The Robot Control Using The Wireless Communication And The

A modern and unified treatment of the mechanics, planning, and control of robots, suitable for a first course in robotics.

In the past years there has been considerable effort to move robots from industrial environments to our daily lives where they can collaborate and interact with humans to improve our life quality. One of the key challenges in this direction is to make a suitable robot control system that can adapt to humans and interactively learn from humans to facilitate the efficient and safe co-existence of the two. The applications of such robotic systems include: service robotics and physical human-robot collaboration, assistive and rehabilitation robotics, semi-autonomous cars, etc. To achieve the goal of integrating robotic systems into these applications, several important research directions must be explored. One such direction is the study of skill transfer, where a human operator’s skilled executions are used to obtain an autonomous controller. Another important direction is shared control, where a robotic controller and humans control the same body, tool, mechanism, car, etc. Shared control, in turn invokes very rich research questions such as co-adaptation between the human and the robot, where the two agents can benefit from each other’s skills or must adapt to each other’s behavior to achieve effective cooperative task executions. The aim of this Research Topic is to help bridge the gap between the state-of-the-art and above-mentioned goals through novel multidisciplinary approaches in human-in-the-loop robot control and learning.

A comprehensive exploration of the control schemes of human-robot interactions In Human-Robot Interaction Control Using Reinforcement Learning, an expert team of authors delivers a concise overview of human-robot interaction control schemes and insightful presentations of novel, model-free and reinforcement learning controllers. The book begins with a brief introduction to state-of-the-art human-robot interaction control and reinforcement learning before moving on to describe the typical environment model. The authors also describe some of the most famous identification techniques for parameter estimation. Human-Robot Interaction Control Using Reinforcement Learning offers rigorous mathematical treatments and demonstrations that facilitate the understanding of control schemes and algorithms. It also describes stability and convergence analysis of human-robot interaction control and reinforcement learning based control. The authors also discuss advanced and cutting-edge topics, like inverse and velocity kinematics solutions, H2 neural control, and likely upcoming developments in the field of robotics. Readers will also enjoy: A thorough introduction to model-based human-robot interaction control Comprehensive explorations of model-free human-robot interaction control and human-in-the-loop control using Euler angles Practical discussions of reinforcement learning for robot position and force control, as well as continuous time reinforcement learning for robot force control In-depth examinations of robot control in worst-case uncertainty using reinforcement learning and the control of redundant robots using multi-agent reinforcement learning Perfect for senior undergraduate and graduate students, academic researchers, and industrial practitioners studying and working in the fields of robotics, learning control systems, neural networks, and computational intelligence, Human-Robot Interaction Control Using Reinforcement Learning is also an indispensable resource for students and professionals studying reinforcement learning.

This book highlights relevant studies and applications in the area of robotics, which reflect the latest research, from interdisciplinary theoretical studies and computational algorithm development, to representative applications. It presents chapters on advanced control, such as fuzzy, neural, backstepping, sliding mode, adaptive, predictive, diagnosis and fault tolerant control etc. and addresses topics including cloud robotics, cable-driven robots, two-wheeled robots, mobile robots, swarm robots, hybrid vehicle, and drones. Each chapter employs a uniform structure: background, motivation, quantitative development (equations), case studies/illustration/tutorial (simulations, experiences, curves, tables, etc.), allowing readers to easily tailor the techniques to their own applications.

