Novel 6-DOF Wearable Exoskeleton with Pneumatic Force-Feedback for Bilateral Teleoperation

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Abstract: Magnetic drive pump has got great achievement and has been widely used in some special fields. Currently, the researches on magnetic drive pump have focused on hydraulic design, bearing axial alignment, etc. A magnetic drive pump with low flow and high head have been developed overseas. However, low efficiency and large size are the common disadvantages for the magnetic drive pump. In order to study the performance of high-speed magnetic drive pump, FLUENT is used to simulate the inner flow field of magnetic drive pumps with different rotate speeds, and get velocity and pressure distributions of inner flow field. According to analysis the changes of velocity and pressure to ensure the stable operation of pump and avoid cavitation. Based on the analysis of velocity and pressure, this paper presents the pump efficiency of magnetic drive pumps with different rotated speeds by calculating the power loss in impeller and volute, hydraulic loss, volumetric loss, mechanical loss and discussing the different reasons of power loss between the magnetic drive pumps with different rotated speeds. In addition, the magnetic drive pumps are tested in a closed testing system. Pressure sensors are set in inlet and outlet of magnetic drive pumps to get the pressure and the head, while the pump efficiency can be calculated by calculating the power loss between the input power and the outlet power. The results of simulation and test are in agreement, which shows that the method of simulation is feasible. The proposed research provides the instruction to design high-speed magnetic drive pump.

Key words: exoskeleton arm, teleoperation, pneumatic force-feedback, hybrid fuzzy control

1 Introduction

At first look at modern society, more and more robots and automated devices are coming into our life and serve for human. But on even further look, tele操作 system is still an idea among lower levels, essentially providing the “grunt” to perform some routine tasks. Human control is limited to very low levels just as the term human interface which is coined by SHI. The master-slave teleoperation system for the safe manipulation of radioactive materials in a contaminated area in 1957 was the typical example of this concept. Hereafter, exoskeleton arms with force-feedback have been widely developed in the fields of robot teleoperation, haptic interface to enhance the performance of the human operator, also in the exciting applications in surgery planning, personnel training, and physical rehabilitation. DUBEY, et al[3], developed a methodology to incorporate sensor and actuator function into human controlled teleoperation systems. In their approach, the operator was retained at all phases of the operation, and was assisted by adjusting system parameters which were not under direct control by the operator, specifically, the mapping of positions and velocities between the master and slave arms and their impedance parameters. The ESA Human exoskeleton was developed to enable force-feedback control of the robot in the complex environment of the international space station with redundant robotic arms[4]. In recent work[5–6], an exoskeleton was used to control the position of body parts with new concepts were applied in the design. Several researchers from Korea and China[7–10], supported by National Natural Science Foundation of China(Grant No. #), National Hi-tech Research and Development Program of China(863 Program, Grant No. #), Beijing Municipal Natural Science Foundation of China(Grant No. #), and Zhejiang Provincial Natural Science Foundation of China(Grant Nos. #, #), also in the exciting applications in surgery planning, personnel training, and physical rehabilitation. DUBEY, et al[3], developed a methodology to incorporate sensor and actuator function into human controlled teleoperation systems. In their approach, the operator was retained at all phases of the operation, and was assisted by adjusting system parameters which were not under direct control by the operator, specifically, the mapping of positions and velocities between the master and slave arms and their impedance parameters. The ESA Human exoskeleton was developed to enable force-feedback control of the robot in the complex environment of the international space station with redundant robotic arms[4]. In recent work[5–6], an exoskeleton was used to control the position of body parts with new concepts were applied in the design. Several researchers from Korea and China[7–10], supported by National Natural Science Foundation of China(Grant No. #), National Hi-tech Research and Development Program of China(863 Program, Grant No. #), Beijing Municipal Natural Science Foundation of China(Grant No. #), and Zhejiang Provincial Natural Science Foundation of China(Grant Nos. #, #). Supported by National Natural Science Foundation of China(Grant No. #), National Hi-tech Research and Development Program of China(863 Program, Grant No. #), Beijing Municipal Natural Science Foundation of China(Grant No. #), and Zhejiang Provincial Natural Science Foundation of China(Grant Nos. #, #).

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supervisor giving the command through the exoskeleton arm in safe zone with visual display interface; ② slave system is designed to move the exoskeleton through the Internet or Ethernet. In section 2, by using the orthogonal experiment design method, the design foundation of ZJUESA and its optimal design are presented. Then in section 3, we describe a novel hybrid fuzzy control system for the force feedback on ZJUESA. Consequently, the force feedback control simulations and experiment results analysis are presented in section 4, followed by discussions and conclusions.

