

Compliance Control

- **Using non-complementary switching mode**

- Torque command only adds joint torque in the applied direction
- No need to compensate for Back-EMF
- Increases backdrivability of joints

- **Compliance control scheme**

- Ignoring inertial force and Coriolis force terms
- Gravity and friction is compensated in joint space
- X_{des} : desired motion
- f_{des} : desired force
- Γ_{null} : null space joint torque