Controlling Robots using Blynk, Virtuino, Cayenne, Thingspeak, Firebase DESCRIPTION This book provides a platform to the readers, where they can understand the applications of ‘Internet of Things’ to control the robotic platform. It covers the basic knowledge of the mobile apps with their designing steps and programming. The objective of the book is to discuss various applications of robotic platform where ‘Internet of things’ can play an important role. This book comprises of total seventeen chapters for designing different independent prototypes for the various control methods. It covers introduction to IoT and basic components to design a robotic platform. The system demonstration is done with the help of Ti Launch Pad and other interfacing devices. The control of robot with different mobile apps like Blynk, Virtuino, Cayenne, Thingspeak, Firebase are included for vast coverage of scope. It would be beneficial for the people who want to get started with hardware based robotic prototypes with IoT. This book is entirely based on the practical experience of the authors while undergoing projects with the students and industries. KEY FEATURES The book provides gradual pace of basics to advanced interfacing and programming with Ti launch pad for IoT applications. It provides a unique style for IoT applications with program codes. It discusses various applications where the Internet of Things plays an important role, and considers a number of different independent prototypes for various mobile robotics platform control methods. The control of robot with different mobile apps like Blynk, Virtuino, Cayenne, Thingspeak, Firebase are included for vast coverage of scope. Step by step programming, to get started with Ti launch Pad Case studies to provide solution to real time problems The case studies and programming in book are tested on real hardware during handling the industrial and student projects. WHAT WILL YOU LEARN Interfacing of Ti launch Pad and NodeMCU with Input/Output Devices Serial Communication between Ti Launch Pad and NodeMCU Robot Control Using the Blynk, Virtuino App Environment Monitoring Robot with BLYNK App Sensory Data Acquisition Robot Using a ThingSpeak Server Robot Control with Cayenne App, Local Server and NodeMCU, Firebase Server WHO THIS BOOK IS FOR Students pursuing BE/BSc/ME/MSc/BTech/MTech in Computer Science, Electronics, Electrical. Table of Contents 1. Introduction 2. Components of a Robotic Platform 3. Interfacing of Ti launch Pad with Input/Output Devices 4. Interfacing of NodeMCU with Input/Output Devices 5. Serial Communication between Ti Launch Pad and NodeMCU 6. Robot Control Using the Blynk App 7. Robot Control Using the Virtuino App 8. Environment Monitoring Robot with BLYNK App 9. Sensory Data Acquisition Robot Using a ThingSpeak Server 10. Robot Control with Cayenne App 11. Robot Control with Local Server and NodeMCU 12. Robot Control with a Firebase Server 13. XBee and Wi-Fi Modem Based Robot Control 14. Fire Fighting Robot 15. The Internet of Things Robotic Arm 16. The Smart Orchard with a Robotic Arm Sprinkler 17. Smart Farming with the IoT

Programming Robot ControllersMcGraw-Hill/TAB Electronics

Tutors can design entry-level courses in robotics with a strong orientation to the fundamental discipline of manipulator control pdf solutions manual Overheads will save a great deal of time with class preparation and will give students a low-effort basis for more detailed class notes Courses for senior undergraduates can be designed around Parts I – III; these can be augmented for masters courses using Part IV

Humanoid Robots: Modeling and Control provides systematic presentation of the models used in the analysis, design and control of humanoid robots. The book starts with a historical overview of the field, a summary of the current state of the art achievements and an outline of the related fields of research. It moves on to explain the theoretical foundations in terms of kinematic, kineto-static and dynamic relations. Further on, a detailed overview of biped balance control approaches is presented. Models and control algorithms for cooperative object manipulation with a multi-finger hand, a dual-arm and a multi-robot system are also discussed. One of the chapters is devoted to selected topics from the area of motion generation and control and their applications. The final chapter focuses on simulation environments, specifically on the step-by-step design of a simulator using the Matlab® environment and tools. This book will benefit readers with an advanced level of understanding of robotics, mechanics and control such as graduate students, academic and industrial researchers and professional engineers. Researchers in the related fields of multi-legged robots, biomechanics, physical therapy and physics-based computer animation of articulated figures can also benefit from the models and computational algorithms presented in the book. Provides a firm theoretical basis for modelling and control algorithm design Gives a systematic presentation of models and control algorithms Contains numerous implementation examples demonstrated with 43 video clips

Contents:Editorial (H I Christensen et al.)The Harvard Binocular Head (N J Ferrier & J J Clark)Heads, Eyes, and Head-Eye Systems (K Pahlavan & J-O Eklundh)Design and Performance of TRISH, a Binocular Robot Head with Torsional Eye Movements (E Milios et al.)A Low-Cost Robot Camera Head (H I Christensen)The Surrey Attentive Robot Vision System (J R G Pretlove & G A Parker)Layered Control of a Binocular Camera Head (J L Crowley et al.)SAVIC: A Simulation, Visualization and Interactive Control Environment for Mobile Robots (C Chen & M M Trivedi)Simulation and Expectation in Sensor-Based Systems (Y Roth & R Jain)Active Avoidance: Escape and Dodging Behaviors for Reactive Control (R C Arkin et al.) Readership: Engineers and computer scientists. keywords:Active Vision;Robot Vision;Computer Vision;Model-Based Vision;Robot Navigation;Reactive Control;Robot Motion Planning;Knowledge-Based Vision;Robotics