2 Configuration of the Exoskeleton Arm System

The master-slave control is widely employed in the robot manipulator, where the keyboard is the routine input device for the master-slave control system. The configuration of the exoskeleton arm presented in this paper is shown in Fig. 1.

![Fig. 1. Configuration of the exoskeleton arm system](image)

In the system, the Joystick as the command generator of the structure mechanical model and can transfer the motions of human upper arm to the slave manipulator position-control-commands through the Internet or Ethernet between the master and slave computers. With this information, the slave manipulator mimics the motion of the operator. At the same time, the force-feedback signals, detected by the 6-axis force/torque sensor on the slave robot arm end effector, are sent back to indicate the pneumatic actuators for the force-feedback on ZJUESA to realize the bilateral teleoperation.

Since ZJUESA is designed by following the physiological parameters of the human upper-limb, with such a device the human operator can control the manipulator more comfortably and intuitively than the system with the joystick or the keyboard input.

3 Design of the Exoskeleton Arm

What we desire is an arm exoskeleton which is capable of following motions of the human upper-limb accurately and supplying the human upper-limb with proper force feedback if needed. In order to achieve an ideal controlling performance, we have to examine the structure of the human upper-limb.

3.1 Anatomy of human upper-limb

3.1.1 Upper-limb

Recently, various parts of the human upper-limb anatomy have been studied. The arm that surrounds the shoulder muscles, tendons and bones are too complex to be utilized in mechanical design of an anthropomorphic robot arm. From the view of the mechanism, we should set up a more practicable model for easy and effective realization.

Fig. 2 introduces the configuration of human upper-limb and its equivalent mechanical model, which is a 7-DOF structure, including 3 degrees of freedom for shoulder (flexion/extension, abduction/adduction and rotation), 1 degree of freedom for elbow (flexion/extension) and 3 degrees of freedom for wrist (flexion/extension, pronation/supination and flexion/extension). The details about the joints can be found in Refs. [18, 20]. The skeletal joints can be considered as spherical joints and the elbow as a revolution joint. It is a good approximation model for the human upper-limb, and the base model for the design and construction of exoskeleton arm-ZJUESA.

![Fig. 2. Configuration of human upper limb and its equivalent mechanical model](image)

3.2 Mechanism of the exoskeleton arm

Because the goal of this work is to control the movements of the human arm accurately for teleoperation, ZJUESA ought to make the best of motion scope of the human upper-limb and limit it as little as possible. A flexible structure with the same or similar configuration of human upper-limb is an ideal choice. Based on the anatomy of human upper-limb, the joint motion originates from extension or flexion of the muscle and ligament with each other to generate torque around the bones. Compared with the serial mechanism, the movements of the parallel mechanism are driven by the
prismatic joints in the parallel mechanism lie on the surface of human upper-limb.

The 3RPS parallel mechanism is one of the simplest mechanisms. Fig. 3 explains the principle of the 3RPS parallel mechanism. KIM, et al.\(^\text{[11]}\) introduced it into the KIST design. Here we follow this concept. The two revolution degrees of freedom embodied in the 3RPS are for flexion/extension, abduction/adduction at shoulder. Its third translation degree of freedom along z axis can be used for the dimension adjustment of ZJUESA parallel mechanism.

As mentioned above, the best design is to make the workspace of ZJUESA as fully cover the scope of the human upper-limb motion as possible. We employ the 3RPS parallel mechanism for the shoulder, whose workspace mainly influences the workspace of ZJUESA. The optimal design of 3RPS parallel mechanism for the shoulder is the key point of ZJUESA optimal design. However, it is a designing problem with multi-factors, saying the displacement of the prismatic (factor A), circumradius ratio of the upper and lower platforms (factor B), initial length of the prismatic (factor C), and their coupling parameters (factor A+B, A+C and B+C) (Table 1) namely, its workspace, weight, size. So, we use the orthogonal experiment design method with 6 key factors\(^{[21]}\) and Eq. (1) gives the expression of the optimal target function of this problem:

\[
Q = F \left( L_0, \theta - \theta_0, \frac{r}{R} \right), \tag{1}
\]

where \(L_0\) is the initial length of the prismatic, \(R\) is the circumradius of the lower base in 3RPS mechanism, \(r\) is the cirumradius of the upper base in 3RPS mechanism, \(\theta\) is the expected reachable angle around axis. In this array the first column implies the displacement of the prismatic (factor A), the second column implies\((\theta - \theta_0)\) (factor B), the third column implies \(\frac{r}{R}\) (factor C).

