

**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:** Actuator slack | | | | | | **Activity nr:09** |
| **Starting date:** 23.04.2019 | | | **End date:** 23.05.2019 | | | |
| **Dependency:**  Joint control | **Past Activities:** | | IMU calculation  Microcontroller | | | |
| **Following**  **Activities:** | |  | | | |
| **Goal:** Eliminate actuator slack impact | | | | | | |
| **Description:** Measure actuator angles with encoder while switching torque direction on the actuators. Decide if measurement errors while switching are considerable. If the slack has a meaningful impact, find a way to compensate for it. | | | | | | |
| **Total Workload:** 100 hours | | | **Work distribution:**  Kristoffer  Jakob  Henrik  Jonas  Endre | 20 hours  20 hours  20 hours  20 hours  20 hours | | |
| **Expenses:** | | | | | | |
| **Resources:** | | | | | | |
| **Hazards:**  Motor torque,Voltage | | | | | | |
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