

THE MINISTRY OF SCIENCE AND HIGHER EDUCATION
OF THE RUSSIAN FEDERATION

ITMO University
(ITMO)

Faculty of Control Systems and Robotics

Report of 4th lab
for the subject
“Simulation of Robotic Systems”

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Saint Petersburg 2025

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1 PROBLEM

In this work, we have to create a model of 2 planar connected using tendon.

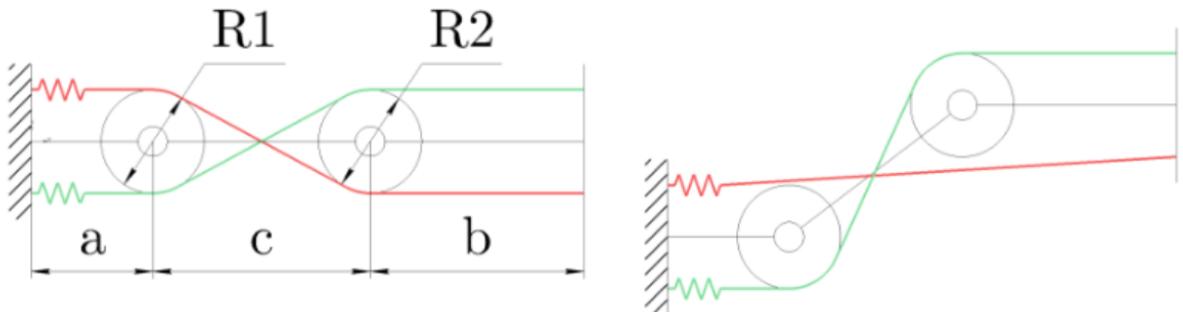


Figure 1 — Schema from the task

My variant for the problem is shown below:

R_1	R_2	a	b	c
0.021	0.017	0.045	0.099	0.043

Table 1 — System parameters

Then we have to add the actuators which attached to the tendons with the following parameters:

q	Amplitude	Frequency	Bias
1	3.616	36.16	3.21
2	4.97	2.24	-3.58

Table 2 — Parameters for actuators

2 SOLUTION

The model can be viewed in the included XML file.

We use this helper function to set the torque for the actuator.

```
1 def set_torque(mj_data, actuator:int, time, a, f, p):
2     mj_data.ctrl[actuator] = a * np.sin(time * f + p)
3
4     ...
5
6     AMP_1 = 3.616
7     FREQ_1 = 36.16
8     BIAS_1 = 3.21
9
10
11    ...
12
13    for i in range(STEP_NUM):
14        if viewer.is_alive():
15            set_torque(data, 0, data.time, AMP_1, FREQ_1, BIAS_1)
16            set_torque(data, 1, data.time, AMP_2, FREQ_2, BIAS_2)
17
18        ...
19
20    else:
21        break
22
23 viewer.close()
```