Table 1. Factors and their levels

<table>
<thead>
<tr>
<th></th>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A+B</th>
<th>A+C</th>
<th>B+C</th>
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<tr>
<td>1</td>
<td>60</td>
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<tr>
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<td>0.389</td>
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<td></td>
</tr>
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<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>180</td>
</tr>
</tbody>
</table>

The orthogonal experiment design allows a decrease in the number of experiments performed with only slightly less accuracy than full factor testing. The orthogonal experiment design concept can be used for any complicated system being investigated, regardless of the nature of the system. During the optimization, all variables, even continuous ones, are thought of discrete “levels”. In an orthogonal experiment design, the levels of each factors are allocated by using an orthogonal array\(^{[22]}\). By discretizing variables in this way, a design of experiments is advantageous in that it can reduce the number of combinations and is resistant to noise and conclusions valid over the entire region spanned by the control factors and their setting.

Table 2 describes an orthogonal experiment design array for 6 key factors\(^{[23]}\). In this array the first column implies the number of the experiments and factors A, B, C, A+B,
Table 2. Orthogonal experiment design array L36 for 6 key factors

<table>
<thead>
<tr>
<th>Experiment No.</th>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A*B</th>
<th>A*C</th>
<th>B*C</th>
<th>Result Q</th>
</tr>
</thead>
<tbody>
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<td>1</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>1</td>
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<td>Y₁</td>
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<tr>
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<td>1</td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>2</td>
<td>2</td>
<td>Y₂</td>
</tr>
<tr>
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<td>1</td>
<td>1</td>
<td>3</td>
<td>1</td>
<td>3</td>
<td>3</td>
<td>Y₃</td>
</tr>
<tr>
<td>4</td>
<td>1</td>
<td>1</td>
<td>4</td>
<td>1</td>
<td>4</td>
<td>4</td>
<td>Y₄</td>
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<tr>
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<td>2</td>
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<td>2</td>
<td>2</td>
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<td>6</td>
<td>Y₆</td>
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<tr>
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<td>3</td>
<td>1</td>
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<td>2</td>
<td>9</td>
<td>10</td>
<td>10</td>
<td>Y₃₆</td>
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<tr>
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<td>3</td>
<td>3</td>
<td>9</td>
<td>11</td>
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<td>Y₃₅</td>
</tr>
<tr>
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<td>3</td>
<td>3</td>
<td>4</td>
<td>9</td>
<td>12</td>
<td>12</td>
<td>Y₃₆</td>
</tr>
</tbody>
</table>

The relation between column IV and columns I, II is that: if level of A is n and level of B is m, the level of A+B is 3(n−1)+m, where n = 1, 2, 3 and m = 1, 2, 3.

All the cases can be expressed as follows:

(1, 1) → 1 (1, 2) → 2 (1, 3) → 3;
(2, 1) → 4 (2, 2) → 5 (2, 3) → 6;
(3, 1) → 7 (3, 2) → 8 (3, 3) → 9.

The first element in the bracket represents the corresponding level of factor A in Table 1 and the latter means the corresponding level of the factor B. Factor A+B has totally 9 levels, as factor A and factor B have 3 levels, respectively.

Likewise, the relation between column V and columns I, III is

(1, 1) → 1 (1, 2) → 2 (1, 3) → 3 (1, 4) → 4;
(2, 1) → 5 (2, 2) → 6 (2, 3) → 7 (2, 4) → 8;
(3, 1) → 9 (3, 2) → 10 (3, 3) → 11 (3, 4) → 12.

Also the relation between column VI and columns II, III is

(1, 1) → 1 (1, 2) → 2 (1, 3) → 3 (1, 4) → 4;
(2, 1) → 5 (2, 2) → 6 (2, 3) → 7 (2, 4) → 8;
(3, 1) → 9 (3, 2) → 10 (3, 3) → 11 (3, 4) → 12.

The optimal design is carried out according to the first three columns:

\[ K_i = \max \{I_{ij}\} - \min \{I_{ij}\}, \quad (3) \]

where \( i = A, B, C, A*B, A*C, B*C; j \) is the number of \( i \) rank.

