a disturbance is to occur. The compensation principle is theoretically as well as practically demonstrated.

C-20 : 10th Dec. 1987 (Thursday) 04.45 p.m. - 05.00 p.m.
C-21 : 11th Dec. 1987 (Friday) 02.00 p.m. - 02.15 p.m.