

Master's thesis

Simulation of complex actuators

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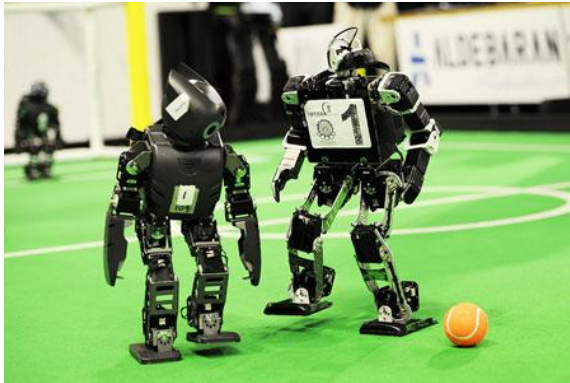
Univerity of Liège

Academic year 2015-2016

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Context & Motivation



Subject of work

Required features:

- realistic physics simulation
- ability to control the simulation from outside
- the model of the robot should receive instructions at a relatively high frequency and be able to interpret the same instructions that the real robot will

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Choices

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Modelling

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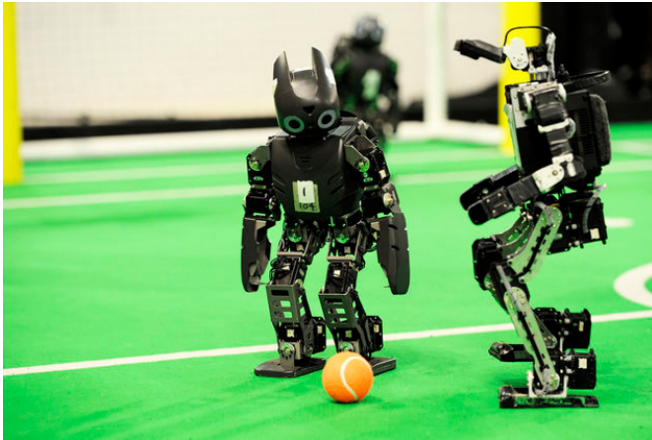
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Simulation modus operandi

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Applications (1/2)



Applications (2/2)

