

Impedance Minimizing Control for an End-Effector Upper Limb Rehabilitation Robot

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This paper presents an impedance minimizing control (IMC) for an end-effector upper-limb rehabilitation robot. IMC allows the robot to achieve a desired impedance model by applying assistive torque. IMC showed 4.7 times less impedance compared to the case without IMC through an experiment applied to our end-effector upper limb rehabilitation robot.