

# **Modeling, Analysis and Control of a Class of Elastically Joints-actuated Multibody Systems**

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# TIPS TO BE CONVERGED

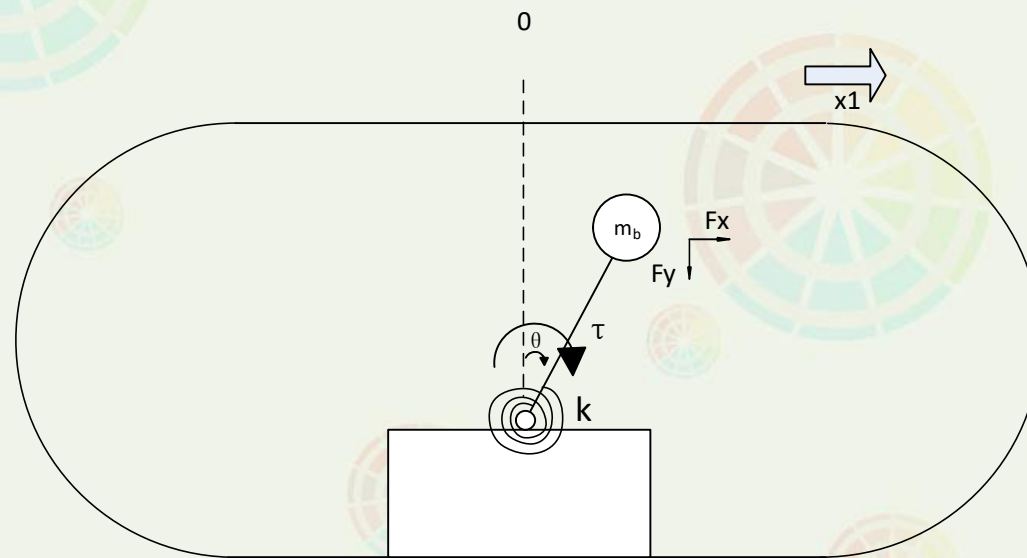
- **INTRODUCTION**
- **CASE STUDY**
- **APPLICATIONS**
- **CHALLENGES**
- **FUTURE WORKS**
- **REFERENCE**

# INTRODUCTION

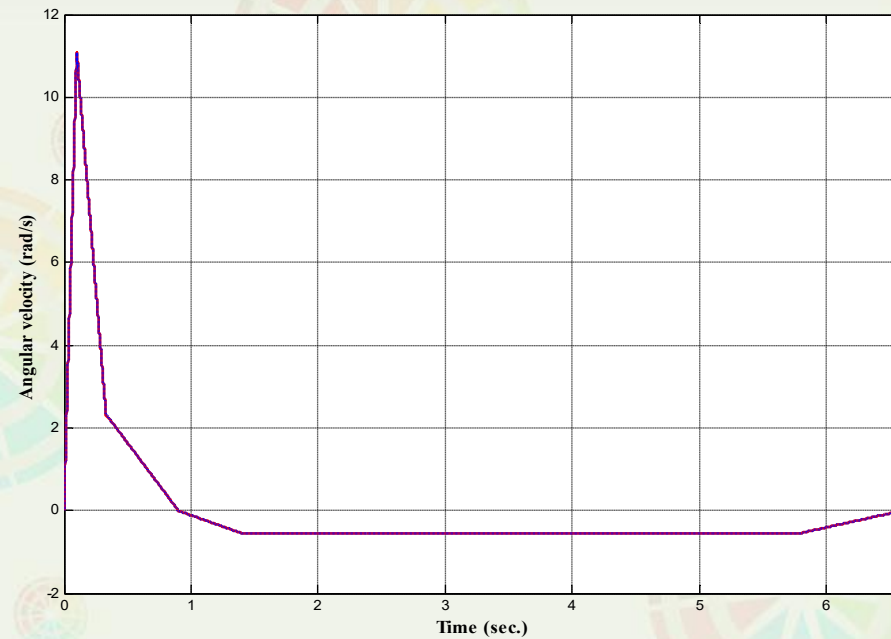
- **Ideals**
  - Software control
  - Rigid transmissions  
& minimizing compliance
- **Reality**
  - Impacts
  - Kinetic energy transfer

