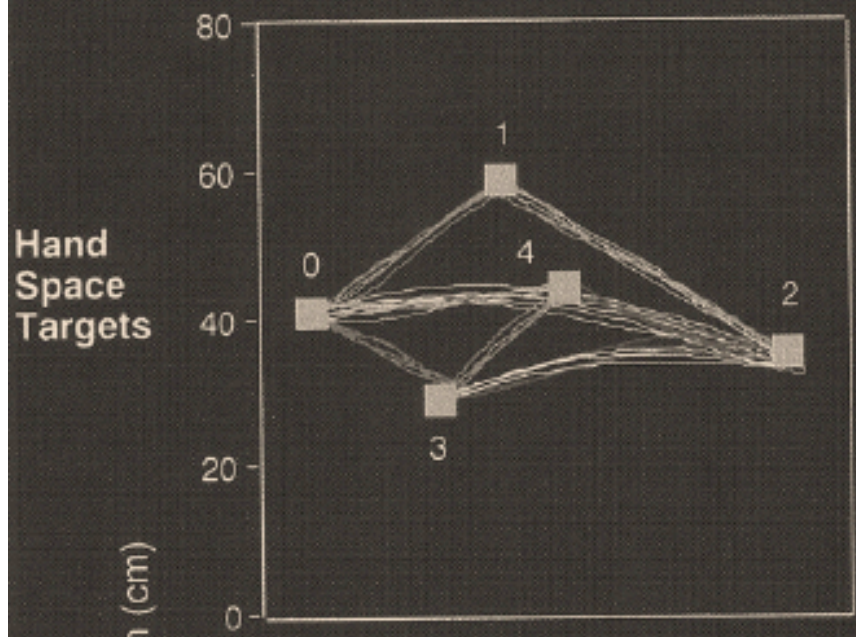
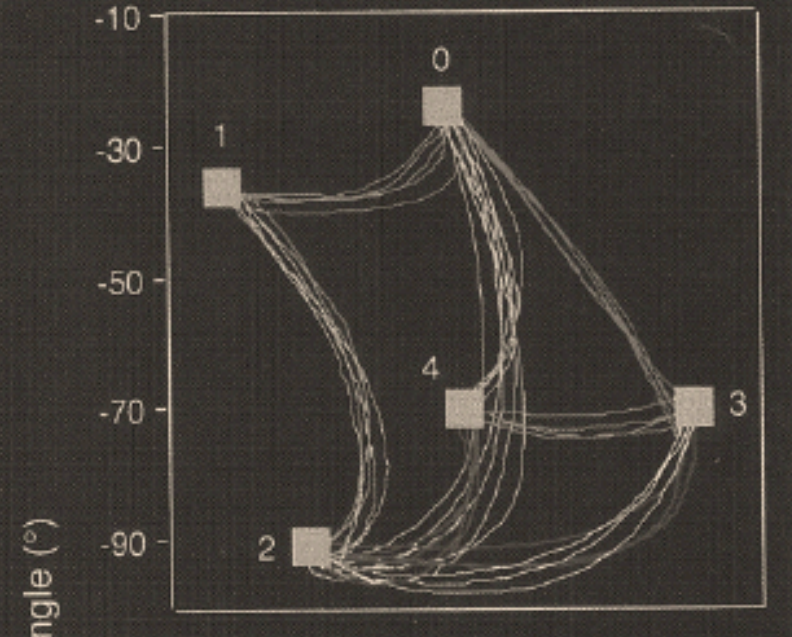


