

Inverse Kinematics and Master-Slave Control for a 7-DoF Tendon-Driven Humanoid Robot Arm

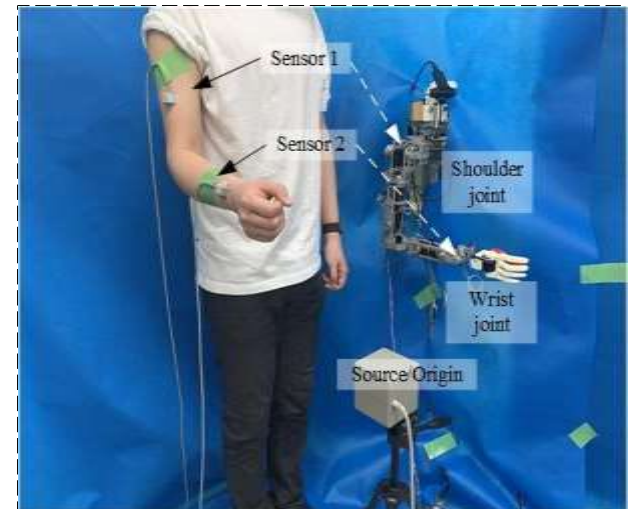
Zhenyu Sun and Wenyang Li

Department of Mechanical Engineering and Intelligent Systems, The University of Electro-Communications, Japan

Xiaobei Jing and Xu Yong

Shenzhen Institutes of Advanced Technology, China

- Analysis of Kinematics and Inverse Kinematics of 7-DOF Robot Arm.
- The mapping relationship between robot arm joints and human arm joints.
- Research on master-slave control strategy.
- Communication based on ROS/ARM/FPGA.



Schematic diagram of master-slave control system