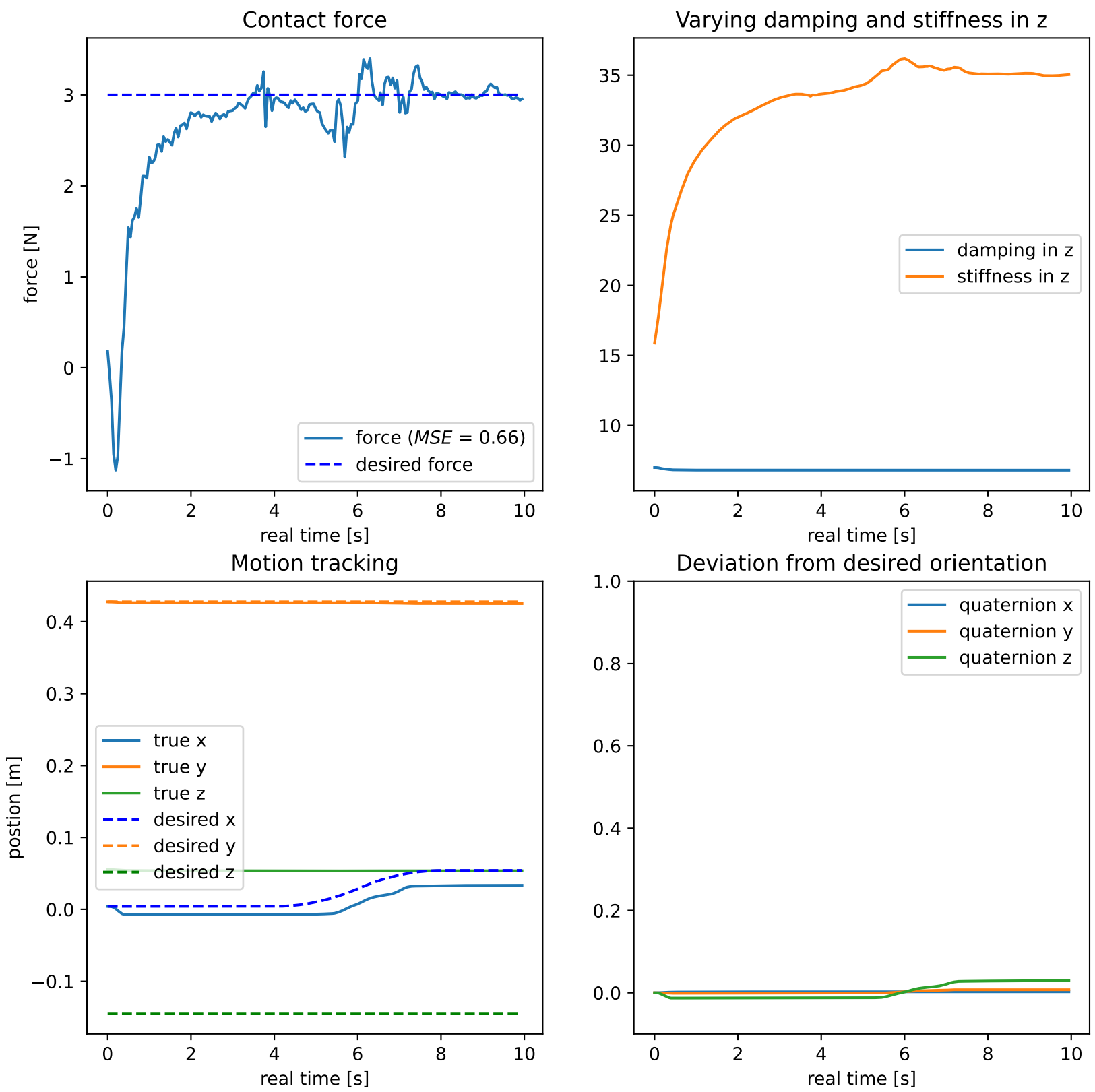
Performance of Force-based VIC (experiment)
Contact force
force [N]
real time [s]
force (MSE = 0.66)
desired force
Varying damping and stiffness in z
real time [s]
damping in z
stiffness in z
Motion tracking
postion [m]
real time [s]
true x
true y
true z
desired x
desired y
desired z
Deviation from desired orientation
real time [s]
quaternion x
quaternion y
quaternion z