書名：Adaptive Control of Robot Manipulators
--- A Unified Regressor-Free Approach

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簡介：

This book introduces a unified function approximation approach to the control of uncertain robot manipulators containing general uncertainties. It works for free space tracking control as well as compliant motion control. It is applicable to the rigid robot and the flexible joint robot. Even with actuator dynamics, the unified approach is still feasible. All these features make the book stand out from other existing publications.

特色：

1. Introduces a regressor-free algorithm, which is a significant difference to other methods.
2. Uses a unified approach that is applicable to most of the robot adaptive control problems directly.
3. Adopts a control strategy that can tolerate time-varying uncertainties, which is infeasible for most of the traditional adaptive controllers.

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