This book includes a selection of research papers in robot control applications. The description of projects using robotic systems in areas such as vision, navigation, path planning, trajectories, non-holonomic systems, mobile robotics, robot control with very specific structures, as well as artificial intelligence systems is pointed out. It also presents several tools and mathematical concepts that allow the development and operation of robotic systems. Additionally, the development of different ideas in control systems that are useful and hopefully enriching for the reader are also presented in this book.

As technology continues to develop, certain innovations are beginning to cover a wide range of applications, specifically mobile robotic systems. The boundaries between the various automation methods and their implementations are not strictly defined, with overlaps occurring. Specificity is required regarding the research and development of android systems and how they pertain to modern science. Control and Signal Processing Applications for Mobile and Aerial Robotic Systems is a pivotal reference source that provides vital research on the current state of control and signal processing of portable robotic designs. While highlighting topics such as digital systems, control theory, and mathematical methods, this publication explores original inquiry contributions and the instrumentation of mechanical systems in the industrial and scientific fields. This book is ideally designed for technicians, engineers, industry specialists, researchers, academicians, and students seeking current research on today?s execution of mobile robotic schemes.

This book covers the most attractive problem in robot control, dealing with the direct interaction between a robot and a dynamic environment, including the human-robot physical interaction. It provides comprehensive theoretical and experimental coverage of interaction control problems, starting from the mathematical modeling of robots interacting with complex dynamic environments, and proceeding to various concepts for interaction control design and implementation algorithms at different control layers. Focusing on the learning principle, it also shows the application of new and advanced learning algorithms for robotic contact tasks.

This Research Topic presents bio-inspired and neurological insights for the development of intelligent robotic control algorithms. This aims to bridge the inter-disciplinary gaps between neuroscience and robotics to accelerate the pace of research and development.

The first book of the new, textbook series, entitled Applied Dynamics of Manipulation Robots: Modelling, Analysis and Examples, by M. Vukobratovic, published by Springer-Verlag (1989) was devoted to the problems of dynamic models and dynamic analysis of robots. The present book, the second in the series, is concerned with the problems of the robot control. In conceiving this textbook, several dillemas arouse. The main issue was the question on what should be incorporated in a textbook on such a complex subject. Namely, the robot control comprises a wide range of topics related to various aspects of robotics, starting from the syn thesis of the lowest, executive, control level, through the synthesis of trajectories (which is mainly related to kinematic models of robots) and various algorithms for solving the problem of task and robot moti on planning (including the solving of the problems by the methods of artificial intelligence) to the aspects of processing the data obtai ned from sensors. The robot control is closely related to the robot pro gramming (i. e. the development of highly-specialized programming lan guages for robot programming). Besides, numerous aspects of the con trol realization should be included here. It is obvious that all these aspects of control cannot be treated in detail in the frame of a text book.

Drones, RC cars, artificial limbs, Roombas-the robots have arrived! Anyone interested in taking control before the machines do needs a helpful resource. Author and physics teacher Bobby Mercer will show

readers 20 inexpensive, easy-to-build and robots that can be built with everyday items. The Robot Book will teach readers how to use recycled motors and computer components, junk drawer supplies, and old mechanical toys to build a variety of devices. They will learn how to turn a toothbrush, an old cell phone, and scrap wire into a Brush Bot, or hack a toy car to hotwire a Not-So-Remote Bot. A small electric fan, several craft sticks, and rubber bands make a Fan-Tastic Dancing Machine, and drinking straws, string, tape, and glue can be used to construct a working model of the human hand. Every hands-on project contains a materials list and detailed step-by-step instructions with photos. Mercer also includes explanations of the science and technology behind each robot, including concepts such as friction, weight and mass, center of gravity, kinetic and potential energy, electric circuitry, DC vs. AC current, and more. Teachers will appreciate the opportunity to augment their STEM curricula while having fun at the same time. These projects are also perfect for science fairs or design competitions. Bobby Mercer has been a high school physics teacher for over two decades. He is the author of The Flying Machine Book, The Racecar Book and Junk Drawer Physics and lives with his family outside of Asheville, North Carolina.

