

ABSTRACT

A nonlinear adaptive control method and system for mechanical arm motion control. The method comprises the steps of inputting the output of an incremental nonlinear inverse dynamics controller into a servo motor driver for driving a mechanical arm, and the like. A mechanical arm motion load model and an external disturbance model required by controller parameter tuning are not needed, so that the technical problems in the existing mechanical arm motion control technology of difficulty in motion load model identification and controller time-varying parameter tuning are solved.

FIG. 1