# CASE STUDY

- Elastically joint-actuated cart-pole system

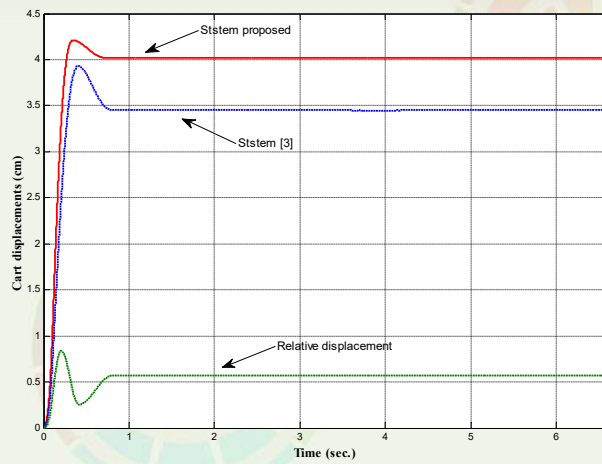


Elastically joint-actuated cart-pole system

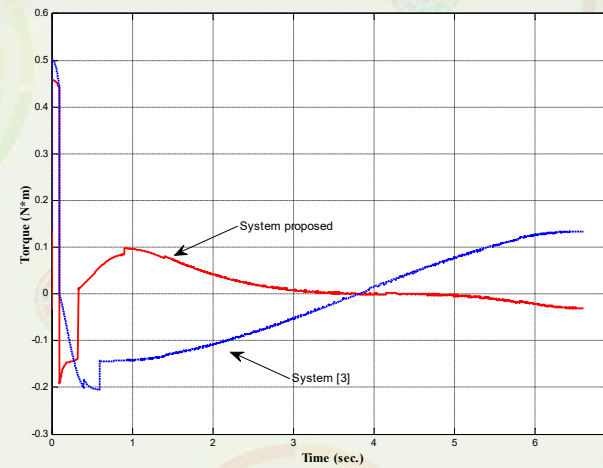


Optimized angular velocity profile for one fully stroke

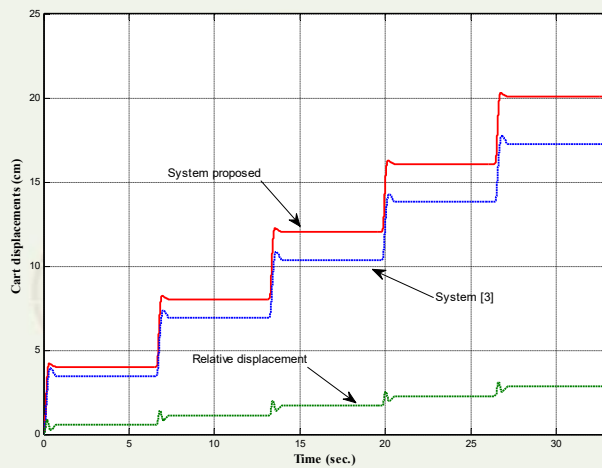
$$\dot{\theta}_d(t) = \begin{cases} 110.669t & 0 \leq t < 0.1 \\ 11.0669 - 37.97(t - 0.1) & 0.1 \leq t < 0.33 \\ -4.094(t - 0.9) & 0.33 \leq t < 0.9 \\ -0.10928(t - 0.9) & 0.9 \leq t < 1.4 \\ -0.5464 & 1.4 \leq t < 5.8 \\ 0.683(t - 6.6) & 5.8 \leq t < 6.6 \end{cases}$$



