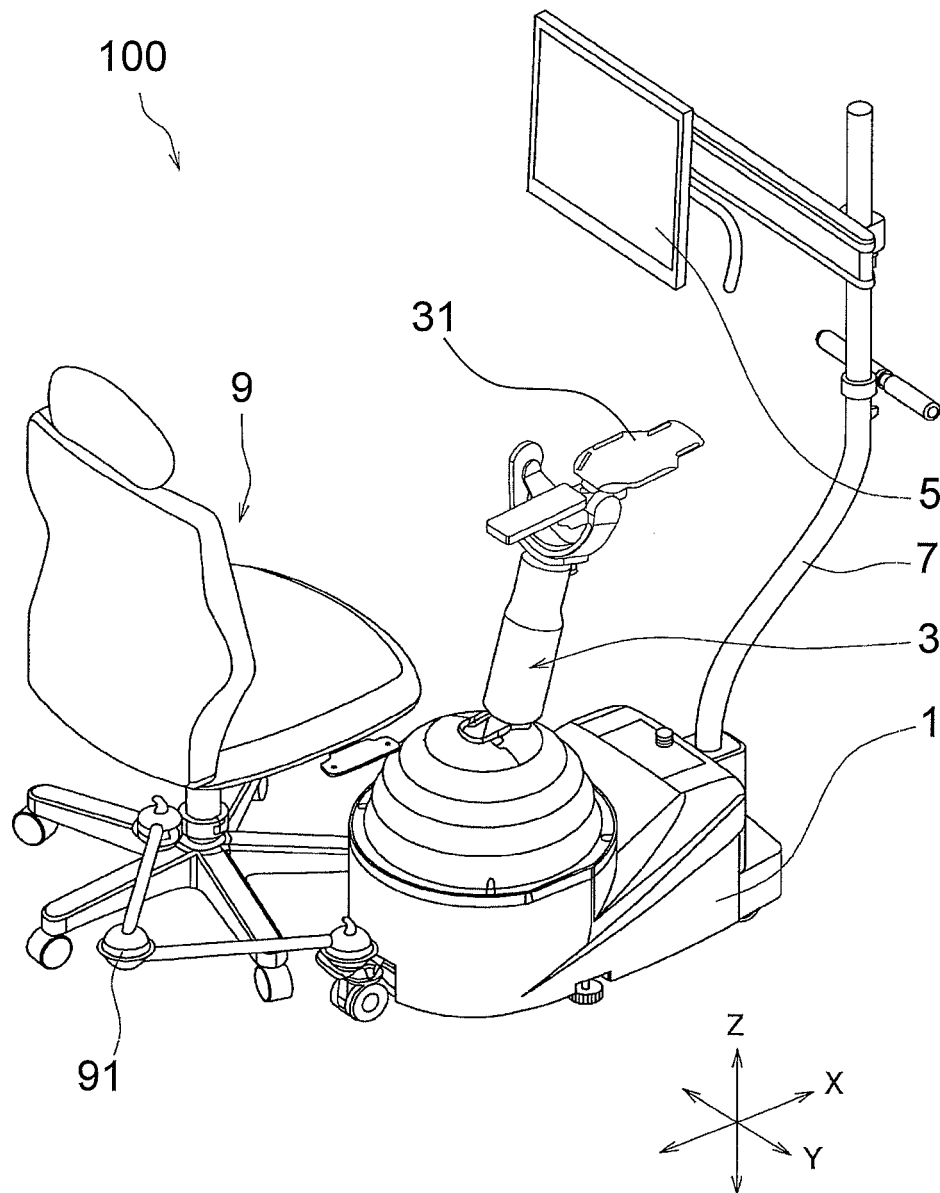
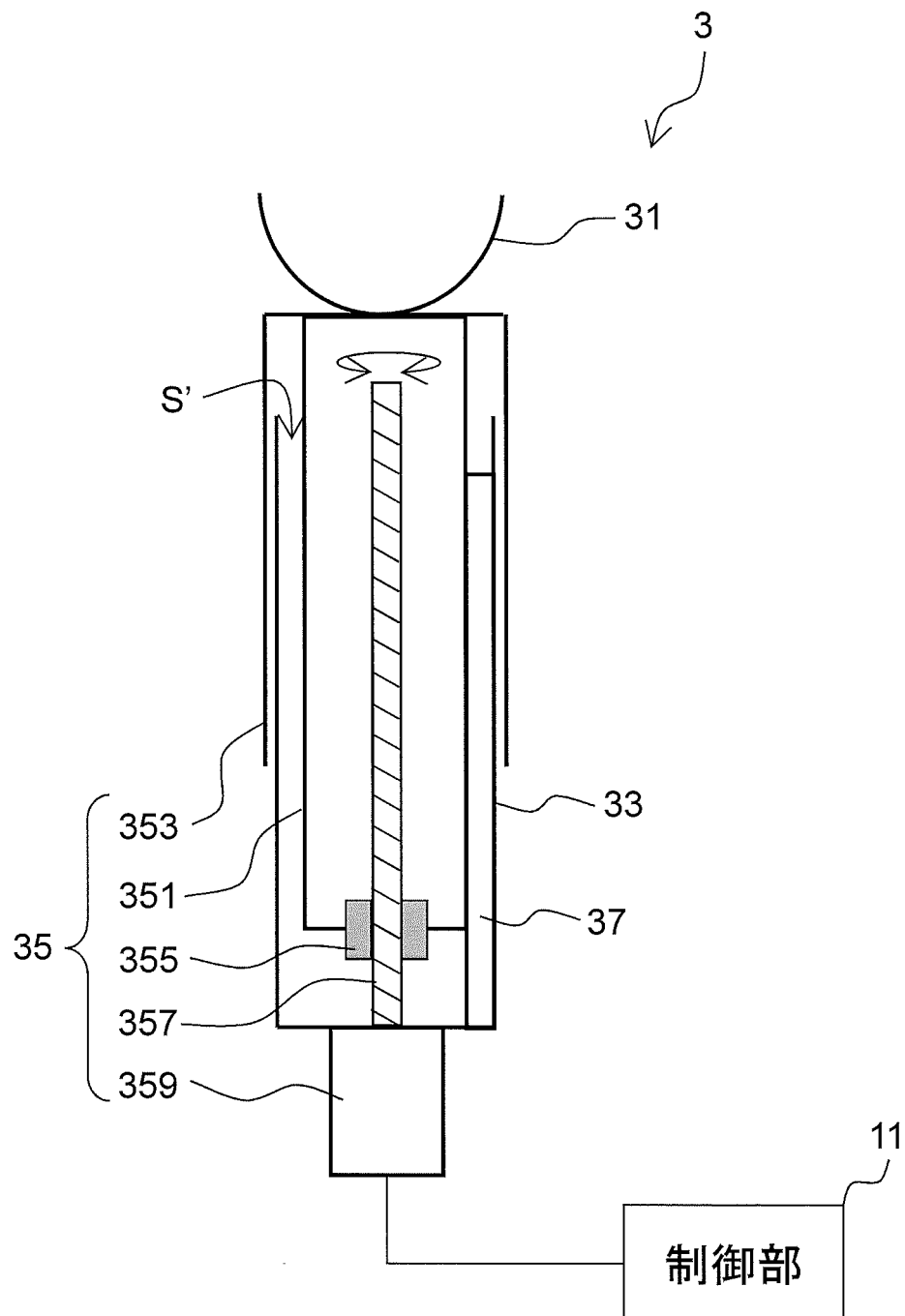


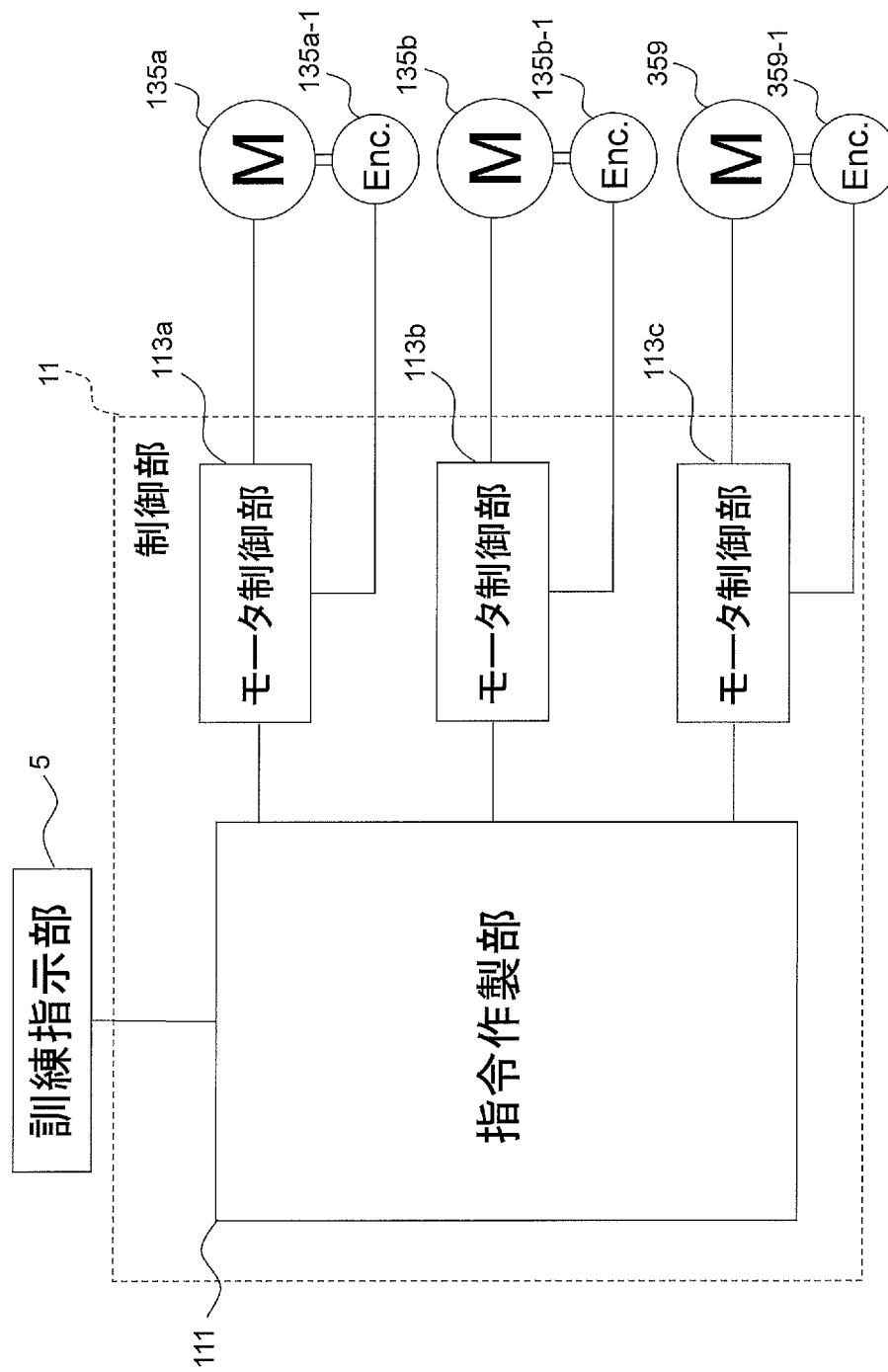
[図1]



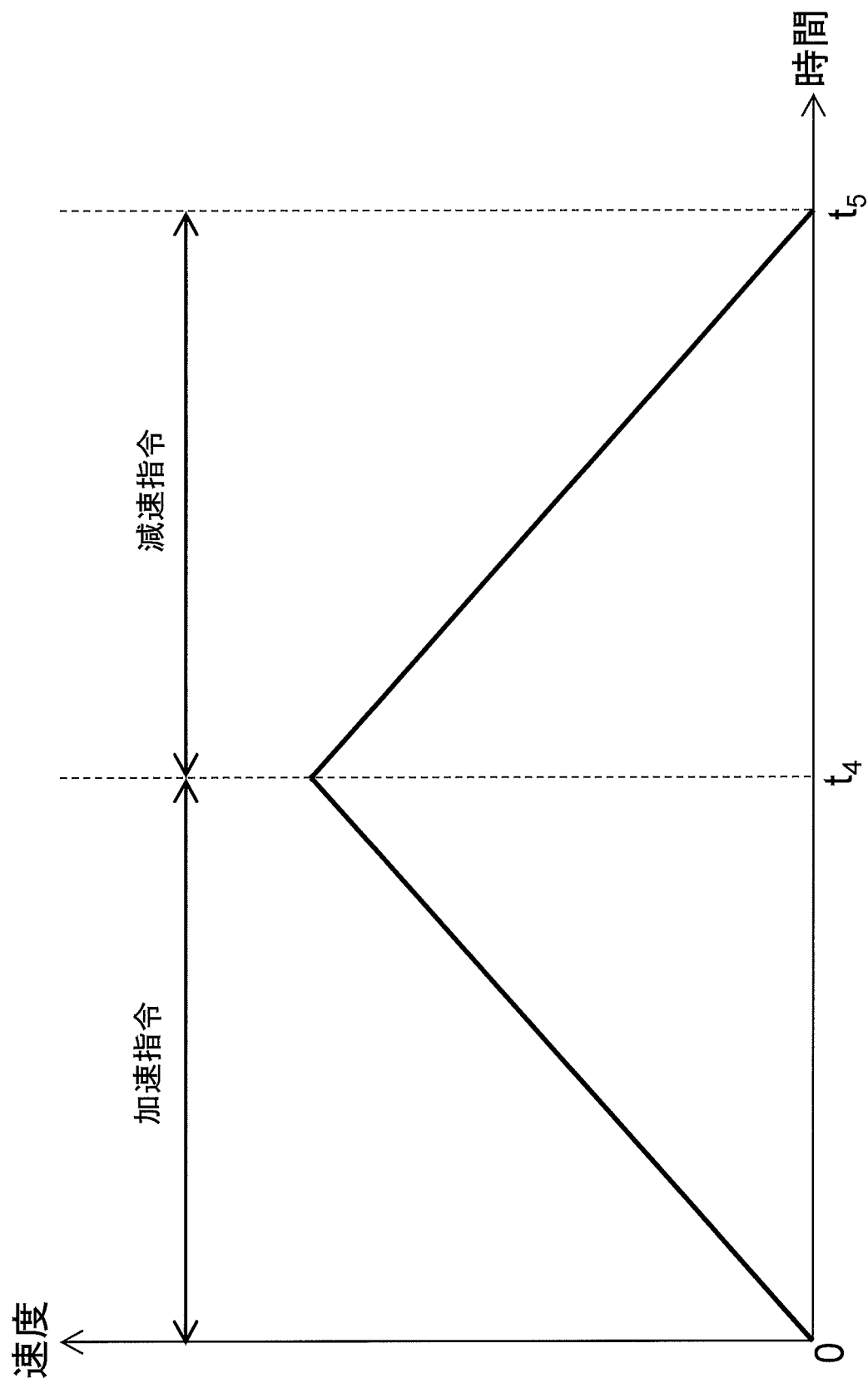
[図3]



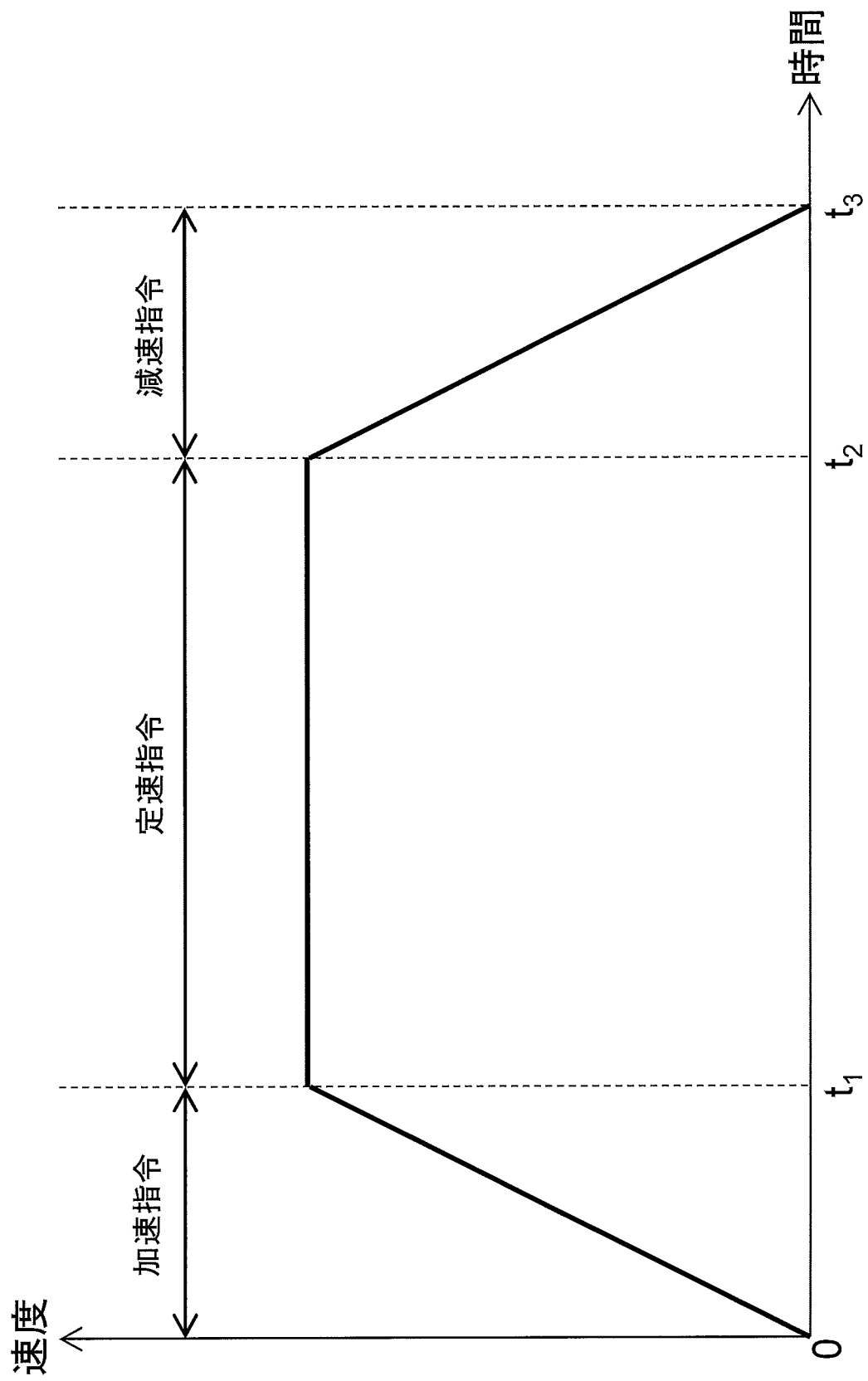
[図4]



