

**Department of Engineering Cybernetics,   
Automation Technology Programme**

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| **Course: TELE3001 Bachelor Thesis** | | | | | | **Date:** 24.01.2019 |
| **Project:** Instrumentation of bipedal robotprototype | | | | | | |
| **Activity:** Joint control | | | | | | **Activity nr:06** |
| **Starting date:** 04.02.2019 | | | **End date:** 08.03.2019 | | | |
| **Dependency:** Finish project description | **Past Activities:** | | Finish project description | | | |
| **Following**  **Activities:** | | Actuator slack  IMU calculation | | | |
| **Goal:** Find upper/lower joint limits and voltage/PWM-frequency to reach limits | | | | | | |
| **Description:** Wire signal connections from joints through motor control units to the DS1005 dSpace hardware. Use dSpace to measure joint limits and test actuator linearity. | | | | | | |
| **Total Workload:** 220 hours | | | **Work distribution:**  Jakob  Kristoffer | 110 hours  110 hours | | |
| **Expenses:** | | | | | | |
| **Resources:** | | | | | | |
| **Hazards:**  Motor torque, Voltage | | | | | | |
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