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SS1-5   SS1-5   SS1-5   Copying System Considering Reproduction Stiffness   Satoshi Nishimura (Keio University)   TT5-5   TT5-	SS1-5
SS1-6 Three-inertia System Based on Two-inertia Model Using Modal Transformation of Real Range  -13:00  Session Room 1 (1204)  IS1: High Precision Motion Control in Mechatronic Systems  Prof. Tom Oomen  Prof. Kenta Seki  Akinori Yabuki (Nagaoka University of Technology)  Akinori Yabuki (Nagaoka University of Technology)  Shingo Ito (TU Wien)  TH6-6 Whigh-speed Scanning with Nanometer Resolution  Shingo Ito (TU Wien)  Frof. Session Room 3 (1206)  TT7: Rehabilitation and Welfare Applications  TT8: Advanced Control Theory  Prof. Hyungbo Shim  Prof. Naoki Motoi  Dr. Masato Tanaka	SS-0   Three-inertia System Based on Two-inertia Model Ling Model and Model Transformation of Real Range   Title
Session Room 1 (1204)  IS1: High Precision Motion Control in Mechatronic Systems  TT7: Rehabilitation and Welfare Applications  TT8: Advanced Control Theory  Prof. Tom Oomen  Prof. Satoshi Komada  Prof. Hyungbo Shim  Prof. Kenta Seki  Prof. Naoki Motoi  Dr. Masato Tanaka	Session Room 1 (1204)  Session Room 2 (1205)  Session Room 3 (1208)  Session Room 3 (1208)  TTP: Rehabilitation and Welfare Applications  TTP: Advanced Control Theory  Prof. Tom Oomen  Prof. Satoshi Komada  Prof. Hyungbo Shim  Prof. Nacki Motoi  Dr. Masato Tanaka  Title  First Autor  Title  First Autor  Title  Takenori Atsumi (Chiba Institute of Technology)  Takenori Atsumi (Chiba Institute of Technology)  TTP-1  Study on control of power assist device in tendon driven mechanism using elastic element  Takashi Fuyuki (Mie University)  TTB-1  Acoustic Impedance Control for Cenerating Virtual Wall  TTB-1  Acoustic Impedance Control for Cenerating Virtual Wall  TTB-1  Acoustic Impedance Control for Cenerating Virtual Wall  TTB-1  Tomohiro Usami (Mie University)  TTB-2  Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method  Tomohiro Usami (Mie University)  TTP-3  Postural Control Experiments for 3D Inverted Pendulum Using Wearable-CMG  A study on PWM-type input systems: Ability of multiple pulses to generate arbitrary vectors and University)  Masayasu Suzuki (Utsunomiya University)  TTP-4  Analysis of Adaptive Controller on Oligitated Controller on Bilateral Controller on Bilateral Controller on Bilateral Controller Systems: Ability of multiple pulses to generate arbitrary vectors and University)  TTR-4  Analysis of Adaptive Controller on Bilateral Controller on Bilateral Controller System for Bilateral Controller on Oligon System for Bilateral Controller on Oligon System for Bilateral Controller on Oligon System for
IS1: High Precision Motion Control in Mechatronic Systems  TT7: Rehabilitation and Welfare Applications  TT8: Advanced Control Theory  Prof. Tom Oomen  Prof. Kenta Seki  Prof. Naoki Motoi  TT8: Advanced Control Theory  Prof. Hyungbo Shim  Dr. Masato Tanaka	IS1: High Precision Motion Control in Mechatronic Systems   TT7: Rehabilitation and Welfare Applications   TT8: Advanced Control Theory
Prof. Tom Oomen Prof. Satoshi Komada Prof. Hyungbo Shim Prof. Kenta Seki Prof. Naoki Motoi Dr. Masato Tanaka	Prof. Tom Oomen Prof. Satoshi Komada Prof. Hyungbo Shim  Prof. Naoki Motoi Dr. Masato Tanaka  Title First Autor Title First Autor  Title Acoustic Impedance Control for Generating Virtual Wall  Title Acoustic Impedance Control for Generating Virtual Wall  Title First Autor  Title