By Eqs. (2), (3) and the kinematics calculation of the 3RPS parallel mechanism [35], the relationship between the target \( Q \) and \( B\) and \( C \) is shown, as shown in Fig. 5.

According to the plots in Fig. 5, superiority and the degree of the influence of each design factor. The factor with bigger extreme difference \( K_s \), as expressed in Eq. (3) has more influence on \( Q \). In this case, it can be concluded that the sensitivity of the factors \( A+B \) and \( A+C \) are high and factors \( B+C \) and \( C \) have weak influence, since \( K_{A+B} \) and \( K_{A+C} \) are much bigger than \( K_{B+C} \) and \( K_{C} \). And the set \( A_iB_1, A_1C_1, A_2B_1, B_1C_1, B_1C_1 \) are the best combination of each factor levels. But there is a conflict with former 3 items in such a set. As their \( K_i \) have little differences between each other, the middle course is chosen. After compromising, we take the level 2 of factor \( A \), the level 1 of factor \( B \) and the level 1 of factor \( C \), namely \( d = 80 \text{ mm}, r/R = 0.5, L_0 = 150 \text{ mm}[35] \).

It is interesting to know how good the results derived from the above 36 trials are, when compared with all other possible combinations. Because of its mutual balance of orthogonal arrays, this performance ratio can be guaranteed.
by the theorem in non-parametric statistics\textsuperscript{[13]}. It predicts that this optimization is better than 97.29\% of alternatives.

Combined with the kinematics and dynamics simulation of the 3RPS parallel mechanism and ZJUESA with chosen design parameters by ADAMS, we perform the optimal design. Table 3 indicates the joint range and joint torque of each joint on ZJUESA. It is apparent that ZJUESA can almost cover the workspace of human upper-limb well so that it can follow the motion of human operation upper-limb with little constrain, as shown in Fig. 6.

### Table 3. Joint ranges and joint torques for each joint on ZJUESA

<table>
<thead>
<tr>
<th>Joint on ZJUESA</th>
<th>Joint range</th>
<th>Joint torque</th>
<th>Joint density</th>
</tr>
</thead>
<tbody>
<tr>
<td>Flexion/extension(shoulder)</td>
<td>-60–60</td>
<td>36</td>
<td>-</td>
</tr>
<tr>
<td>Abduction/adduction</td>
<td>-50–60</td>
<td>36</td>
<td>-</td>
</tr>
<tr>
<td>Rotation(shoulder)</td>
<td>-20–90</td>
<td>18</td>
<td>-</td>
</tr>
<tr>
<td>Flexion/extension(elbow)</td>
<td>0–90</td>
<td>28</td>
<td>-</td>
</tr>
<tr>
<td>Rotation(wrist)</td>
<td>-20–90</td>
<td>13</td>
<td>-</td>
</tr>
<tr>
<td>Flexion/extension(wrist)</td>
<td>0–60</td>
<td>28</td>
<td>-</td>
</tr>
<tr>
<td>Abduction/ adduction(wrist)</td>
<td>...</td>
<td>...</td>
<td>...</td>
</tr>
</tbody>
</table>

Fig. 6. Motion of exoskeleton arm following the operator

4 Hybrid Fuzzy-Controller for the Force Feedback On Zjuesa

In master-slave manipulation, besides the visual feedback and man-machine soft interface, the force feedback is another good choice to enhance the control performance. If the slave faithfully reproduces the master motions and the master accurately feels the slave forces, the operator can experience the same interaction with the teleoperated tasks, as would the slave. In this way the teleoperation becomes more intuitive.

In our bilateral teleoperation system with ZJUESA, a 6 axis force/torque sensor is mounted on the end effector of the slave manipulator and detects the force and torque acting on the end effector during performing the work. This information is transferred to the master site in real time. With dynamic calculation, the references of the generating force on actuators of ZJUESA are obtained. Hereafter, the feeling can be reproduced by means of the pneumatic system.

Eq. (4) expresses the relation between the force and torque on the end effector and the torques generating on the joints:

\[ \tau = f^T F, \]

where \( F \) —Force and torque on the joints, \( f \) —Torque on each joint, \( J \) —Jacobian matrix of ZJUESA.