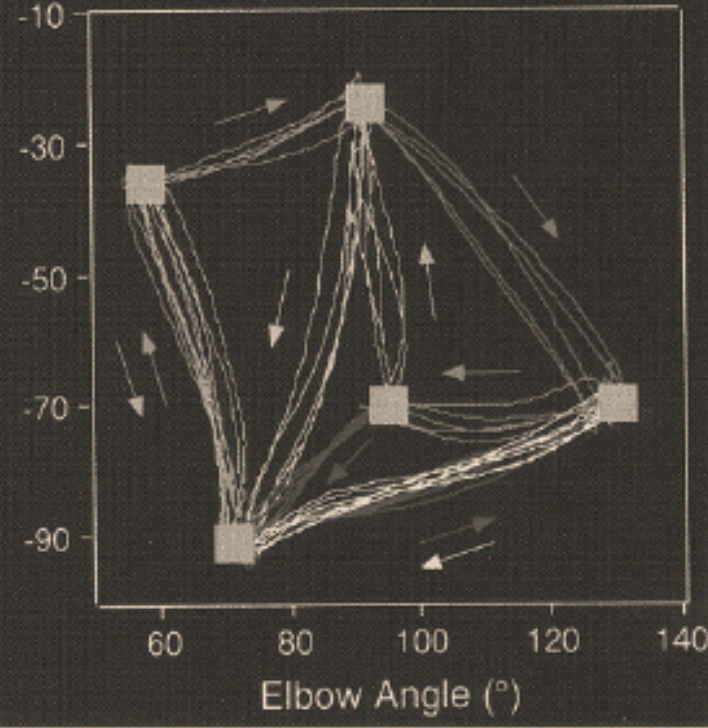
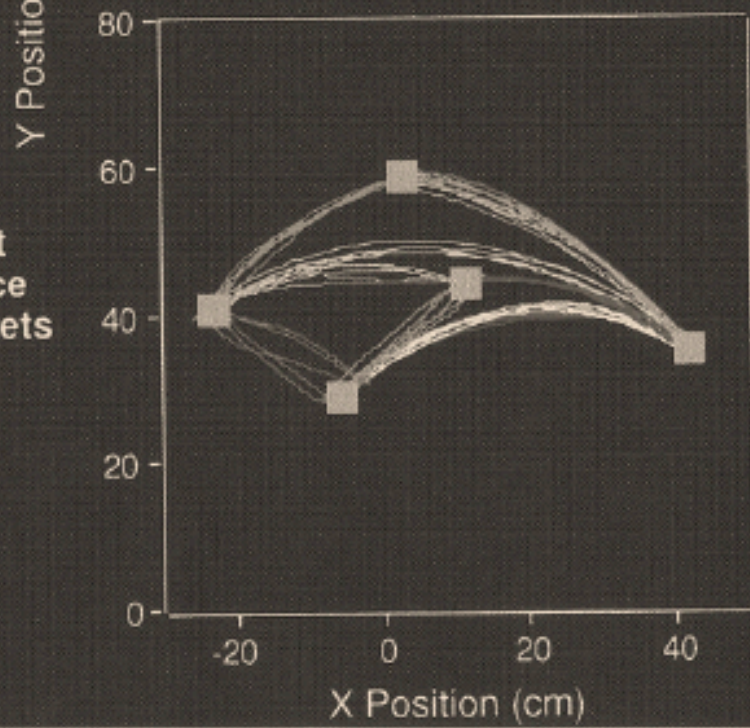
Hand Space