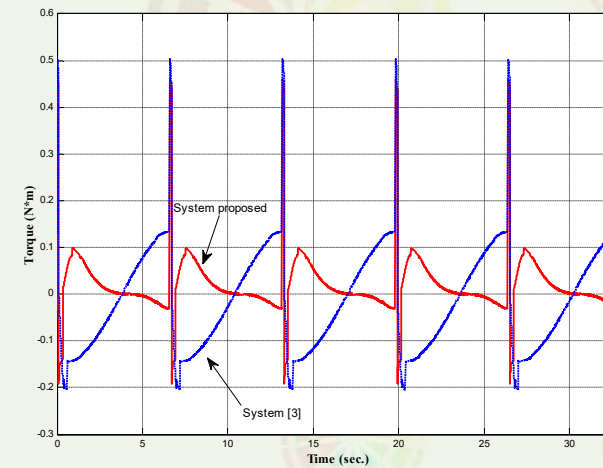
(a)



(b)

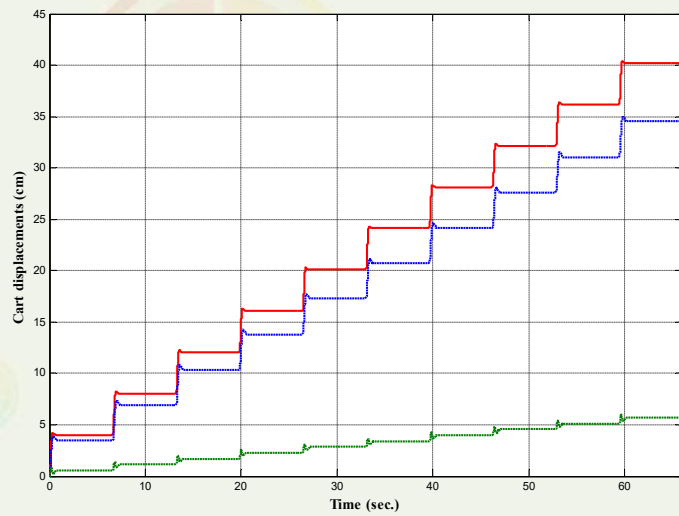


(c)

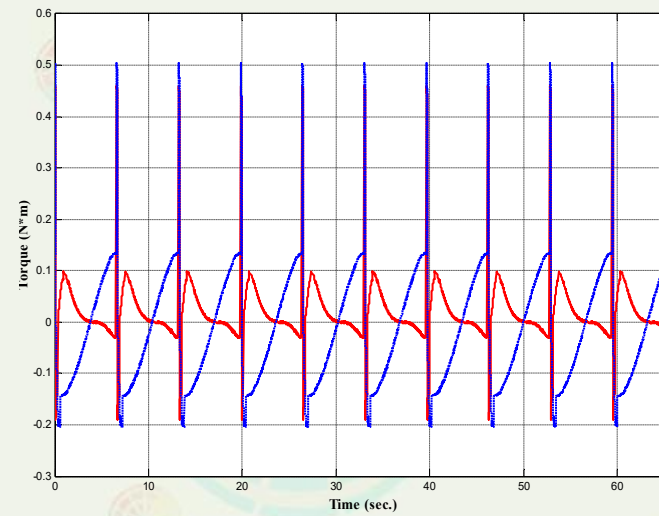


(d)

Comparisons of trajectories of cart displacement and control input for one and five cycles respectively under Collocated PFL technique



(a)



(b)

Comparison of trajectories of cart displacement and control input for ten cycles under Collocated PFL technique

# APPLICATIONS

- Legged robot systems
- Manipulators
- Rescue robots
- Medical rehabilitation devices
- Haptic devices

