Title ~~Communication D. D. A MPRL~~ MPRL ~~Dynamic Difficulty~~ DDA Date / Time 24/7/~~8~~ 9 Page No.

Dynamic Difficulty Adjustment

where?

(inertia dissipation

LabVIEW → (roll, pitch, yaw) → Blender

LabVIEW ⇄ Motors (Voltage ↓, encoder val. ↑)

~~difficulty definition~~

measured by heuristic fun others

(performance. difficulty

~~Difficulty = f(m, G, ...)~~

Best task performance.

~~completion time: ex) 15 sec slow out of shortest path~~

completion time / expected time (shortest path)
goal time.

ex) 80 out of 100

80/100

healthy participant average force

RT DDA by RL

~~DDA RT RL with RL~~

Score = state

|W-L| < ε

W or L rate

50:50

Work

given time. X

game properties

~~6 para~~ 6 dissipation parameter

① range of motion

② Coordination

③ motion control

① |W-L| < ε

② |r_i - r_{i+1}| < ε

③ Σ [r_{i+1} - r_i > 0]

50:50 progress

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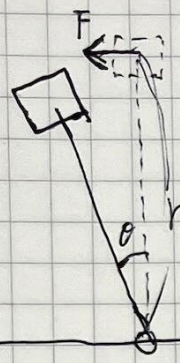


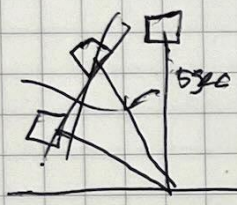
$I\ddot{\theta} + c\dot{\theta} = \tau$

$\omega = \dot{\theta} = \frac{\tau}{c} - K e^{-\frac{c}{I}t}$

$\theta = \int \omega dt + \theta$

target : rpy

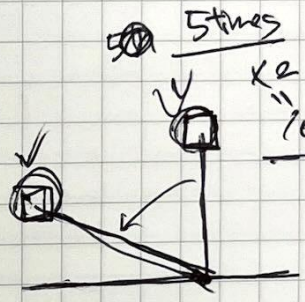
1 round



10 target posture

turn Lose rate... given the

move in 5sec



negative the

55 → -15...

$J_1 g_1 + J_2 g_2 + J_3 g_3$

X 1.1 X 0.9

increase decrease.