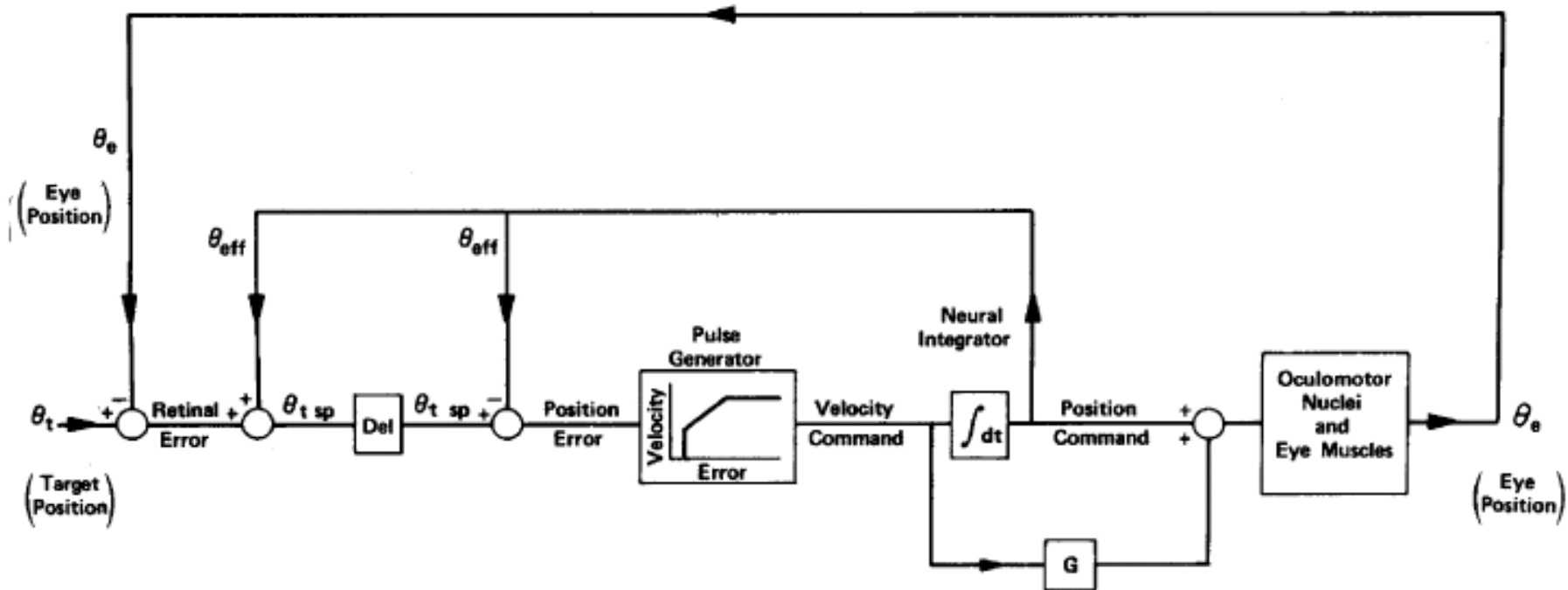


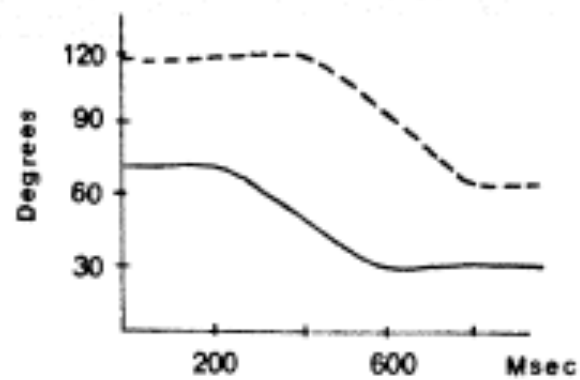
Joint Space