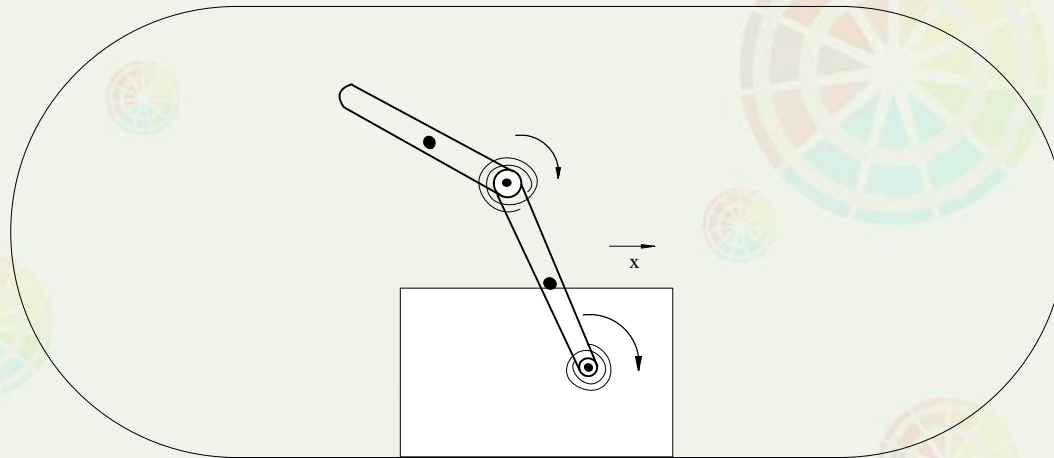


# CHALLENGES

- Controller design (highly nonlinear and strong coupling)
- Synchronization of motion cycles between different bodies
- Optimization of the parametric selection
- Nonintegrability of the system dynamics
- Characterization of second-order nonholonomic constraints

# FUTURE WORKS

- Elastically Integrated Joints-Actuated Cart-Pole Underactuated System



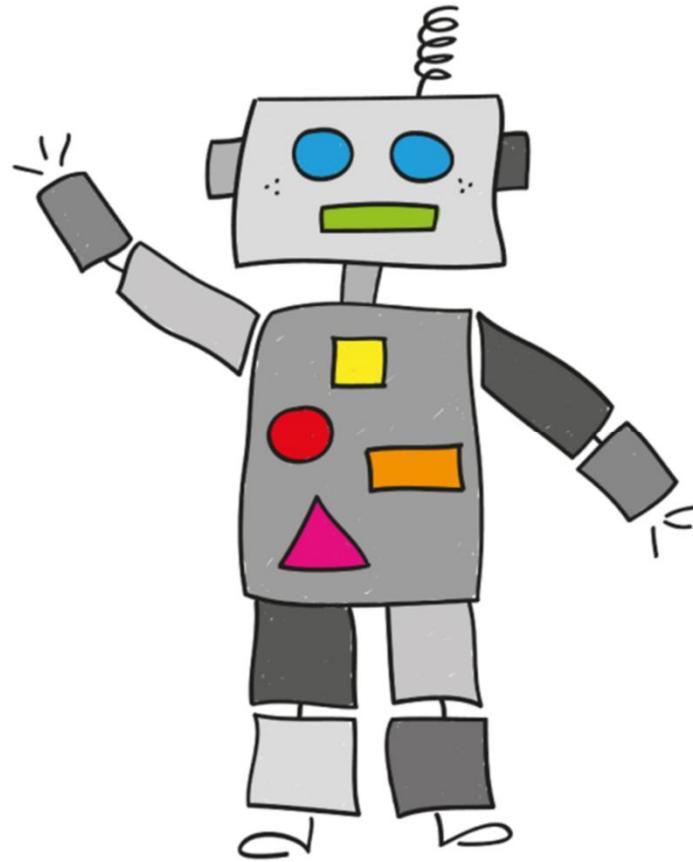
Elastically integrated Joints-Actuated Cart-Pole Underactuated System

# REFERENCE

- [1] P. Liu, H. Yu, and S. Cang, “Modelling and control of an elastically joint-actuated cart-pole underactuated system,” the 2014 IEEE International Conference on Automation and Computing, 2014, pp. 26–31.
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# QUESTIONS?

# THANK YOU!



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