3 RESULT

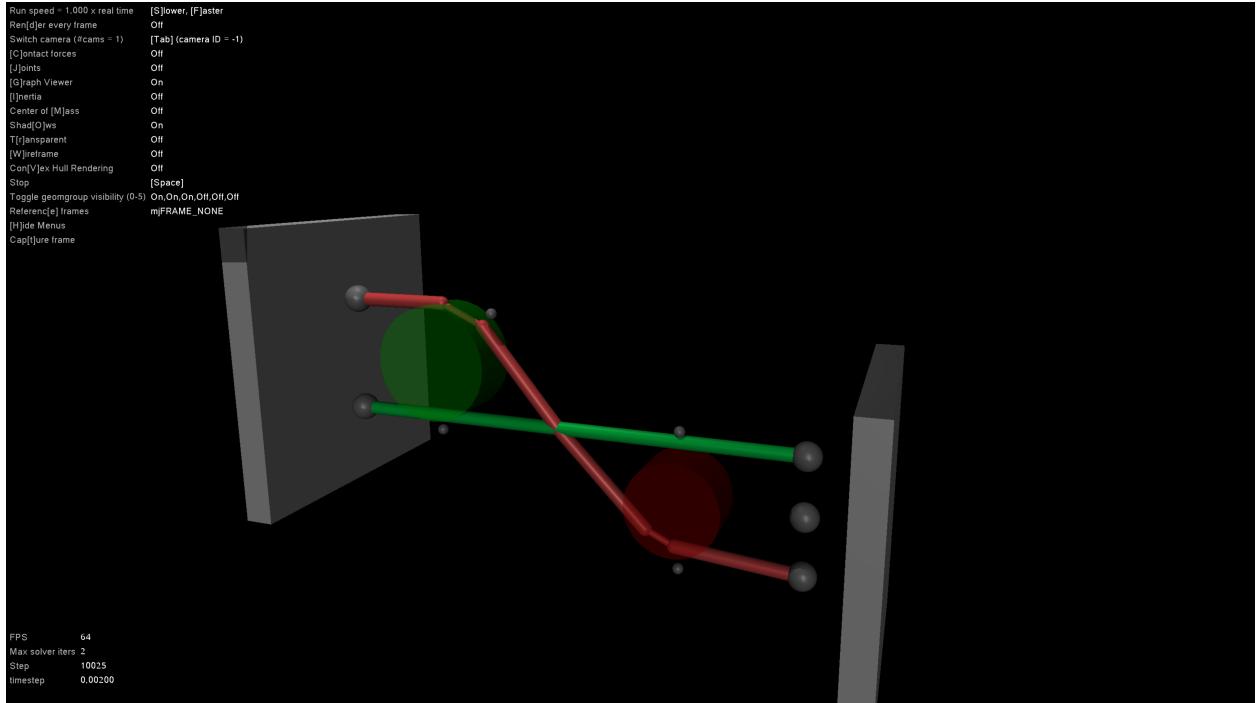


Figure 2

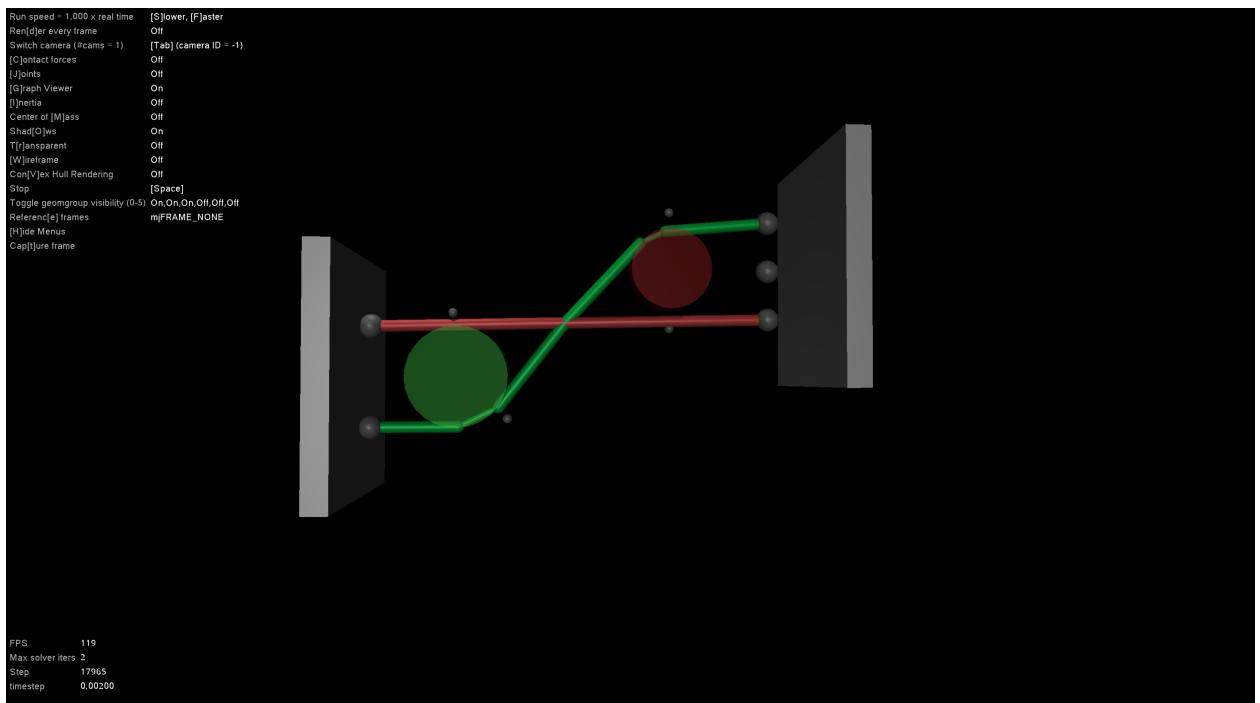


