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Control and Design Flexible-Link Manipulators
sign of flexible-link robotic manipulators. The philosophy and technical difficulties The philosophy and technical difficulties associated with these robots are illustrated in section 2.1.

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Control for flexible-link robots is a non-trivial problem that has elevated difficulty comparing to the control of rigid-link manipulators. This is because the dynamic model of the flexible-link robot contains the nonlinear rigid link motion coupled with the distributed effects of the links

Model-based and model-free control of flexible-link robots ...

The paper presents a comparative study on representative methods for model-based and model-free control of flexible-link robots. Model-based techniques for the control of flexible-link robots can come up against limitations when an accurate model is unavailable, due to parameters uncertainty or truncation of high order vibration modes.