By dividing the force arm, it is easy to get to the generating force of the prismatics on the 3RPS parallel mechanism, it can be calculated as follows\textsuperscript{[35]}:

\[ f = (f_4, f_5, f_6, f_7)^T = \left( \frac{r_1}{a_3}, \frac{r_2}{a_4}, \frac{r_3}{a_5}, \frac{r_6}{a_6} \right)^T, \]

where \( a_i \) \((i=3, 4, 5, 6)\) is the force arm of the shoulder ring, elbow, wrist ring and wrist, as explained by Eq. (5):

\[ f = \begin{bmatrix} f_1 \\ f_2 \\ f_3 \end{bmatrix} = G_f \left( \begin{bmatrix} \tau_{\text{3RPS}} \end{bmatrix} \right), \]

where \( G_f \) —Jacobian matrix of 3RPS parallel mechanism,

\( \tau_{\text{3RPS}} \) —Torques on 3RPS parallel mechanism,

\( \tau_3 = \left( \tau_1, \tau_2 \right)^T \),

\( f_{\text{3RPS}} \) —Force on 3RPS parallel mechanism.

Therefore, with Eqs. (5), (6), the total seven force references are obtained for the pneumatic system on ZJUESA. Fig. 7 explains the scheme of the pneumatic cylinder-valve system for the force feedback.

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the specially tuning of relatively simple linear or nonlinear controllers. As a result, for pressure or force control in such a nonlinear system, especially in which the chamber pressure vibrates rapidly, the conventional control method can hardly have a good performance.

Fortunately, the introduction of the hybrid control method mentioned, gives out a solution to this problem. But the traditional design of the hybrid controller is always complicated and only available to the proportion or servo valve system. In our system, we figured out a kind of novel hybrid fuzzy control strategy for the high-speed on-off valves, which is much simpler and can be realized by micro control units (MCUs) in the contributed architecture. This strategy is composed of two main parts: a fuzzy controller and a bang-bang controller. The fuzzy controller provides a formal methodology for representing, manipulating, and implementing a person’s heuristic knowledge about how to control a system. It can be regarded as an artificial nervous system in a closed-loop system in real time and can get the control information either from a human decision maker who performs the control task or by self-learning. The bang-bang controller can help the system to get the control information much more quickly.

Fig. 8 shows the concept of the proposed hybrid fuzzy controller. The concept of multimode switching is applied to activate either the bang-bang controller or the fuzzy controller mode.

Bang-bang control is applied when the actual output is far away from reference value. In this mode, fast tracking of the output is implemented. The fuzzy controller is activated when the output is near the set point, which needs accuracy control.

In the fuzzy-control mode, we use pressure error \( e(t) = P_{\text{ref}}(t) - P_{\text{man}}(t) \) and its change \( \dot{e}(t) \) as the input variables on which to make decisions. On the other hand, the width of the high voltage in one PWM period is denoted as the output of the controller.

As mentioned above, the PC on master site works as the supervisor for real-time displaying, kinematics calculation and exchanges the control data with the slave computer and so on. For the sake of reducing the burden of the master PC, the distributed control system is introduced. Each control unit contains a Mega8 MCU of ATMEL Inc., working as a hybrid fuzzy-controller for each cylinder respectively, and forms a pressure closed-loop control. The controller samples the pressure in chamber with 20 kHz sampling rate.
by the in-built analog-digital converters. These controllers keep in contact or get the differential pressure signals from the master PC through RS232, as depicted in Fig. 9. In this mode, fast tracking of the output is implemented.

5 Force Feedback Experiments

Fig. 10 gives out the set up of the force feedback experiments. The system includes the soft interface, data acquisition, Mega8 MCU experiment board, on-off valves, sensors of displacement and pressure, and the oscilloscope. We chose the cylinder DSNU-10-40-P produced by FESTO Inc. The soft signal generator and data acquisition are both designed in the LabVIEW, with which users may take advantage of its powerful graphical programming capability. The most obvious difference is that LabVIEW is a graphical compiler that uses icons instead of lines of text. Additionally, LabVIEW has a large set of built-in mathematical functions and graphical data visualization and data input objects typically found in data acquisition and analysis applications.

The plots in Fig. 11 give out experimental results of the chamber pressure outputs with step input signals on one joint. While at frequencies higher than 80 Hz, force is sensed through the operator’s joint, muscle and tendon receptors, and the operator is unable to respond to, and low amplitude disturbances at these frequencies. We remove reflected force signals above 80 Hz band by fast Fourier transfer (FFT) and get the smoothed curve in the plots. One is obtained by using hybrid control strategy and another is obtained by using traditional fuzzy controller without bang-bang controller. Although these two curves both track the reference well with very good amplitude match (less than 5% error) and a few milliseconds misalignment in the time profile, by comparing these two curves, it can be found that the adjust time of the curve with hybrid control strategy is less than 0.03 s, which is much less than 0.05 s of other with traditional fuzzy controller.

