

Session Room 3 (1206)		
V2: Video and Interactive Session 2		
13:00–14:00 Video Session 14:00–15:00 Poster Session		
Prof. Koichi Hidaka Mr. Jurgen van Zundert		
	Title	First Autor
V2-1	A Proposal of Two-Wheeled Inverted Vehicle with Two Stable Running Modes	Takumi Kato (Chuo University)
V2-2	Optimal Automatic Formation Control for Two-Wheeled Vehicles Using Model Predictive Control with Temporal Logic Constraints	Shunta Haga (Chiba University)
V2-3	High-Accuracy Force Control of Flexible Manipulator based on Nominal Stiffness Design of Load Side Observer	Akiko Nakamura (Yokohama National University)
V2-4	Compensating quasi-static disturbances for inferential control: an observer-based approach applied to a wafer stage	Noud Mooren (Eindhoven University of Technology)
V2-5	Position Estimation by High Frequency Injection in Piezoelectric Actuators	Yuya Sakuragi (Nagoya Institute of Technology)
V2-6	Mathematical Modeling Considering Nonlinearities in Shape-Memory-Alloy Actuators	Takuya Sakagami (Nagoya Institute of Technology)
V2-7	Implementation of feedback and disturbance feedforward control on an industrial active vibration isolation system	Michiel Beijen (Eindhoven University of Technology)
V2-8	Enabling High Precision for Position-dependent Motion Systems using Iterative Learning Control	Robin de Rozario (Eindhoven University of Technology)
V2-9	Yaw Axis Rotation Control about Two-Degree-of-Freedom Wheel	Atsushi Kashima (National Institute of Technology, Kisarazu College)
V2-10	Consideration of Polar Coordinates Rehabilitation Robot from the Viewpoint of Manipulability	Takahiro Fujishiro (Yokohama National University)
V2-11	Static Grasp Analysis of Tendon Type Robot Hand	Akito Sato (National Institute of Technology, Gunma College)
V2-12	Experimental Study on Bilateral Control System with Considering Rigidity of Tactile Object	Atsushi Fujii (National Institute of Technology, Gunma College)