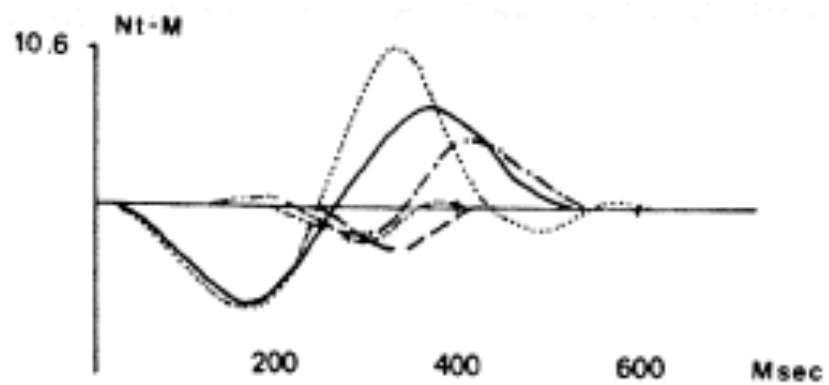
Joint Space Targets



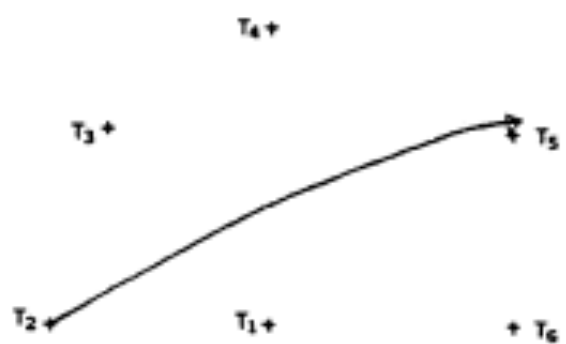