As intelligent autonomous agents and multiagent system applications become more pervasive, it becomes increasingly important to understand the risks associated with using these systems. Incorrect or inappropriate agent behavior can have harmful - fects, including financial cost, loss of data, and injury to humans or systems. For - ample, NASA has proposed missions where multiagent systems, working in space or on other planets, will need to do their own reasoning about safety issues that concern not only themselves but also that of their mission. Likewise, industry is interested in agent systems that can search for new supply opportunities and engage in (semi-) automated negotiations over new supply contracts. These systems should be able to securely negotiate such arrangements and decide which credentials can be requested and which credentials may be disclosed. Such systems may encounter environments that are only partially understood and where they must learn for themselves which aspects of their environment are safe and which are dangerous. Thus, security and safety are two central issues when developing and deploying such systems. We refer to a multiagent system s security as the ability of the system to deal with threats that are intentionally caused by other intelligent agents and/or s- tems, and the system s safety as its ability to deal with any other threats to its goals."

Introduction to Mobile Robot Control provides a complete and concise study of modeling, control, and navigation methods for wheeled non-holonomic and omnidirectional mobile robots and manipulators. The book begins with a study of mobile robot drives and corresponding kinematic and dynamic models, and discusses the sensors used in mobile robotics. It then examines a variety of model-based, model-free, and vision-based controllers with unified proof of their stabilization and tracking performance, also addressing the problems of path, motion, and task planning, along with localization and mapping topics. The book provides a host of experimental results, a conceptual overview of systemic and software mobile robot control architectures, and a tour of the use of wheeled mobile robots and manipulators in industry and society. Introduction to Mobile Robot Control is an essential reference, and is also a textbook suitable as a supplement for many university robotics courses. It is accessible to all and can be used as a reference for professionals and researchers in the mobile robotics field. Clearly and authoritatively presents mobile robot concepts Richly illustrated throughout with figures and examples Key concepts demonstrated with a host of experimental and simulation examples No prior knowledge of the subject is required; each chapter commences with an introduction and background

Presents the normal kinematic and dynamic equations for robots, including mobile robots, with coordinate transformations and various control strategies This fully updated edition examines the use of mobile robots for sensing objects of interest, and focus primarily on control, navigation, and remote sensing. It also includes an entirely new section on modeling and control of autonomous underwater vehicles (AUVs), which exhibits unique complex three-dimensional dynamics. Mobile Robots: Navigation, Control and Sensing, Surface Robots and AUVs, Second Edition starts with a chapter on kinematic models for mobile robots. It then offers a detailed chapter on robot control, examining several different configurations of mobile robots. Following sections look at robot attitude and navigation. The application of Kalman Filtering is covered. Readers are also provided with a section on remote sensing and sensors. Other chapters discuss: target tracking, including multiple targets with multiple sensors; obstacle mapping and its application to robot navigation; operating a robotic manipulator; and remote sensing via UAVs. The last two sections deal with the dynamics modeling of AUVs and control of AUVs. In addition, this text: Includes two new chapters dealing with control of underwater vehicles Covers control schemes including linearization and use of linear control design methods, Lyapunov stability theory, and more Addresses the problem of ground registration of detected objects of interest given their pixel coordinates in the sensor frame Analyzes geo-registration errors as a function of sensor precision and sensor pointing uncertainty Mobile Robots: Navigation, Control and Sensing, Surface Robots and AUVs is intended for use as a textbook for a graduate course of the same title and can also serve as a reference book for practicing engineers working in related areas.

This book presents recent advances in robot control theory on task space sensory feedback control of robot manipulators. By using sensory feedback information, the robot control systems are robust to various uncertainties in modelling and calibration errors of the sensors. Several sensory task space control methods that do not require exact knowledge of either kinematics or dynamics of robots, are presented. Some useful methods such as approximate Jacobian control, adaptive Jacobian control, region control and multiple task space regional feedback are included. These formulations and methods give robots a high degree of flexibility in dealing with unforeseen changes and uncertainties in its kinematics and dynamics, which is similar to human reaching movements and tool manipulation. It also leads to the solution of several long-standing problems and open issues in robot control, such as force control with constraint uncertainty, control of multi-fingered robot hand with uncertain contact points, singularity issue of Jacobian matrix, global task-space control, which are also presented in this book. The target audience for this book includes scientists, engineers and practitioners involved in the field of robot control theory.

