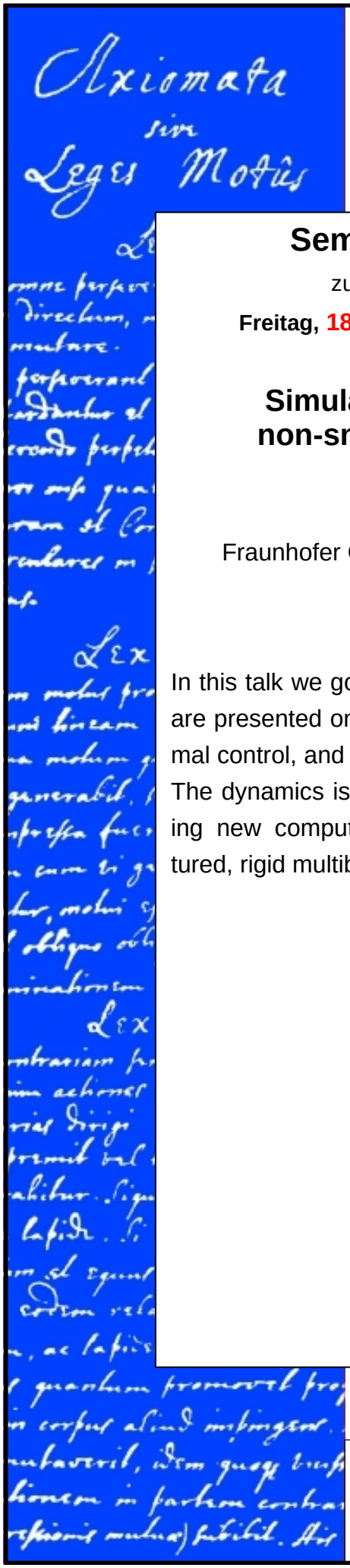

Seminar über Fragen der Mechanik

zu folgendem Vortrag wird herzlich eingeladen

Freitag, 18.03.2016, 10:30 Uhr, Haberstraße 1, Raum 01.025

Simulation of a balancing humanoid with non-smooth contact and feedback control

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Fraunhofer Chalmers Research Centre Industrial Mathematics, Robotics, Optimization, Control Theory

In this talk we go through an example of a balancing humanoid. Details are presented on design of feedback control using linear quadratic optimal control, and simulation with inelastic collisions and Coulomb friction. The dynamics is modeled using discrete mechanics, and simulated using new computationally efficient recursive algorithms for tree structured, rigid multibody systems.

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