

# Contents

<b>Acknowledgement</b>	<b>ix</b>
<b>Agraïments</b>	<b>xi</b>
<b>Abstract</b>	<b>xiii</b>
<b>Resum</b>	<b>xv</b>
<b>Resumen</b>	<b>xvii</b>
<b>List of Terms</b>	<b>xxxiii</b>
<b>1 Introduction</b>	<b>1</b>
Motivations . . . . .	2
Contributions and Manuscript Outline . . . . .	2
<b>2 State of the Art</b>	<b>7</b>
2.1 Multi-rate Estimation and Control . . . . .	7
2.1.1 Periodic Modelling . . . . .	8
2.1.2 Multi-rate Estimation based on Holds . . . . .	9
2.1.2.1 Dual-rate High Order Holds based on Primitive Functions . . . . .	11
2.1.2.2 Dual-rate Dynamic Model based Holds. . . . .	14
2.1.3 Multi-rate Control . . . . .	15
2.1.3.1 Multi-rate PID . . . . .	16
2.1.3.2 Multi-rate Linear Quadratic Regulator . . . . .	17
2.2 Nonlinear Optimal Control . . . . .	19
2.2.1 Receding Horizon Control . . . . .	20
2.2.2 Iterative Linear Quadratic Regulator . . . . .	21
2.2.3 Extended Rauch-Tung-Striebel Controller . . . . .	22
2.3 Visual Feedback Control . . . . .	26
2.3.1 Camera-robot Configurations . . . . .	26

2.3.2	Task Functions in Visual Feedback Control . . . . .	26
2.3.2.1	Camera Space Control . . . . .	27
2.3.2.2	Joints Space Control . . . . .	28
2.3.3	Features Selection . . . . .	28
2.3.3.1	Geometric Features . . . . .	29
2.3.3.2	Luminance/Photometric Features . . . . .	30
2.3.3.3	Moment Features . . . . .	30
2.3.4	The Interaction Matrix . . . . .	32
2.3.5	Visual Feedback Control Laws . . . . .	33
2.3.5.1	2D Visual Feedback Control . . . . .	33
2.3.5.2	3D Visual Feedback Control . . . . .	34
2.3.6	Problems in Visual Feedback Control . . . . .	35
2.3.6.1	Local Minima . . . . .	35
2.3.6.2	Singularity . . . . .	36
2.3.6.3	Feature Visibility . . . . .	36
2.3.7	Multi-rate Visual Feedback Control . . . . .	37
<b>3</b>	<b>Visual Feedback Control based on DR-HOHs</b>	<b>39</b>
3.1	Motivation . . . . .	39
3.2	Visual feedback wheeled robot control based on DR-HOHs . . . . .	40
3.3	Visual Feedback Robot Control based on DR-HOHs . . . . .	47
3.3.1	Results under Simulation . . . . .	49
3.3.2	Experimental Results . . . . .	51
3.4	Asyn. Dual-rate High Order Holds with Time Delay Compensation . . . . .	53
3.4.1	Concepts and Formulation . . . . .	54
3.4.2	Data Estimation from Vision Systems . . . . .	59
3.4.2.1	Simulated results . . . . .	59
3.4.2.2	Experimental results . . . . .	63
3.4.3	Visual Feedback Robot Control based on Asyn. DR-HOH-TDC . . . . .	66
3.5	Summary . . . . .	76
3.6	Discussion . . . . .	77
<b>4</b>	<b>Visual Feedback Control based on DR-NLHOHs</b>	<b>81</b>
4.1	Motivation . . . . .	81
4.2	Multi-rate Nonlinear Holds . . . . .	82
4.2.1	Methodology . . . . .	84
4.2.2	Example . . . . .	86
4.3	Visual Feedback Wheeled Robot Control based on DR-NLHOHs	89

4.4 Visual Feedback Robot Manipulator Control based on DR-NLHOHs . . . . .	94
4.4.1 Results . . . . .	97
4.5 Summary . . . . .	101
<b>5 VFC based on Reference Features Filtering Strategy</b>	<b>103</b>
5.1 Motivation . . . . .	103
5.2 Reference features filtering control strategy . . . . .	104
5.2.1 Kalman Filter (KF) . . . . .	105
5.2.2 Extended Kalman Filter/Smoother (EKFS) . . . . .	106
5.2.3 Visual Feedback Control . . . . .	107
5.3 Dual-rate reference filtering control strategy . . . . .	110
5.3.1 Dual-rate Kalman Filter (DR-KF) . . . . .	110
5.3.2 Dual-sampling Extended Kalman Filter/Smoother (DS-EKFS) . . . . .	111
5.3.3 Visual Feedback Control . . . . .	115
5.4 Analysis and results . . . . .	116
5.4.1 Simulation Results . . . . .	116
5.4.2 Experimental Results . . . . .	123
5.5 Summary . . . . .	135
<b>6 Conclusions and Perspectives</b>	<b>137</b>
6.1 Contributions . . . . .	137
6.1.1 Sensor latency issue . . . . .	137
6.1.2 On providing suitable trajectories issue . . . . .	138
6.2 Perspectives . . . . .	139
<b>A Experimental Platforms</b>	<b>141</b>
A.1 Real platforms . . . . .	144
A.1.1 Industrial Robotic Cells . . . . .	144
A.1.1.1 Robot KR5 sixx R650 . . . . .	144
A.1.1.2 Robot Agilus R900 sixx . . . . .	146
A.1.1.3 Supplementary Tools . . . . .	147
A.1.1.4 On Externally Control of Kuka Robots . . . . .	151
A.1.1.5 Software . . . . .	156
A.1.1.6 Applications Highlights . . . . .	156
A.1.2 SUMMIT Mobile Robot Platform . . . . .	160
A.2 Virtual platforms . . . . .	162
A.2.1 Industrial Robotic Cell Simulator . . . . .	162
A.2.2 SUMMIT Mobile Platform Simulator . . . . .	164
<b>References</b>	<b>167</b>