* Details the PICmicro microcontroller * Covers designing the robot system, software development, and advanced programming * Explains microcontroller connections

Build simple yet amazing robotics projects using ESP8266 About This Book Get familiar with ESP8266 and its features. Build Wi-FI controlled robots using ESP8266 A project based book that will use the ESP8266 board and some of its popular variations to build robots. Who This Book Is For This book is targeted at enthusiasts who are interested in developing low-cost robotics projects using ESP8266. A basic knowledge of programming will be useful but everything you need to know is are covered in the book. What You Will Learn Build a basic robot with the original ESP8266, Arduino UNO, and a motor driver board. Make a Mini Round Robot with ESP8266 HUZZAH Modify your Mini Round Robot by integrating encoders with motors Use the Zumo chassis kit to build a line-following robot by connecting line sensors Control your Romi Robot with Wiimote Build a Mini Robot Rover chassis with a gripper and control it through Wi-Fi Make a robot that can take pictures In Detail The ESP8266 Wi-Fi module is a self-contained SOC with an integrated TCP/IP protocol stack and can give any microcontroller access to your Wi-Fi network. It has a powerful processing and storage capability and also supports application hosting and Wi-Fi networking. This book is all about robotics projects based on the original ESP8266 microcontroller board and some variants of ESP8266 boards. It starts by showing all the necessary things that you need to build your development environment with basic hardware and software components. The book uses the original ESP8266 board and some variants such as the Adafruit HUZZAH ESP8266 and the Adafruit Feather HUZZAH ESP8266 . You will learn how to use different type of chassis kits, motors, motor drivers, power supplies, distribution boards, sensors, and actuators to build robotics projects that can be controlled via Wi-Fi. In addition, you will learn how to use line sensors, the ArduiCam, Wii Remote, wheel encoders, and the Gripper kit to build more specialized robots. By the end of this book, you will have built a Wi-Fi control robot using ESP8266. Style and approach A project-based guide that will help you build exciting robotics using ESP8266.

Through expanded intelligence, the use of robotics has fundamentally transformed a variety of fields, including manufacturing, aerospace, medicine, social services, and agriculture. Continued research on robotic design is critical to solving various dynamic obstacles individuals, enterprises, and humanity at large face on a daily basis. Robotic Systems: Concepts, Methodologies, Tools, and Applications is a vital reference source that delves into the current issues, methodologies, and trends relating to advanced robotic technology in the modern world. Highlighting a range of topics such as mechatronics, cybernetics, and human-computer interaction, this multi-volume book is ideally designed for robotics engineers, mechanical engineers, robotics technicians, operators, software engineers, designers, programmers, industry professionals, researchers, students, academicians, and computer practitioners seeking current research on developing innovative ideas for intelligent and autonomous robotics systems.

This book presents in a systematic manner the advanced technologies used for various modern robot applications. By bringing fresh ideas, new concepts, novel methods and tools into robot control, robot vision, human robot interaction, teleoperation of robot and multiple robots system, we are to provide a state-of-the-art and comprehensive treatment of the advanced technologies for a wide range of robotic applications. Particularly, we focus on the topics of advanced control and obstacle avoidance techniques for robot to deal with unknown perturbations, of visual servoing techniques which enable robot to autonomously operate in a dynamic environment, and of advanced techniques involved in human robot interaction. The book is primarily intended for researchers and engineers in the robotic and control community. It can also serve as complementary reading for robotics at the both graduate and undergraduate levels.