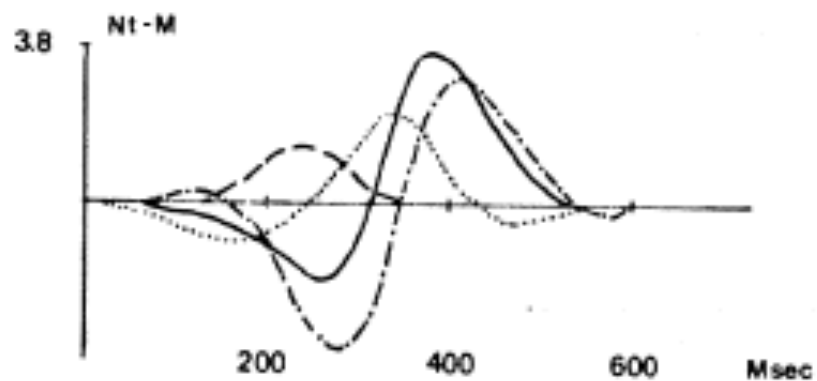
A



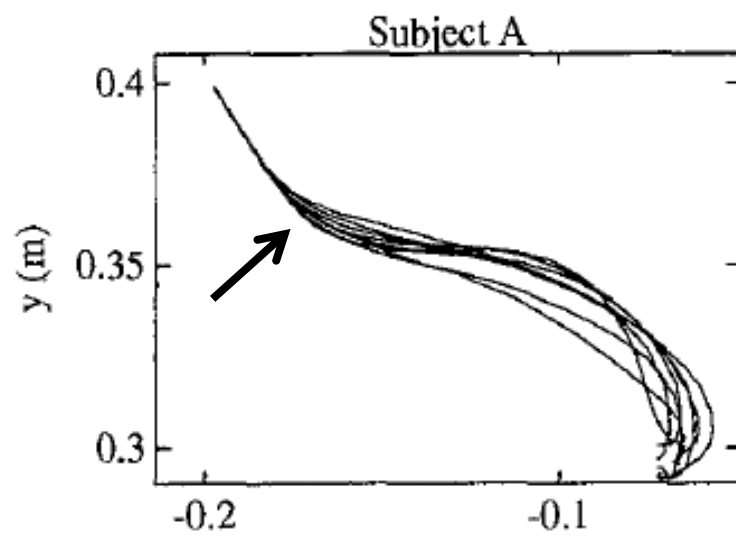
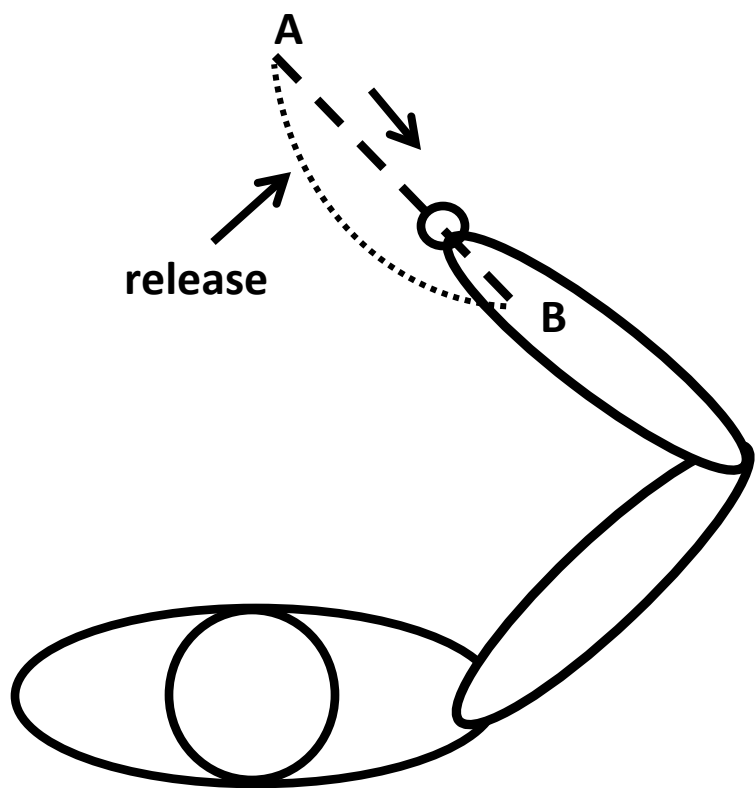
C



