

Sliding Mode Control of an Internet Teleoperated PUMA 600 Robot

Authors : Abdallah Ghoul, Bachir Ouamri, Ismail Khalil Bousserhane

Abstract : In this paper, we have developed a sliding mode controller for PUMA 600 manipulator robot, to control the remote robot a teleoperation system was developed. This system includes two sites, local and remote. The sliding mode controller is installed at the remote site. The client asks for a position through an interface and receives the real positions after running of the task by the remote robot. Both sites are interconnected via the Internet. In order to verify the effectiveness of the sliding mode controller, that is compared with a classic PID controller. The developed approach is tested on a virtual robot. The results confirmed the high performance of this approach.

Keywords : internet, manipulator robot, PID controller, remote control, sliding mode, teleoperation

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