In the last decades robots are expected to be of increasing intelligence to deal with a large range of tasks. Especially, robots are supposed to be able to learn manipulation skills from humans. To this end, a number of learning algorithms and techniques have been developed and successfully implemented for various robotic tasks. Among these methods, learning from demonstrations (LfD) enables robots to effectively and efficiently acquire skills by learning from human demonstrators, such that a robot can be quickly programmed to perform a new task. This book introduces recent results on the development of advanced LfD-based learning and control approaches to improve the robot dexterous manipulation. First, there's an introduction to the simulation tools and robot platforms used in the authors' research. In order to enable a robot learning of human-like adaptive skills, the book explains how to transfer a human user’s arm variable stiffness to the robot, based on the online estimation from the muscle electromyography (EMG). Next, the motion and impedance profiles can be both modelled by dynamical movement primitives such that both of them can be planned and generalized for new tasks. Furthermore, the book introduces how to learn the correlation between signals collected from demonstration, i.e., motion trajectory, stiffness profile estimated from EMG and interaction force, using statistical models such as hidden semi-Markov model and Gaussian Mixture Regression. Several widely used human-robot interaction interfaces (such as motion capture-based teleoperation) are presented, which allow a human user to interact with a robot and transfer movements to it in both simulation and real-word environments. Finally, improved performance of robot manipulation resulted from neural network enhanced control strategies is presented. A large number of examples of simulation and experiments of daily life tasks are included in this book to facilitate better understanding of the readers.

This book focuses on two challenges posed in robot control by the increasing adoption of robots in the everyday human environment: uncertainty and networked communication. Part I of the book describes learning control to address environmental uncertainty. Part II discusses state estimation, active sensing, and complex scenario perception to tackle sensing uncertainty. Part III completes the book with control of networked robots and multi-robot teams. Each chapter features in-depth technical coverage and case studies highlighting the applicability of the techniques, with real robots or in simulation. Platforms include mobile ground, aerial, and underwater robots, as well as humanoid robots and robot arms. Source code and experimental data are available at http://extras.springer.com. The text gathers contributions from academic and industry experts, and offers a valuable resource for researchers or graduate students in robot control and perception. It also benefits researchers in related areas, such as computer vision, nonlinear and learning control, and multi-agent systems.

"This textbook offers an overview of techniques stemming from machine learning to train robots to adapt to changes in their environment"--

The book includes topics, such as: path planning, avoiding obstacles, following the path, go-to-goal control, localization, and visual-based motion control. The theoretical concepts are illustrated with a developed control architecture with soft computing and artificial intelligence methods. The proposed vision-based motion control strategy involves three stages. The first stage consists of the overhead camera calibration and the configuration of the working environment. The second stage consists of a path planning strategy using several traditional path planning algorithms and proposed planning algorithm. The third stage consists of the path tracking process using previously developed Gauss and Decision Tree control approaches and the proposed Type-1 and Type-2 controllers. Two kinematic structures are utilized to acquire the input values of controllers. These are Triangle Shape-Based Controller Design, which was previously developed and Distance-Based Triangle Structure that is used for the first time in conducted experiments. Four different control algorithms, Type-1 fuzzy logic, Type-2 Fuzzy Logic, Decision Tree Control, and Gaussian Control have been used in overall system design. The developed system includes several modules that simplify characterizing the motion control of the robot and ensure that it maintains a safe distance without colliding with any obstacles on the way to the target. The topics of the book are extremely relevant in many areas of research, as well as in education in courses in computer science, electrical and mechanical engineering and in mathematics at the graduate and undergraduate levels.

Controlling Robots using Blynk, Virtuino, Cayenne, Thingspeak, FirebaseKey features The book provides gradual pace of basics to advanced interfacing and programming with