Fig. 12 shows the results of tracking a sinusoidal commander. This experiment is implemented to test the dynamic nature of the system. Although there is a little error and delay between the reference curve and the experiment curve, the system has good performance.
realize the bilateral teleoperation with simple motion, in which the slave manipulator is controlled for the shoulder abduction/adduction (the movement of a bone away/toward the midline in the frontal plane) and extension/flexion of elbow (the movement in the sagittal plane) by the teleoperation with ZJUESA.

In the first experiment, the operator performs the shoulder abduction/adduction movement with ZJUESA, when the slave robot follows and holds up the load. With the force feedback on ZJUESA, the operator has feeling as if he holds the load directly without the mechanical structure, as shown in Fig. 13. Plots in Figs. 14, 15 show the torque and force on each joint on ZJUESA during the shoulder abduction/adduction movement from 45° to 90° in the frontal plane) with 5 kg load. There are some remarks. In plots of Fig. 14 shoulder 3RPS-x means the torque around x-axis of 3RPS mechanism at shoulder and the same to shoulder 3RPS-y. Shoulder ring, elbow, wrist ring and wrist represent the torques on these joints, respectively. The characters shoulder 3RPS-1, shoulder 3RPS-2 and shoulder 3RPS-3 in Fig. 15 represent corresponding force on the cylinders on 3RPS parallel mechanism (referring to Fig. 3) with length $L_1$, $L_2$ and $L_3$, respectively.

![Abduction/adduction](image1.png)

Fig. 13. Shoulder abduction/adduction teleoperation

![Extension/flexion](image2.png)

Fig. 16. Extension/flexion for elbow teleoperation

![Torques on the joints of the shoulder abduction/adduction for 5 kg load lifting](image3.png)

Fig. 14. Torques on the joints of the shoulder abduction/adduction for 5 kg load lifting

![Force feedback on the cylinders of the shoulder abduction/adduction for 5 kg load lifting](image4.png)

Fig. 15. Force feedback on the cylinders of the shoulder abduction/adduction for 5 kg load lifting

The operator teleoperates the slave manipulator with force feedback as if he performs for lifting a dumbbell or raising package in daily life (Fig. 16). Fig. 17 shows the moment on each joint during the process for producing the feeling of lifting a 10 kg dumbbell. Fig. 18 depicts the force output of every pneumatic cylinder on ZJUESA.

All these results of experiments demonstrate the effect of ZJUESA system. ZJUESA performs well by following the motions of human upper-limb with little constrain and the pneumatic force feedback system supplies a proper force feedback tracking the reference well.
6 Conclusions

(1) According to the anatomy of human upper-limb, the structure of ZJUESA is presented, which has 6 DOFs totally. 3RPS parallel mechanism analogy to the motion of muscle and ligament of human joint is employed to realize the shoulder structure with 3 degrees of freedom.

(2) The orthogonal experiment design method is employed for the optimal design. As a result a larger workspace of ZJUESA is obtained.

(3) In the interest of much more intuitive feelings in master-slave control process, the force feedback is realized simultaneously on ZJUESA by the pneumatic cylinders. And a novel hybrid fuzzy-controller is introduced in the Mega8 MCU as a unit of the distributed control system due to the non-linearity of the pneumatic system. The bang-bang control is utilized to drive the response of the system much more quickly and the fuzzy controller is activated when the output is near the set point, which needs accurate control.

(4) With sets of experiments, step, slope and sinusoidal commands are taken and the system shows a good performance, and a good agreement is found between the reference curves and experimental curves as well.

(5) The experiments of shoulder abduction/adduction and elbow extension/flexion teleoperation with force feedback are implemented. The results verify the feasibility of ZJUESA master-slave control system and the effect of the hybrid fuzzy controller for the pneumatic system.

References

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Appendix

Appendix and supplement both mean material added at the end of a book. An appendix gives useful additional information, but even without it the rest of the book is complete: In the appendix are forty detailed charts. A supplement, bound in the book or published separately, is given for comparison, as an enhancement, to provide corrections, to present later information, and the like: A yearly supplement is issue.