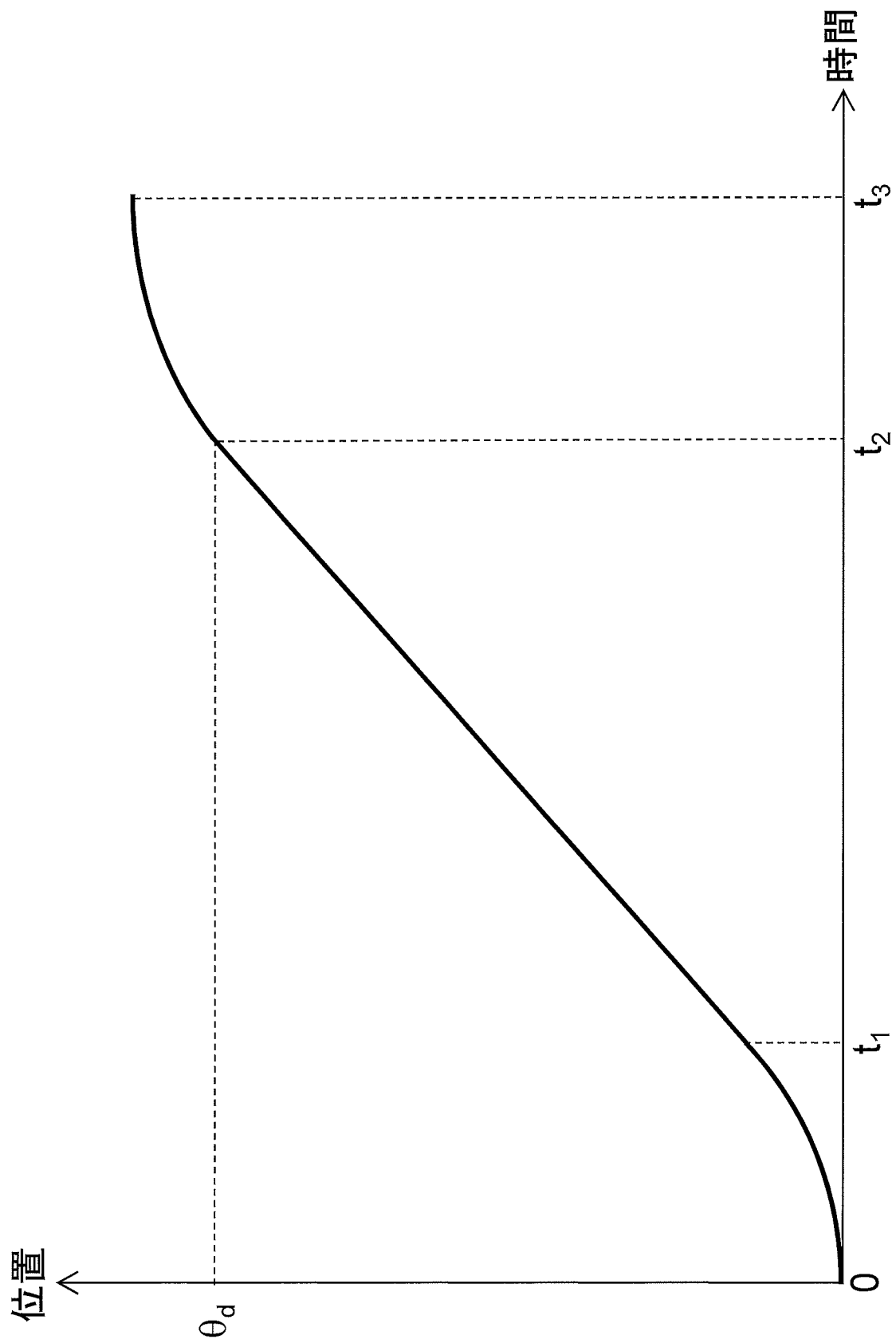
[図5A]



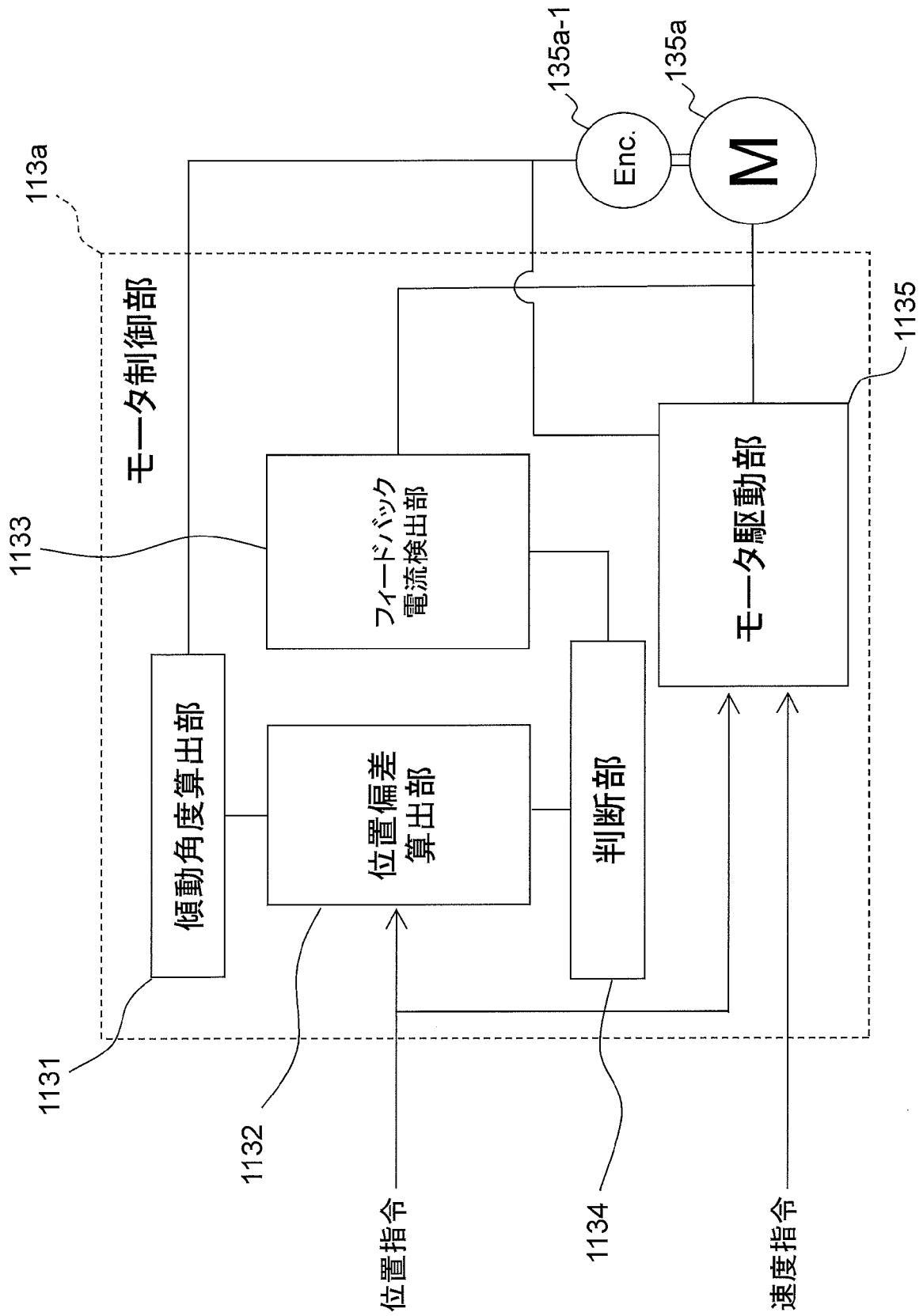
[図5B]



[図6]



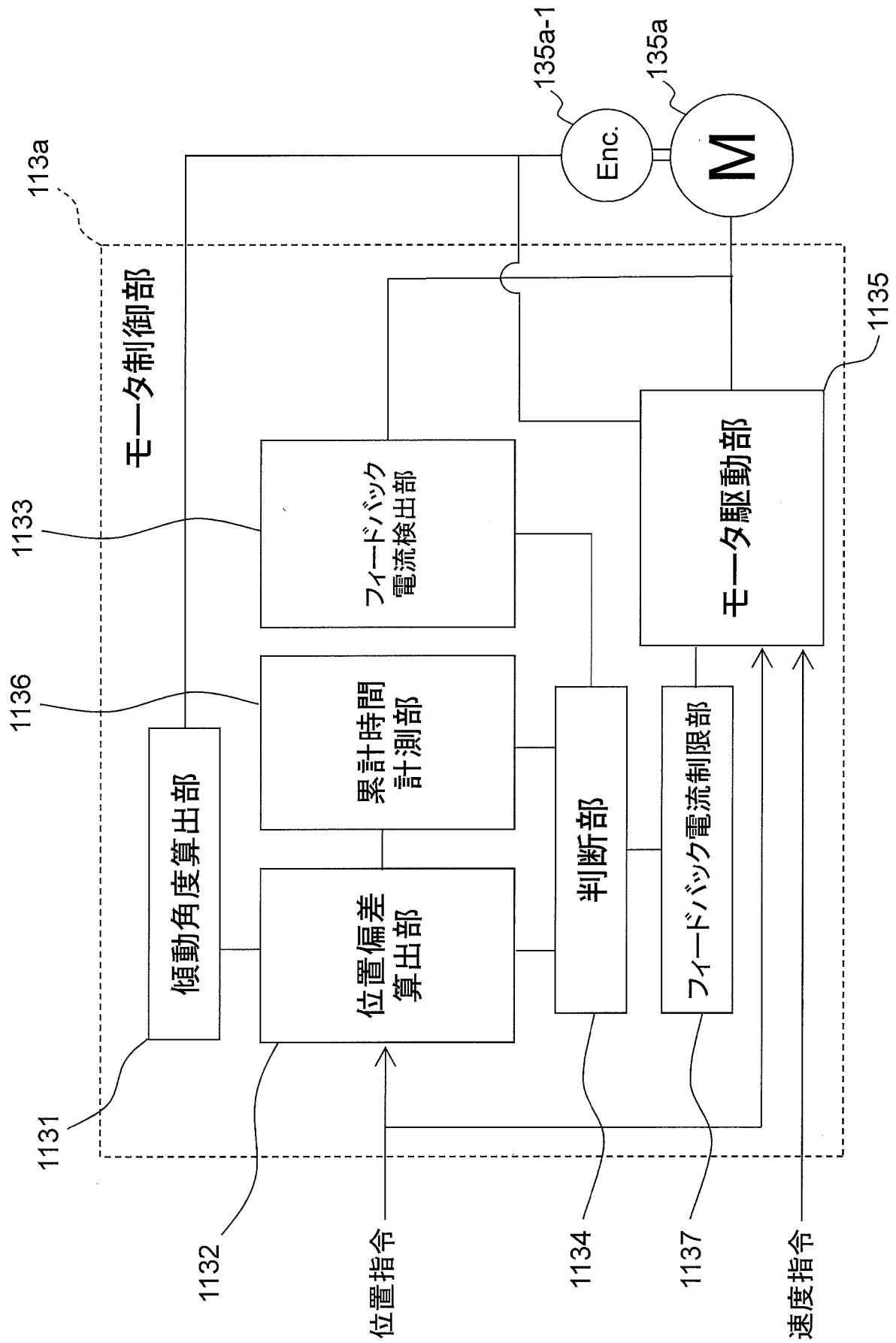
[図7A]



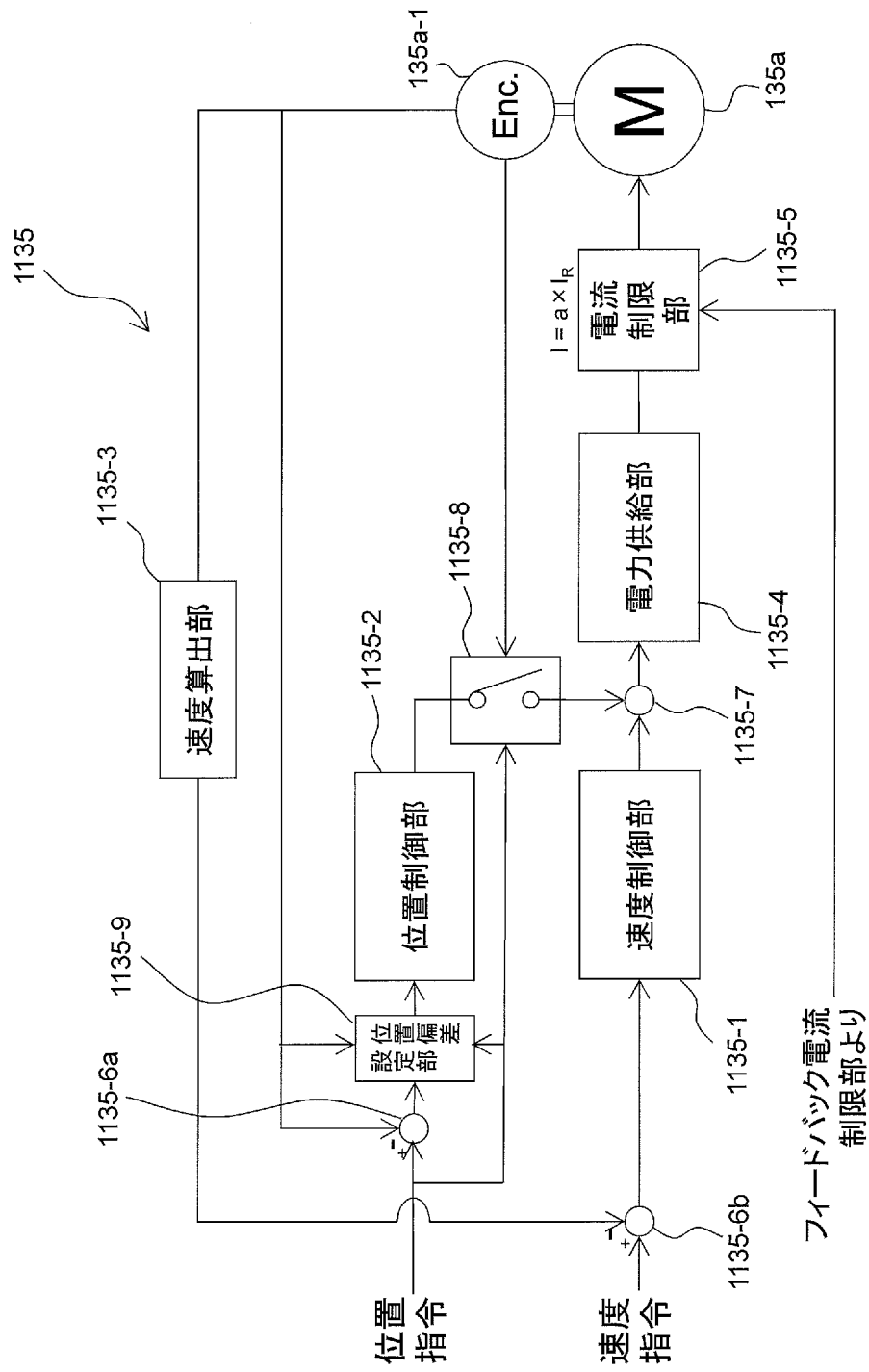
The diagram illustrates a motor control system (113a) with the following components and connections:

- Inputs:**
 - 位置指令 (Position Command):** Input to the **傾動角度算出部 (Tilting Angle Calculation Unit)** (1131).
 - 速度指令 (Velocity Command):** Input to the **判断部 (Judgment Unit)** (1134).
- Processing Units:**
 - 傾動角度算出部 (Tilting Angle Calculation Unit):** (1131) Receives the position command and outputs to the **位置偏差算出部 (Position Deviation Calculation Unit)** (1132).
 - 位置偏差算出部 (Position Deviation Calculation Unit):** (1132) Receives the position deviation and outputs to the **累計時間計測部 (Accumulated Time Measurement Unit)** (1136).
 - 累計時間計測部 (Accumulated Time Measurement Unit):** (1136) Receives the accumulated time and outputs to the **フィードバック電流検出部 (Feedback Current Detection Unit)** (1133).
 - 判断部 (Judgment Unit):** (1134) Receives the velocity command and outputs to the **モータ駆動部 (Motor Drive Unit)** (1135).
- Motor and Encoder:**
 - モータ駆動部 (Motor Drive Unit):** (1135) Receives the drive signal and outputs to the **モータ (Motor)** (M).
 - モータ (Motor):** (M) is connected to the **位置指令 (Position Command)** input.
 - エンコーダ (Encoder):** (Enc.) is connected to the **位置指令 (Position Command)** input.
- System Boundary:** The entire system is