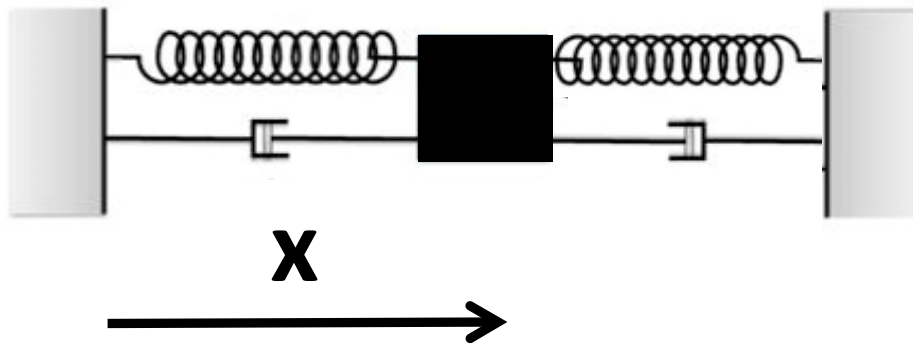
B



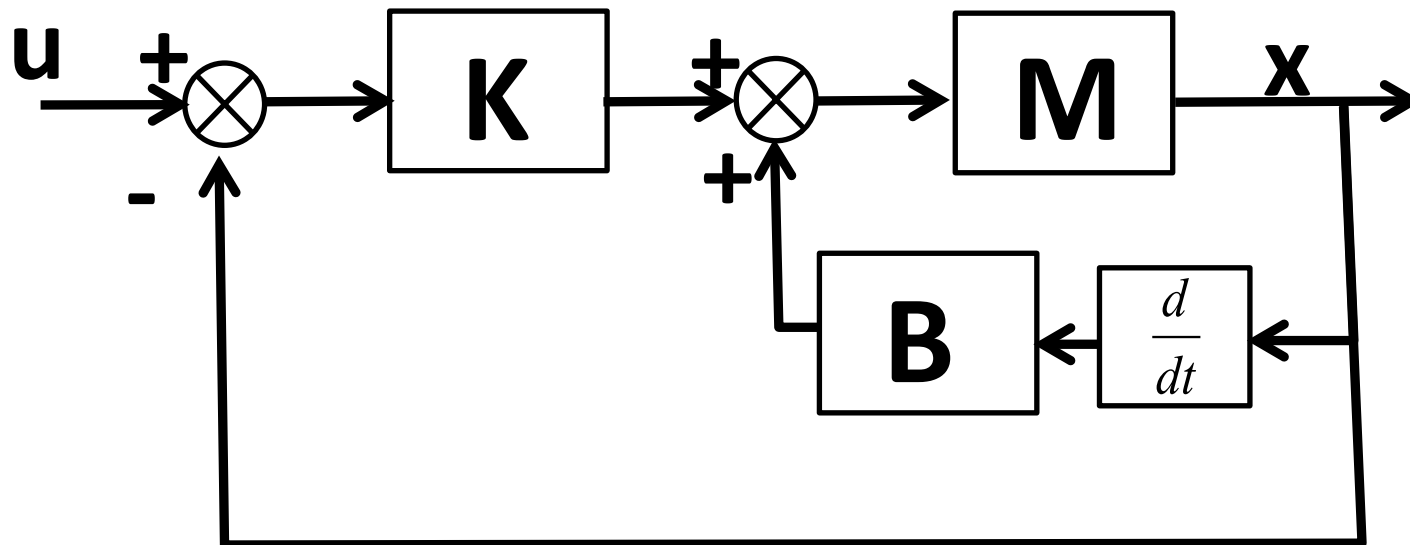
D



A



B



Model Parameters

Arm Segments Length (L) 30 cm

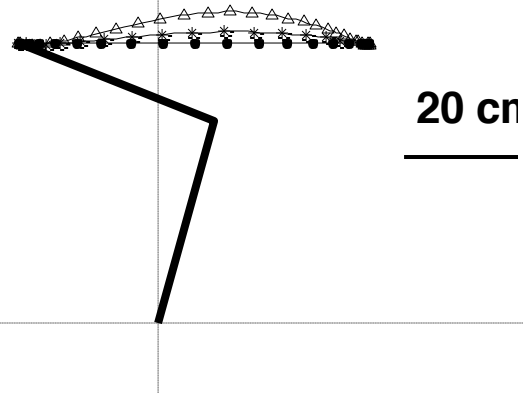
Arm Segments Mass (M) 3Kg

Arm Segments Inertia (I) 2 Kg m²

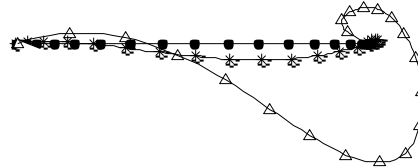
Stiffness (K) $\begin{bmatrix} -15 & -6 \\ -6 & 16 \end{bmatrix}$ Nm/radians

Damping (B) $\begin{bmatrix} -4.6 & -1.8 \\ -1.8 & -4.8 \end{bmatrix}$ Nm Sec/radians

