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in the figure 16 by using system monitor and print the table 2, you can see that the calibration of the system is not so good, the noise sensors and the compensation table are not good, as the over-percentage of the system is in a high speed. that's why it is necessary to perform a good calibration of the system of operation and constant implementation of the compensation table to achieve the performance of the system is better. in figure 17 the sub-impulse of the system is presented, which is pretty good, however, the system of operation calibration and the compensation table is not good, and that's why the sub-impulse of the system is not good. thus, in this case, most interesting to address the optimal control and the future sections, the topic of magnetic levitation system is oriented towards the need to reduce the production costs, since the production of magnetic levitation system can be one of the most important factors in the production of the equipment [10, 11, 12, 18]. the use of advanced control techniques such as optimal control can reduce the production cost and time of realization of the levitation system. in addition to that, the use of optimal control techniques can contribute to the reduction of the environmental impact of the equipment. the following section is the introduction of the optimal control of the magnetic levitation system, and the study of its main advantages and disadvantages. the main characteristics of magnetic levitation systems are summarized, and a description of the modeling as a control system, the description of the objectives, the optimization and implementation of the control design and the real implementation of the optimal control. the purpose is to analyze the relevance of the use of the optimal control techniques in magnetic levitation systems as well as to study its main advantages and disadvantages.

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in this view, we developed a robotic hexapod robot for load bearing actuation. robots in gait generation are specially adapted when exposed to the outside environment. the actuator itself may be active and for example, may use hydraulic, electric or pneumatic actuation. so, the gait contains a combination of the original three gait locomotor actuations to create a new gait. a sensor such as an ultrasonic or infrared one, is typically included in the robot and responds by various degrees of ease of acquisition and processing. this makes the application of robots for off-road propulsion by land vehicles on rough terrains more possible. as such, we present a novel hexapod robot with a combination of three separate gaits that are valid in a spatial pattern that enables omnidirectional locomotion. first, we present a single gait, the so-called 2+1 gait, as a stand alone system. we represent a more versatile system for our gait generation as a three gait locomotor unit, where we combine the two locomotor modes with the 1+0 stance. hence, the 1+0 gait is the gait that has the stationary stance, which may be handled in most of the self-propelled robots. the motor and robot actuator have to be carefully designed in order to increase the deformation. the actuator must also be designed in a way to be able to recover from the deformation and be able to resume its original shape. a study on this is presented in the paper. the requirements were analyzed and divided into different aspects. a simulation example is presented to prove the design process. in this perspective, we have considered the reduction of the number of transducer bars (bar or rods) required to form sensor arrays. the sensor array is mainly used for pressure measurement on the foot sole, and pressure data from pressure sensors on the sole can be acquired by a hydraulic cylinder, which will generate a reaction force on the sensor, which the sensor will measure. the combination of the pressure distribution on the sole of the foot and/or the vertical displacement of the sensor can be used to create a sensor array. the linear fitting of the output of the pressure sensor on the foot sole can be used to measure the pressure distribution on the foot sole, and the linear transformation of the output can be used to read the vertical displacement of the pressure sensors, in which the transformation output can be converted to the vertical displacement of the sensors by applying a correction factor. therefore, a sensor can be formed by a pressure sensor and its output is divided into two parts, which are the foot pressure distribution and the sensor vertical displacement. furthermore, it can be assumed that these elements are independent of each other, so each element’s data can be obtained separately. the number of transducer bars is reduced, because each sensor requires a bar to be added. a simulation test for the sensor array is presented to confirm that the sensor array can be formed by the reduced number of transducer bars. 5ec8ef588b