

Publications for Patrik Axelsson

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PhD Thesis

Patrik Axelsson. *Sensor Fusion and Control Applied to Industrial Manipulators*. Linköping Studies in Science and Technology. Dissertations No. 1585, Linköping University, SE-581 83 Linköping, Sweden, May 2014.

Licentiate's Thesis

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Journal Papers

André Carvalho Bittencourt and Patrik Axelsson. Modeling and experiment design for identification of wear in a robot joint under load and temperature uncertainties based on friction data. *IEEE/ASME Transactions on Mechatronics*, 19(5):1694–1706, October 2014.
DOI: 10.1109/TMECH.2013.2293001.

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Conference Papers

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Patrik Axelsson, Goele Pipeleers, Anders Helmersson, and Mikael Norrlöf. H-infinity synthesis method for control of non-linear flexible joint models. In *Proceedings of the 19th IFAC World Congress*, Cape Town, South Africa, August 2014. Accepted for publication.

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Patrik Axelsson, Umut Orguner, Fredrik Gustafsson, and Mikael Norrlöf. ML estimation of process noise variance in dynamic systems. In *Proceedings of the 18th IFAC World Congress*, pages 5609–5614, Milano, Italy, August/September 2011.

André Carvalho Bittencourt, Patrik Axelsson, Ylva Jung, and Torgny Brogårdh. Modeling and identification of wear in a robot joint under temperature uncertainties. In *Proceedings of the 18th IFAC World Congress*, pages 10293–10299, Milano, Italy, August/September 2011.

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Patrik Axelsson, Daniel Axehill, Torkel Glad, and Mikael Norrlöf. Iterative learning control – from a controllability point of view. In *Proceedings of Reglermötet*, Linköping, Sweden, June 2014.

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