

MOTION CONTROL METHOD AND SYSTEM FOR TROWELING ROBOT AND TROWELING ROBOT

ABSTRACT

5 Embodiments of the present application provide a motion control method and system for a
troweling robot and a troweling robot and relate to the field of robot control technologies. The
motion control method for a troweling robot includes: obtaining kinetics parameter information and
motor load rate information of the troweling robot; obtaining environmental information of a
position of the troweling robot; inputting the motor load rate information and the environmental
10 information into a preset neural network to obtain ground environment parameter information;
inputting the kinetics parameter information and the ground environment parameter information
into a model predictive controller to obtain inclination adjustment information; and controlling a
troweling plate mechanism of the troweling robot based on the inclination adjustment information.
The motion control method for a troweling robot can achieve a technical effect of improving
15 precision and smoothness of motion control of the troweling robot.

FIG. 1 accompanies abstract.