Figure 3

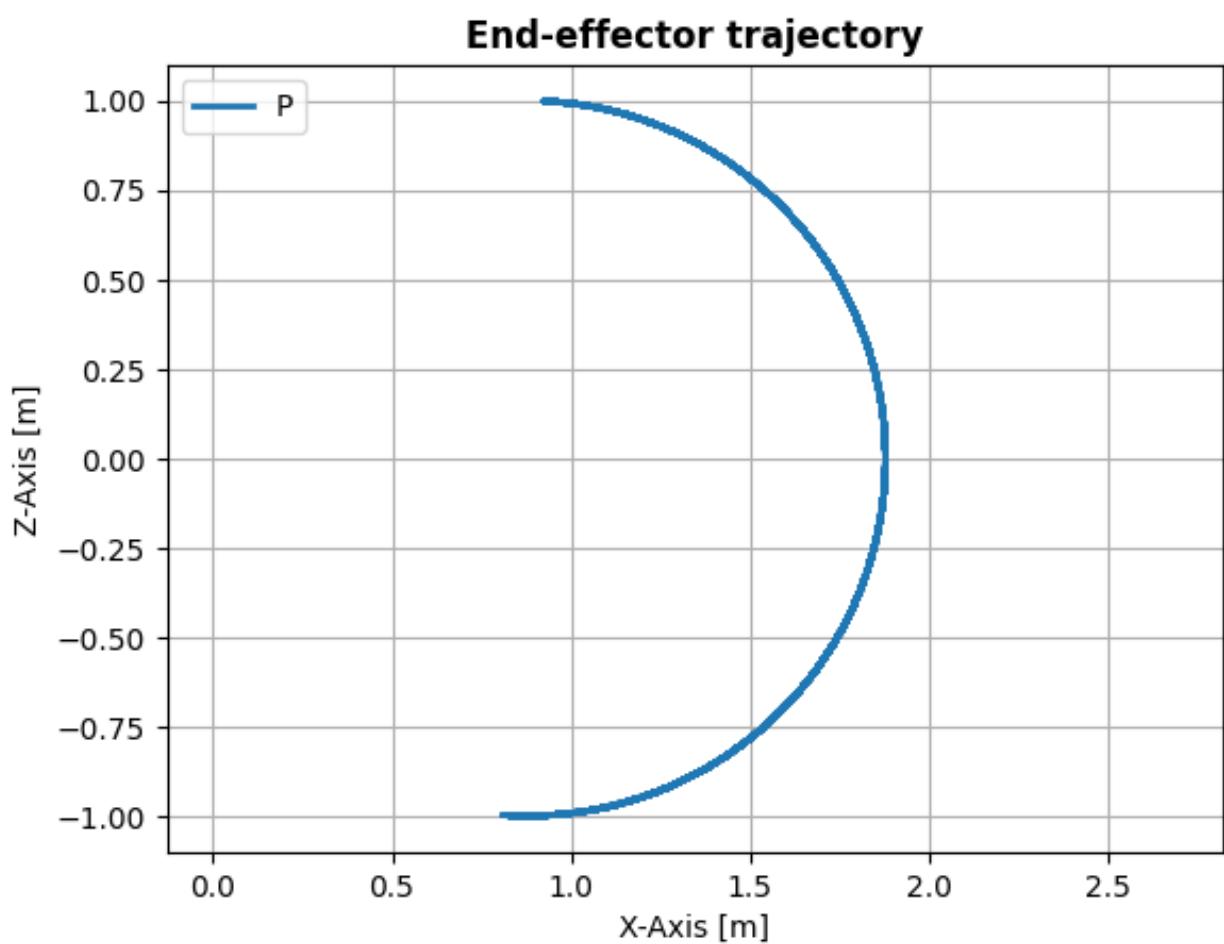


Figure 4 — Trajectory of the effector