

A Time-delayed Control Scheme with a Sliding Mode Controller for a Robot Manipulator

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- The time–delayed control (TDC) scheme with a sliding mode controller for a robot manipulator is presented.
- TDC is designed with the sliding mode controller (SMC) to improve the control performance.
- The performances are compared by simulating the same trajectory tracking task of a three link robot manipulator under different control schemes.

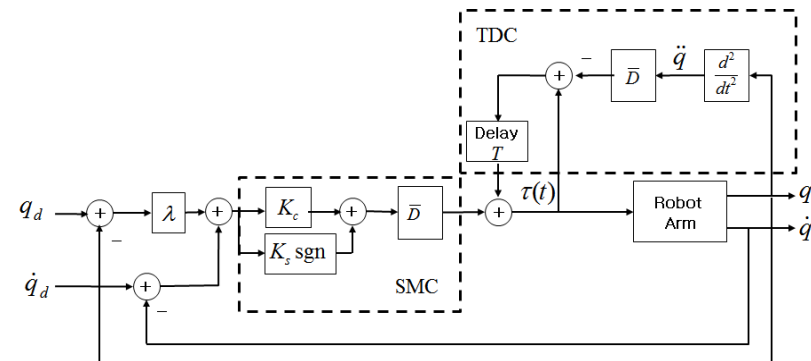


Fig. 1 TDC-SMC Control block diagram