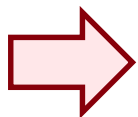


NOLWENN BRIQUET-KERESTEDJIAN

ADAPTIVE STRATEGIES FOR IMPACT DETECTION

- 2nd-year PhD student
- French nationality



Serial robot manipulator



Impact detection
Operator / Environment

- Without force/torque sensor
- In presence of modeling uncertainties

- I. Quantification of the detection sensitivity**
- II. Determination of impact intention
- III. Adaptation of the control laws