

# Master's thesis

## Simulation of complex actuators

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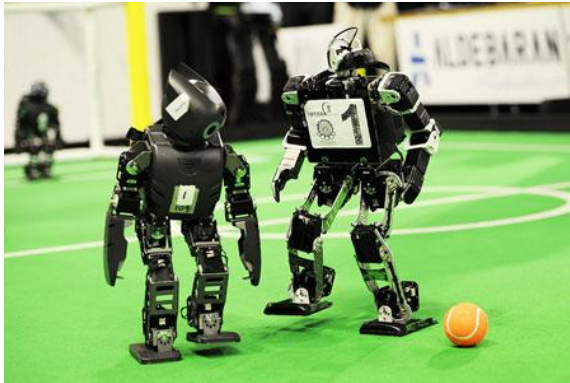
Univerity of Liège

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# Context & Motivation



# Subject of work

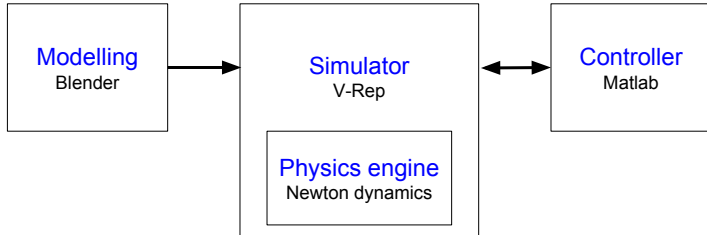
Required features:

- 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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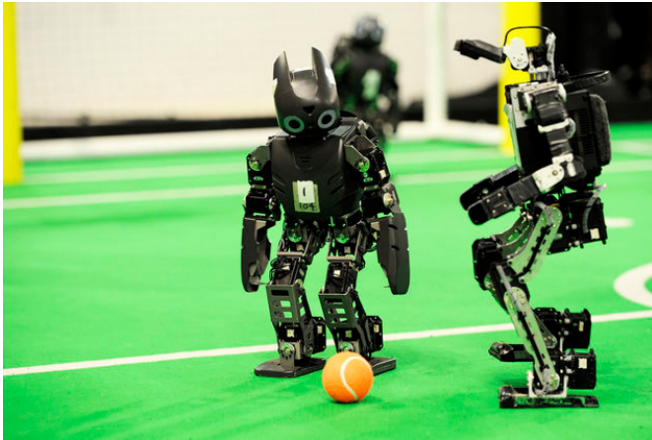
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# Simulation modus operandi

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# Applications (1/2)



## Applications (2/2)

