

ALDF

minim

transmission

ROS

upente.

→ Set actuator.

if R

do libere Pos.

$$f = k_s$$

~~SAD~~

~~AS~~ (2) 3

A[3]

SDF

Soft hand

Plugin

No Contact

$$q = E^{-1} K^T P S$$

$$q_{minic} = q_{minic}$$

readings → 200 BO

$q(2)$ pos, vel, eff

PD

$$q_{pos} - q = q_{eq}$$

write eff (cor)

$$q = E^{-1} R^T \cdot f$$

Transmission