A

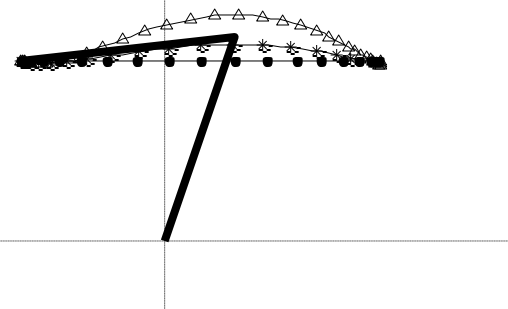


B

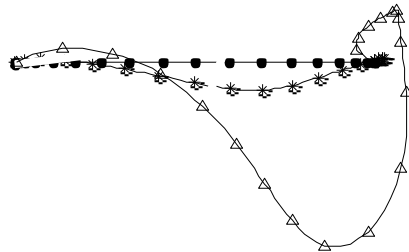


* 2 seconds
 Δ .8 seconds

C



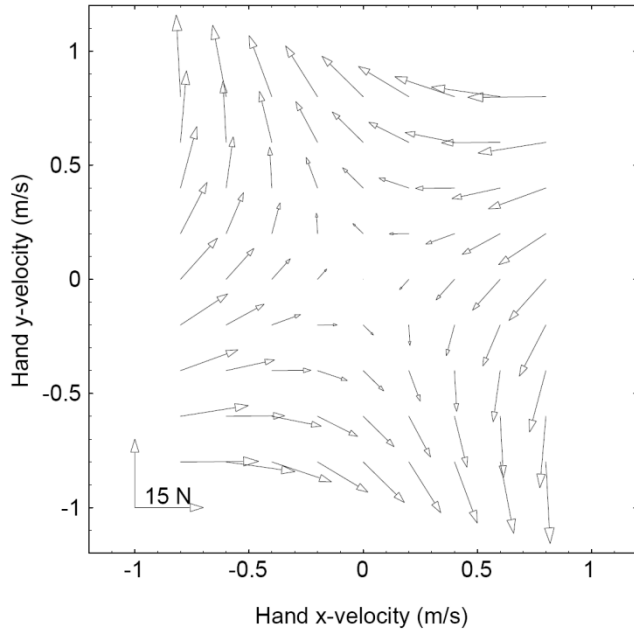
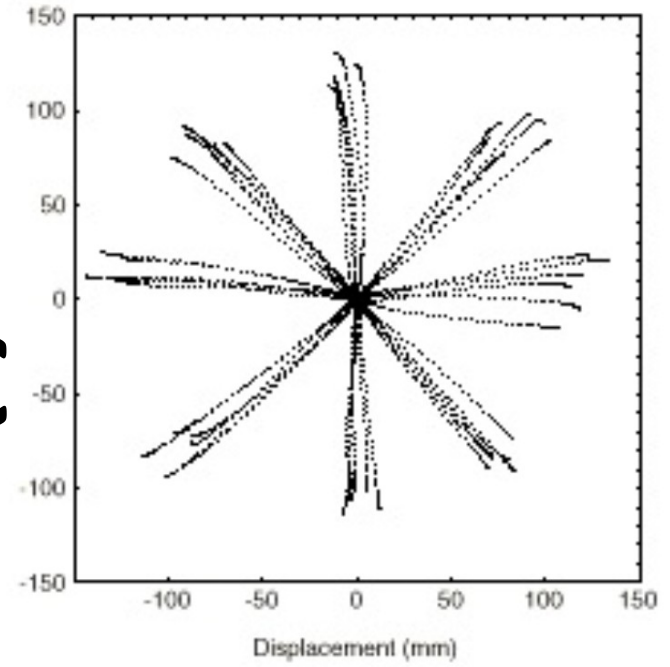
D





