
Contents

1	Outline of Mechatronic Servo Systems	1
1.1	Emergence of Mechatronic Servo Systems.....	1
1.1.1	Control Pattern of Mechatronic Servo Systems	1
1.1.2	Characteristic of Servo System Applications	3
1.2	Issues in Mechatronic Servo Systems	7
1.2.1	Discussion on Modeling of a Mechatronic Servo System	7
1.2.2	Discussion on the Performance of One Axis in a Mechatronic Servo System	9
1.2.3	Discussion on the Performance of a Multi-Axis Mechatronic Servo System	12
1.2.4	Discussion on the Command of Mechatronic Servo Systems	14
2	Mathematical Model Construction of a Mechatronic Servo System	17
2.1	4th Order Model of One Axis in a Mechatronic Servo System .	17
2.1.1	Mechatronic Servo Systems	18
2.1.2	Mathematical Model Derivation of a Mechatronic Servo System	20
2.1.3	Determination Method of Servo Parameters Using a Mathematical Model	23
2.1.4	Experiment Verification of the Mathematical Model ..	27
2.2	Reduced Order Model of One Axis in a Mechatronic Servo System	29
2.2.1	Necessary Conditions of the Reduced Order Model ..	29
2.2.2	Structure Standard of Model	30
2.2.3	Derivation of Low Speed 1st Order Model	31
2.2.4	Derivation of the Middle Speed 2nd Order Model	32
2.2.5	Evaluation of the Low Speed 1st Order Model and the Middle Speed 2nd Order Model	35

2.3	Linear Model of the Working Coordinates of an Articulated Robot Arm	37
2.3.1	A Working Linearized Model of an Articulated Robot Arm	37
2.3.2	Derivation of Adaptable Region of the Working Linearized Model	42
2.3.3	Adaptable Region of the Working Linearized Model and Experiment Verification	51
3	Discrete Time Interval of a Mechatronic Servo System	53
3.1	Sampling Time Interval	53
3.1.1	Conditions Required in the Mechatronic Servo System ..	54
3.1.2	Relation between Control Properties and Sampling Frequency	56
3.1.3	Sampling Frequency Required in the Sampling Control ..	57
3.1.4	Experimental Verification of the Sampling Frequency Determination Method	57
3.2	Relation between Reference Input Time Interval and Velocity Fluctuation	58
3.2.1	Mathematical Model of a Mechatronic Servo System Concerning Reference Input Time Interval	59
3.2.2	Industrial Field Strategy of the Velocity Fluctuation Generated in Reference Input Time Interval	61
3.2.3	Parameter Relation between the Steady-State Velocity Fluctuation and the Mechatronic Servo System	62
3.2.4	Experimental Verification of the Steady-State Velocity Fluctuation	64
3.2.5	Relation between Reference Input Time Interval and Transient Velocity Fluctuation	66
3.2.6	Experimental Verification of the Transient Velocity Fluctuation	67
3.3	Relationship between Reference Input Time Interval and Locus Irregularity	69
3.3.1	Locus Irregularity in the Reference Input Time Interval ..	69
3.3.2	Experimental Verification of the Locus Irregularity Generated in the Reference Input Time Interval	75
3.3.3	Application Value of the Theoretical Analysis Result ..	77
4	Quantization Error of a Mechatronic Servo System	79
4.1	Encoder Resolution	79
4.1.1	Encoder Resolution of the Software Servo System	80
4.1.2	A Mathematical Model and Resolution Judgement for Encoder Resolution	81
4.1.3	Experimental Verification of the Encoder Resolution Determination	84

4.2	Torque Resolution	86
4.2.1	Mathematical Model of the Mechatronic Servo System for Torque Resolution	86
4.2.2	Deterioration of Positioning Precision Due to Torque Quantization Error	88
4.2.3	Deterioration of Ramp Response Due to Torque Quantization Error	89
4.2.4	Derivation of Torque Resolution Determination	93
5	Torque Saturation of a Mechatronic Servo System	97
5.1	Measurement Method for the Torque Saturation Property	97
5.1.1	Torque Saturation of a Mechatronic Servo System	98
5.1.2	Measurement of the Torque Saturation Curve and Experimental Verification	104
5.2	Contour Control Method with Avoidance of Torque Saturation	107
5.2.1	Contour Control Performance with Torque Saturation and High-Precision Contour Control Method	108
5.2.2	Experimental Verification of Contour Control Considering Torque Saturation	114
6	The Modified Taught Data Method	121
6.1	Modified Taught Data Method Using a Mathematical Model ..	121
6.1.1	Derivation of the Modified Taught Data Method	122
6.1.2	Properties Analysis of the Modified Taught Data Method	129
6.1.3	Experimental Verification of the Modified Taught Data Method	133
6.2	Modified Taught Data Method Using a Gaussian Network ..	135
6.2.1	Derivation of Modified Taught Data Method Using a Gaussian Network	137
6.2.2	Experimental Verification for Modified Taught Data Method Using a Gaussian Network	142
6.3	A Modified Taught Data Method for a Flexible Mechanism ..	144
6.3.1	Derivation of Contour Control with Oscillation Restraint Using the Modified Taught Data Method	144
6.3.2	Experimental Verification of Oscillation Restraint Control Using the Modified Taught Data Method	146
7	Master-Slave Synchronous Positioning Control	149
7.1	The Master-Slave Synchronous Positioning Control Method ..	149
7.1.1	Necessity of Master-Slave Synchronous Positioning Control	150
7.1.2	Derivation and Property Analysis of the Master-Slave Synchronous Positioning Control Method	151

7.1.3 Experimental Test of the Master-Slave Synchronous Positioning Control Method	153
7.2 Contour Control with Master-Slave Synchronous Positioning ..	160
7.2.1 Derivation of the Contour Control Method with Master-Slave Synchronous Positioning.....	161
7.2.2 Property Analysis and Evaluation of the Contour Control Method with Master-Slave Synchronous Positioning	163
7.2.3 Experimental Test of the Contour Control Method of Master-Slave Synchronous Positioning.....	166
Glossary	169
Nomenclature	173
Experimental Equipments	179
E.1 DEC-1	179
E.2 Motoman	180
E.3 Performer MK3S	181
E.4 XY Table	181
Appendix	185
A.1 Laplace Transform and Inverse Laplace Transform	185
A.2 Transition Response	186
A.3 Pole Assignment Regulator	187
A.4 Minimal Order Observer	188
References	189
Index	193