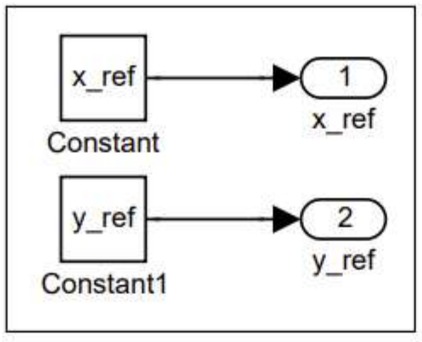
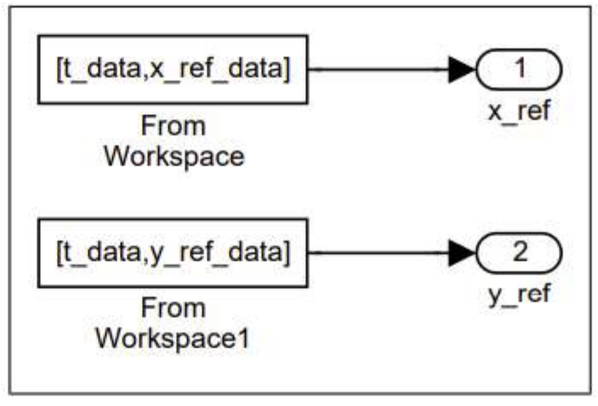
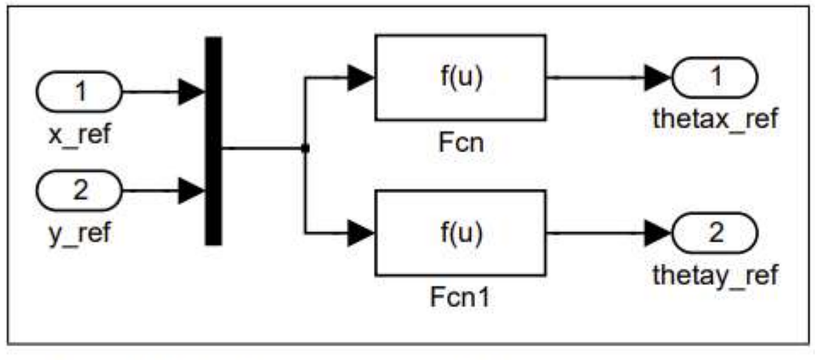


(a1) Subsystem “Command” の内容
(‘sim_robot_xy.slx”, “ex_robot_xy.slx”)

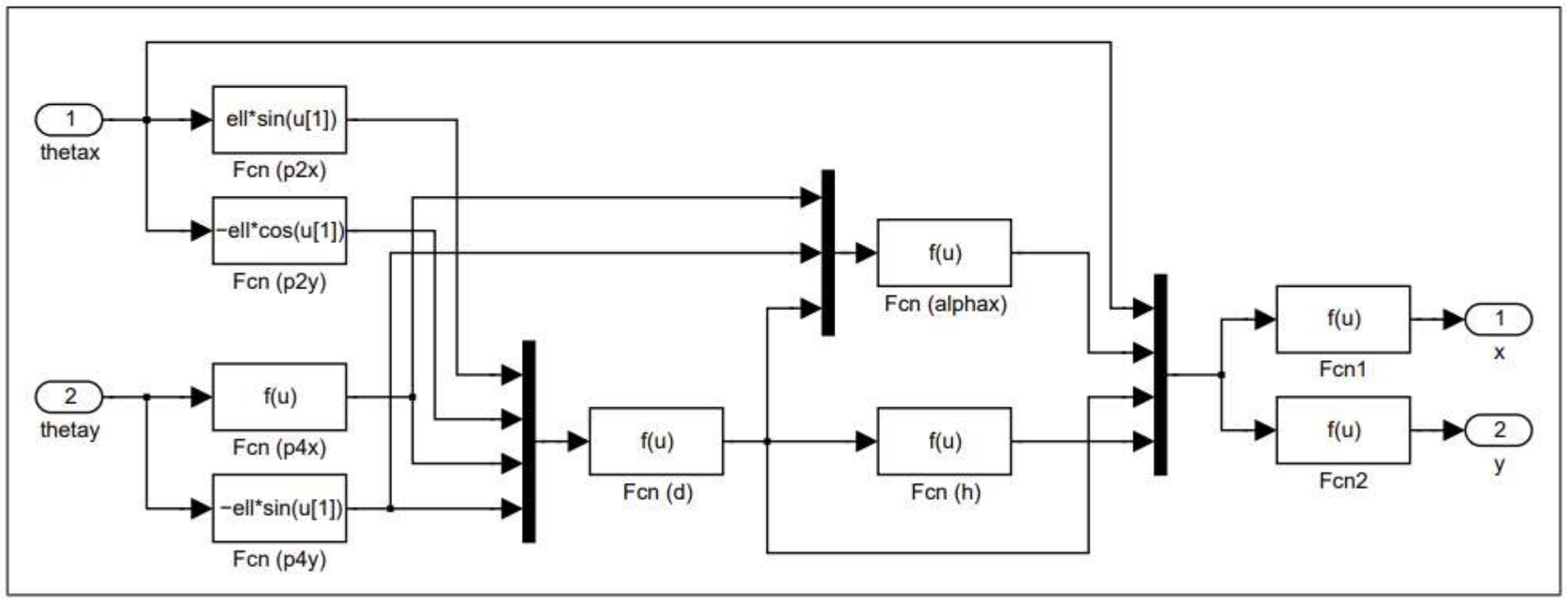


(a2) Subsystem “Command” の内容
(“sim_robot_xy2.slx”, “ex_robot_xy2.slx”)



(Fcn : Expression を “asin(sqrt(u[1]^2+u[2]^2)/(2*ell)) + atan(u[2]/u[1])” に変更
Fcn1 : Expression を “asin(sqrt((u[1]-2*ell)^2+u[2]^2)/(2*ell)) - atan((u[1]-2*ell)/u[2])” に変更)

(b) Subsystem “Inverse” の内容



(Fcn (p2x) : Expression を “ell*sin(u[1])” に変更
Fcn (p2y) : Expression を “-ell*cos(u[1])” に変更
Fcn (p4x) : Expression を “2*ell-ell*cos(u[1])” に変更
Fcn (p4y) : Expression を “-ell*sin(u[1])” に変更
Fcn (alphax) : Expression を “acos((ell^2 + u[3]^2 - (u[1]^2 + u[2]^2))/(2*ell*u[3]))” に変更
Fcn (d) : Expression を “sqrt((u[1]-u[3])^2+(u[2]-u[4])^2)” に変更
Fcn (h) : Expression を “sqrt(ell^2 - (u[1]/2)^2)” に変更
Fcn1 : Expression を “u[4]*cos(u[1]-u[2])-(u[3]/2)*sin(u[1]-u[2])+ell*sin(u[1])” に変更
Fcn2 : Expression を “u[4]*sin(u[1]-u[2])+(u[3]/2)*cos(u[1]-u[2])-ell*cos(u[1])” に変更)

(c) Subsystem “Forward” の内容