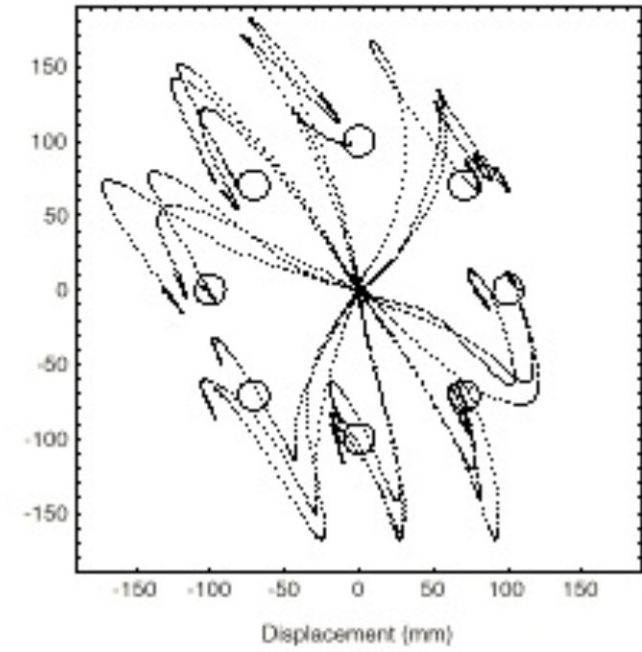
A

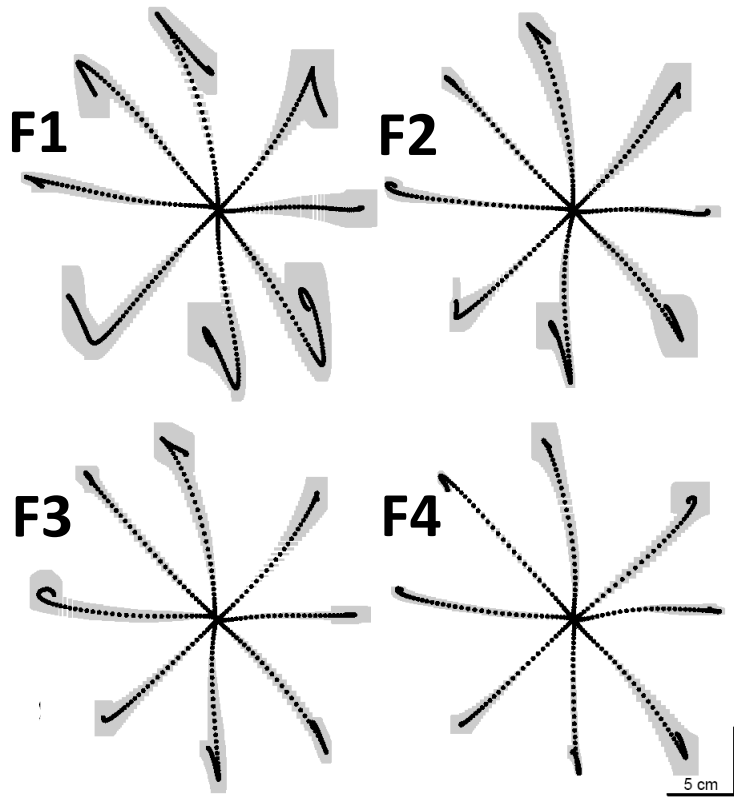
C



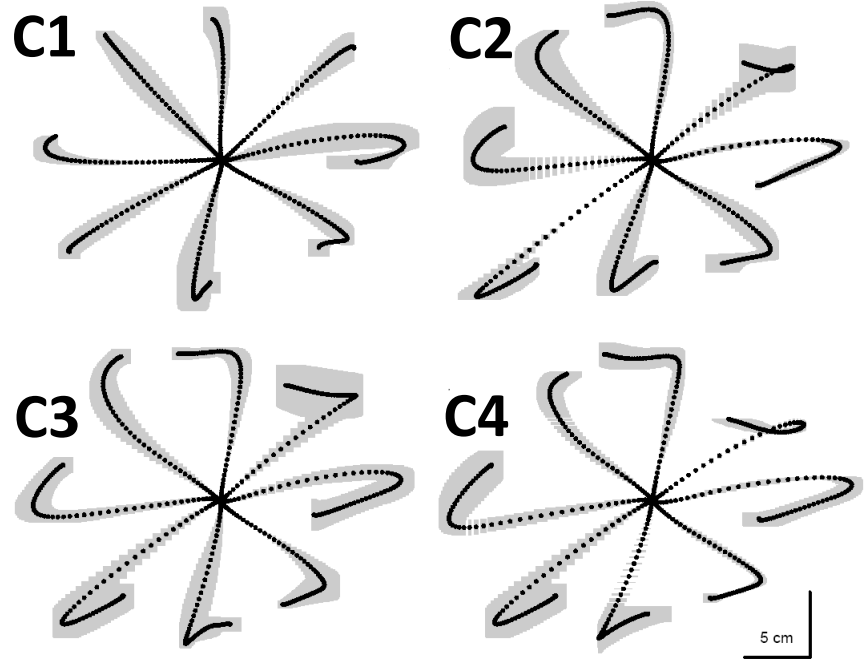
B

D





FIELD



CATCH