

Vodenje v zunanjih koordinatah

Group 1
Signal Builder
Signal 1

$[-0.7 \ 0 \ 0.25 \ 0 \ -\pi/2 \ 0]$

PA10_x
Dir
Kin
Vel
J
Kinematični model

q
 dq

$\text{diag}([0.9; 0.9; 0.9; 0.9; 0.9; 0.9; 0.9])$

J
Pseudoinverse
(weighted)
W
Jp
N

$\text{zeros}(7,1)$

Matrix Multiply

du/dt

K_d

K_p

Matrix Multiply

Matrix Multiply

u
 q
 dq
Inverse Dynamics

1
Torque
0
Speed

Speed Controller
 q u
 $\text{zeros}(1,58)$

ServoStatus
Torque/Speed
AxisAngle
Torque
AxisTorque
Speed
JR3 Force sensor
ExtraBytes
TicToc
PA 10 CONTROL

dq q

Kalman Filter dQ