# Hysteresis Compensation of an Elbow Joint Rehabilitation Robot Featuring Flexible Pneumatic Artificial Muscle Actuation

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- A PAM actuated robot is developed for the elbow joint rehabilitation and movement assistance

- Direct inverse modeling method is utilized to obtain the inverse hysteresis model of the system

- A modified AP algorithm is used to dynamically update the weights of the inverse model
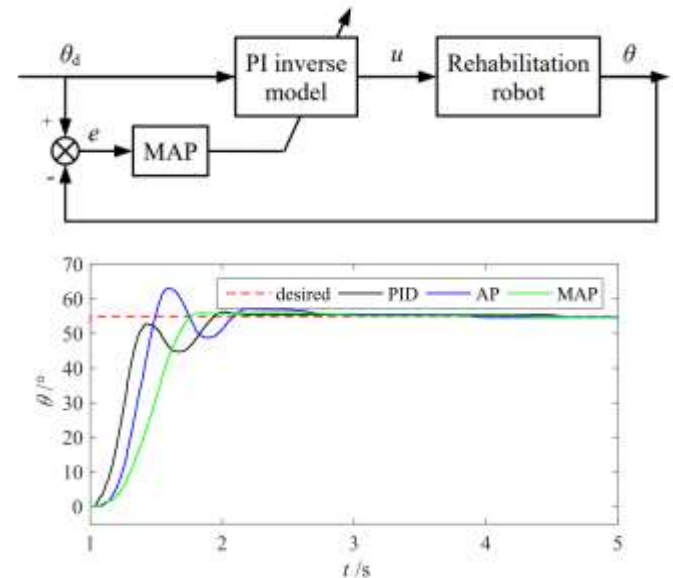
Block diagram of the controller and experiments results