Ti launch pad for IoT applications. It provides a unique style for IoT applications with program codes. It discusses various applications where the Internet of Things plays an important role, and considers a number of different independent prototypes for various mobile robotics platform control methods. The control of robot with different mobile apps like Blynk, Virtuino, Cayenne, Thingspeak, Firebase are included for vast coverage of scope. Step by step programming, to get started with Ti launch Pad Case studies to provide solution to real time problems The case studies and programming in book are tested on real hardware during handling the industrial and student projects. Description This book provides a platform to the readers, where they can understand the applications of 'Internet of Things' to control the robotic platform. It covers the basic knowledge of the mobile apps with their designing steps and programming. The objective of the book is to discuss various applications of robotic platform where 'Internet of things' can play an important role. This book comprises of total seventeen chapters for designing different independent prototypes for the various control methods. It covers introduction to IoT and basic components to design a robotic platform. The system demonstration is done with the help of Ti Launch Pad and other interfacing devices. The control of robot with different mobile apps like Blynk, Virtuino, Cayenne, Thingspeak, Firebase are included for vast coverage of scope.It would be beneficial for the people who want to get started with hardware based robotic prototypes with IoT. This book is entirely based on the practical experience of the authors while undergoing projects with the students and industries.What will you learn Interfacing of Ti launch Pad and NodeMCU with Input/Output Devices Serial Communication between Ti Launch Pad and NodeMCU Robot Control Using the Blynk, Virtuino App Environment Monitoring Robot with BLYNK App Sensory Data Acquisition Robot Using a ThingSpeak Server Robot Control with Cayenne App, Local Server and NodeMCU, Firebase Server Who this book is for Students pursuing BE/BSc/ME/MSc/BTech/MTech in Computer Science, Electronics, Electrical. Table of contents1. Introduction2. Components of a Robotic Platform3. Interfacing of Ti launch Pad with Input/Output Devices4. Interfacing of NodeMCU with Input/Output Devices5. Serial Communication between Ti Launch Pad and NodeMCU6. Robot Control Using the Blynk App7. Robot Control Using the Virtuino App8. Environment Monitoring Robot with BLYNK App9. Sensory Data Acquisition Robot Using a ThingSpeak Server 10. Robot Control with Cayenne App11. Robot Control with Local Server and NodeMCU12. Robot Control with a Firebase Server13. XBee and Wi-Fi Modem Based Robot Control14. Fire Fighting Robot15. The Internet of Things Robotic Arm16. The Smart Orchard with a Robotic Arm Sprinkler17. Smart Farming with the IoT About the authorDr. Anita Gehlot is currently associated with Lovely Professional University as Associate Professor with more than ten years of experience in academics. She has twenty patents in her account. She has published more than fifty research papers in referred journals and conference. She has organized a number of workshops, summer internships and expert lectures for students. She has been invited as session chair keynote speaker to international/national conferences and faculty development program. Dr. Rajesh Singh is currently associated with Lovely Professional University as Professor with more than fifteen years of experience in academics. He has been awarded as gold medalist in M.Tech and honors in his B.E. His area of expertise includes embedded systems, robotics, wireless sensor networks and Internet of Things. He has organized and conducted a number of workshops, summer internships and expert lectures for students as well as faculty. He has twenty-three patents in his account. He has published around hundred research papers in referred journals/conferences. His LinkedIn Profile: linkedin.com/in/dr-rajesh-singh-6380845aHis Website: orcid.org/0000-0002-3164-8905 Dr. Lovi Raj Gupta is the Executive Dean, Faculty of Technology & Sciences, Lovely Professional University. He is a leading light in the field of Technical and Higher education in the country. His research-focused approach and an insightful innovative intervention of technology in education have won him much accolades and laurels.In 2001, he was appointed as Assistant Controller (Technology), Ministry of IT, Govt. of India by the Honorable President of India in the Office of the Controller of Certifying Authorities (CCA). In 2013, he was accorded the role in the National Advisory Board for What Can I Give Mission - Kalam Foundation of Dr. APJ Abdul Kalam. In 2011, he received the MIT Technology Review Grand Challenge Award followed by the coveted Infosys InfyMakers Award in the year 2016. He has ten patents to his account. His LinkedIn Profile: linkedin.com/in/loviraj Bhupendra Singh is Managing Director of Schematics Microelectronics and provides Product design and R&D support to industries and Universities. He has completed BCA, PGDCA, M.Sc. (CS), M.Tech and has more than eleven years of experience in the field of Computer Networking and Embedded systems. He has published twelve books in the area of Embedded Systems and Internet of Things. His Blog: schematicslab.blogspot.in/ His LinkedIn Profile: linkedin.com/in/bhupisir

A study of the latest research results in the theory of robot control, structured so as to echo the gradual development of robot control over the last fifteen years. In three major parts, the editors deal with the modelling and control of rigid and flexible robot manipulators and mobile robots. Most of the results on rigid robot manipulators in part I are now well established, while for flexible manipulators in part II, some problems still remain unresolved. Part III deals with the control of mobile robots, a challenging area for future research. The whole is rounded off with an appendix reviewing basic definitions and the mathematical background for control theory. The particular combination of topics makes this an invaluable source of information for both graduate students and researchers.

