Robotic hand

Fantin Gauthier

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In the realm of robotics, achieving stability is a paramount goal in creating machines that can seamlessly navigate and interact within the human environment. This paper delves into the intricacies of designing a stabilization system for a full human robot project, where the delicate balance between mechanical equilibrium and dynamic motion is a critical challenge. By implementing advanced control algorithms and harnessing principles from biomechanics, we embark on a journey to ensure that the robotic entity maintains equilibrium, responsiveness, and adaptability akin to its human counterpart.

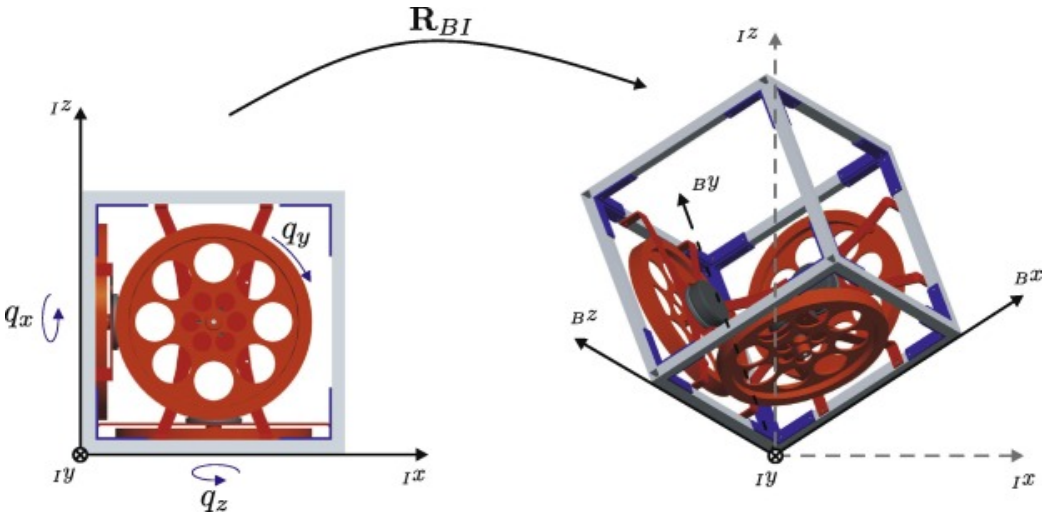

Figure 1: Stabilized inertia cube `www.youtube.com/watch?v=n_6p-1J551Y`