Prof. Kenta Seki Prof. Naoki Motoi Dr. Masato Tanaka	Prof. Kenta Seki Prof. Naoki Motoi Dr. Masato Tanaka  Title First Autor Title First Autor  IS1-1 Sampled-Data Positioning Control Techniques for HDDs Takenori Atsumi (Chiba Institute of Technology)  Tr7-1 Study on control of power assist device in tendon driven mechanism using elastic element  Tr7-2 Investigation of healing by vibration aided Dynamic Kalman Filter and Its Application to Motion Control  IS1-3 Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method  A study on PWM-type input systems: Ability of multiple pulses to generate arbitrary vectors and University)  Masayasu Suzuki (Utsunomiya University)  Tr7-4 Analysis of Adaptive Controller on Object Coordination System for Burch 2007 (Mile University)  Tr8-1 First Autor  Tr8-1 Acoustic Impedance Control of Generating Virtual Wall  Tr8-2 Design of Weighting Function for Hostopy Chapter Placement Tr8-2 Design of Weighting Function for Hostopy Placement Method Using Frequency Responses for stable MIMO plant  Tr8-2 Tuning for Sensitivity Mimimization Using InputOutput Data  Tr8-3 Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method  Tr8-3 A study on PWM-type input systems: Ability of multiple pulses to generate arbitrary vectors and University)  Tr8-4 Stability Orderion Munemitsu Date (Mie University)  Tr8-4 Stability Orderion on Nyquist Stability Order
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Estimation Using Acceleration—aided Dynamic Kalman Filter and Its Application to Motion Control    S1-2   Estimation Using Acceleration—aided Dynamic Kalman Filter and Its Application to Motion Control   S1-3   Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method   T17-2   T17-3   Postural Control Experiments for 3D Inverted Pendulum Using Wearable—CMG   Hiroki Oya (Yokohama National University)   T18-3   Fully Parametrized How Controller Tuning for Sensitivity Minimization Using Input Output Data   T18-3   Stability Guaranteed NCbT Based on Nyquist Stability Criterion   T18-4   Stability Guaranteed NCbT Based on Nyquist Stability Criterion   T18-5   Review on multirate feedforward: model—inverse feedforward control on Takko)   T17-5   Trajectory Planning and Motion Control Reperiments for 3D Inverted Pendulum Using Wearable—CMG   T18-5   T18-5	
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IS1-1   Sampled-Data Positioning Control   Takenori Atsumi (Chiba Institute of TT7-1   device in tendon driven mechanism   Takashi Fuyuki (Mie University)   TT8-1   Acoustic Impedance Control for   Ejji Yoko	aided Dynamic Kalman Filter and Its Application to Motion Control  IS1-3 Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method  IS1-4 A study on PWM-type input systems: Ability of multiple pulses to generate arbitrary vectors and University)  IS1-4 IS1-4 IS1-4 Stability of multiple pulses to generate arbitrary vectors and University)  IS1-4 IS1-4 IS1-4 INT-4
151-1   Techniques for HDDs   Technology)   117-1   device in tendon driven mechanism   Takashi Fuyuki (Mie University)   118-1   Generating Virtual Wall   Eiji Yokota (Kelo University)	ISI-2 Estimation Using Acceleration—aided Dynamic Kalman Filter and Its Application to Motion Control    ISI-2   Estimation Using Acceleration—aided Dynamic Kalman Filter and Its Application to Motion Control   ISI-3   Vibration Suppression by Pole Zero Cancellation with Limited Pole Placement Method   TT7-3   Postural Control Experiments for 3D Inverted Pendulum Using Wearable—CMG   TT8-2   Fully Parametrized H∞ Controller Tuning for Sensitivity Minimization Using InputOutput Data   TT8-3   Tuning for Sensitivity Minimization Using InputOutput Data   TT8-4   Stability of multiple pulses to generate arbitrary vectors and University)   TT8-4   Stability Guaranteed NCbT Based on Nyquist Stability Criterion   Munemitsu Date (Mie University)   TT8-4   Munemitsu Date (Mie University)   TT8-4   Stability Grierion on Nyquist Stability Criterion   Munemitsu Date (Mie University)   TT8-4   Stability Criterion   Stability Criterio
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