There has been great interest in "universal controllers" that mimic the functions of human processes to learn about the systems they are controlling on-line so that performance improves automatically. Neural network controllers are derived for robot manipulators in a variety of applications including position control, force control, link flexibility stabilization and the management of high-frequency joint and motor dynamics. The first chapter provides a background on neural networks and the second on dynamical systems and control. Chapter three introduces the robot control problem and standard techniques such as torque, adaptive and robust control. Subsequent chapters give design techniques and Stability Proofs For NN Controllers For Robot Arms, Practical Robotic systems with high frequency vibratory modes, force control and a general class of non-linear systems. The

last chapters are devoted to discrete- time NN controllers. Throughout the text, worked examples are provided.

This volume surveys three decades of modern robot control theory and describes how the work of Suguru Arimoto shaped its development. Twelve survey articles written by experts associated with Suguru Arimoto at various stages in his career treat the subject comprehensively. This book provides an important reference for graduate students and researchers, as well as for mathematicians, engineers and scientists whose work involves robot control theory.

This book focuses on the development and methodologies of trajectory control of differential-drive wheeled nonholonomic mobile robots. The methodologies are based on kinematic models (posture and configuration) and dynamic models, both subject to uncertainties and/or disturbances. The control designs are developed in rectangular coordinates obtained from the first-order sliding mode control in combination with the use of soft computing techniques, such as fuzzy logic and artificial neural networks. Control laws, as well as online learning and adaptation laws, are obtained using the stability analysis for both the developed kinematic and dynamic controllers, based on Lyapunov's stability theory. An extension to the formation control with multiple differential-drive wheeled nonholonomic mobile robots in trajectory tracking tasks is also provided. Results of simulations and experiments are presented to verify the effectiveness of the proposed control strategies for trajectory tracking situations, considering the parameters of an industrial and a research differential-drive wheeled nonholonomic mobile robot, the PowerBot. Supplementary materials such as source codes and scripts for simulation and visualization of results are made available with the book.

The author has maintained two open-source MATLAB Toolboxes for more than 10 years: one for robotics and one for vision. The key strength of the Toolboxes provide a set of tools that allow the user to work with real problems, not trivial examples. For the student the book makes the algorithms accessible, the Toolbox code can be read to gain understanding, and the examples illustrate how it can be used —instant gratification in just a couple of lines of MATLAB code. The code can also be the starting point for new work, for researchers or students, by writing programs based on Toolbox functions, or modifying the Toolbox code itself. The purpose of this book is to expand on the tutorial material provided with the toolboxes, add many more examples, and to weave this into a narrative that covers robotics and computer vision separately and together. The author shows how complex problems can be decomposed and solved using just a few simple lines of code, and hopefully to inspire up and coming researchers. The topics covered are guided by the real problems observed over many years as a practitioner of both robotics and computer vision. It is written in a light but informative style, it is easy to read and absorb, and includes a lot of Matlab examples and figures. The book is a real walk through the fundamentals of robot kinematics, dynamics and joint level control, then camera models, image processing, feature extraction and epipolar geometry, and bring it all together in a visual servo system. Additional material is provided at http://www.petercorke.com/RVC

Bringing together the latest findings from computer science, mathematics and automatic control, this book examines in depth the theoretical and applied problems related to the control of rigid manipulators. Redundancy, the use of sensors, robustness, and stability analysis are covered in this new unified and coherent approach. Basic mathematical tools are established and a way of properly expressing a user's goal in terms of robot tasks is proposed.

This book presents solutions to control problems in a number of robotic systems and provides a wealth of worked-out examples with full analytical and numerical details, graphically illustrated to aid in reader comprehension. It also presents relevant studies on and applications of robotic system control approaches, as well as the latest findings from interdisciplinary theoretical studies. Featuring chapters on advanced control (fuzzy, neural, backstepping, sliding mode, adaptive, predictive, diagnosis, and fault-tolerant control), the book will equip readers to easily tailor the techniques to their own applications. Accordingly, it offers a valuable resource for researchers, engineers, and students in the field of robotic systems.