enclosed in a dashed box labeled **113a**.

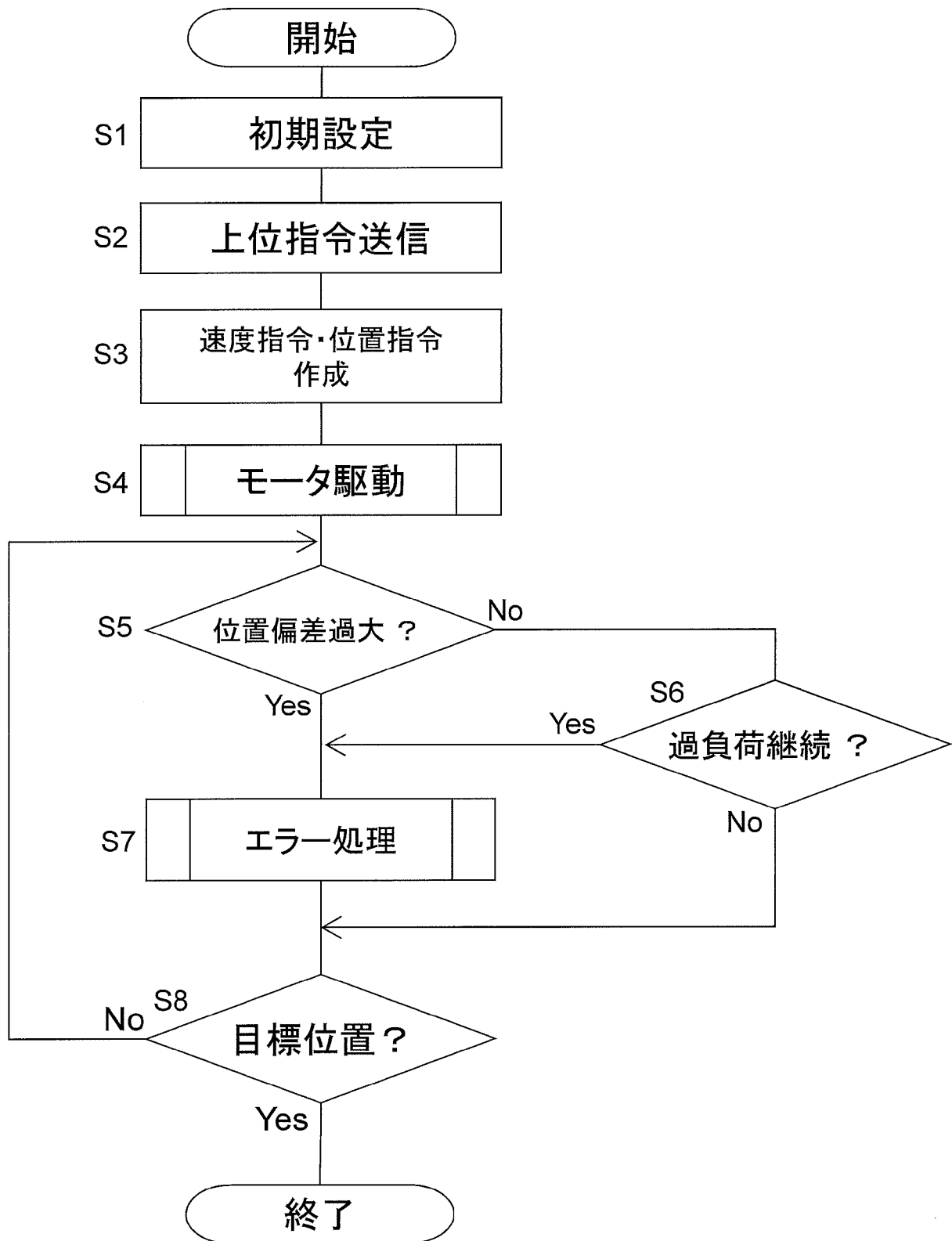
[図7C]



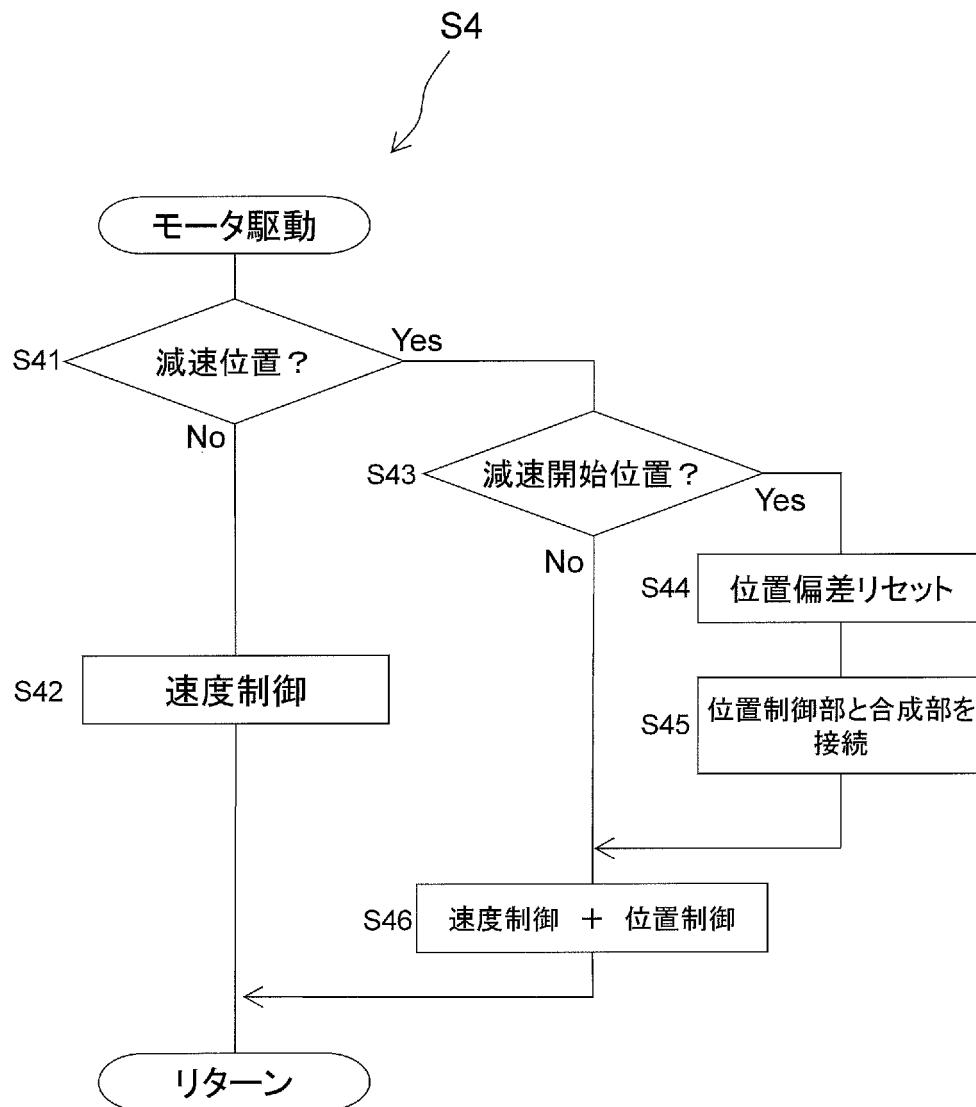
[図8]



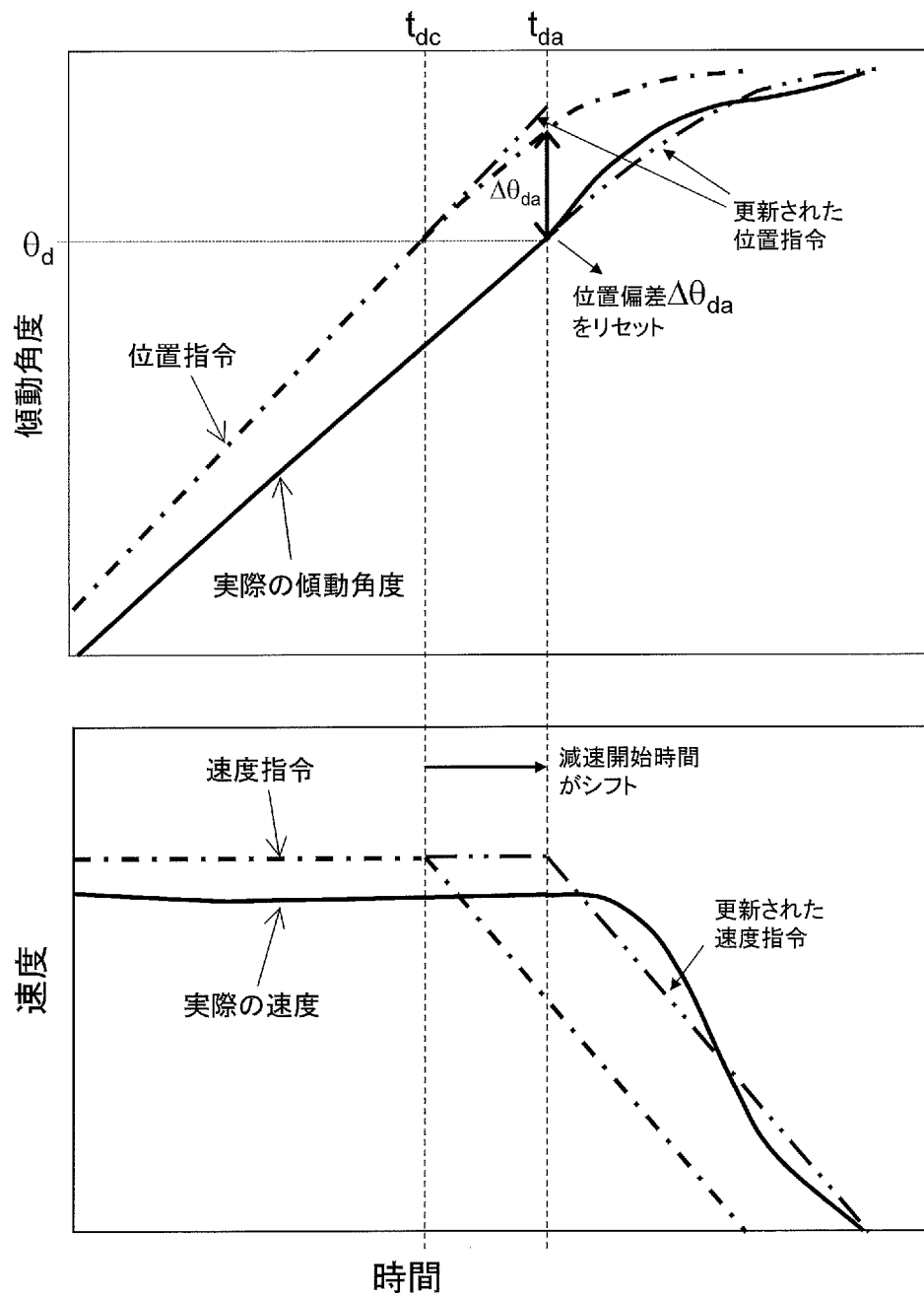
[図9]



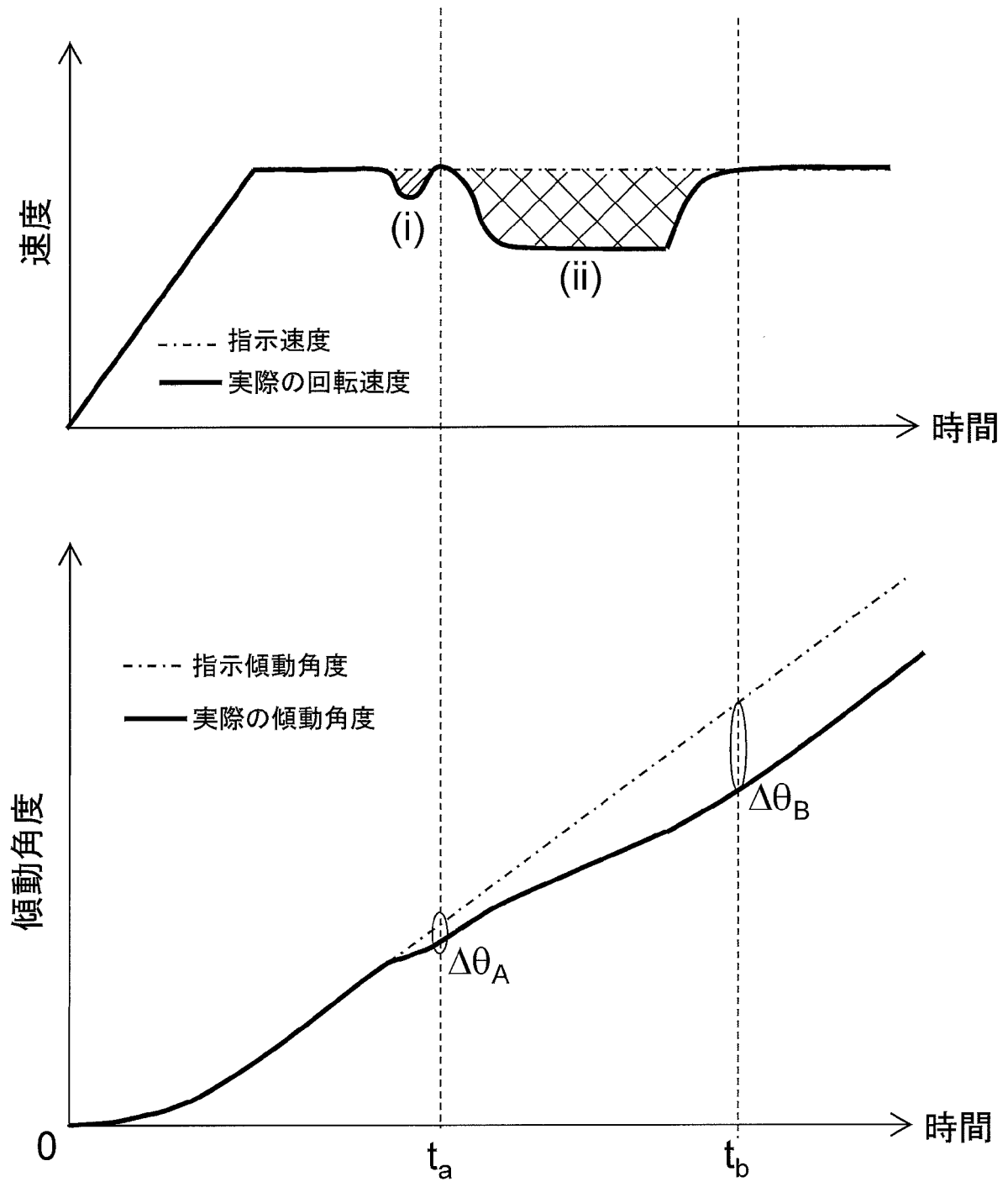
[図10]



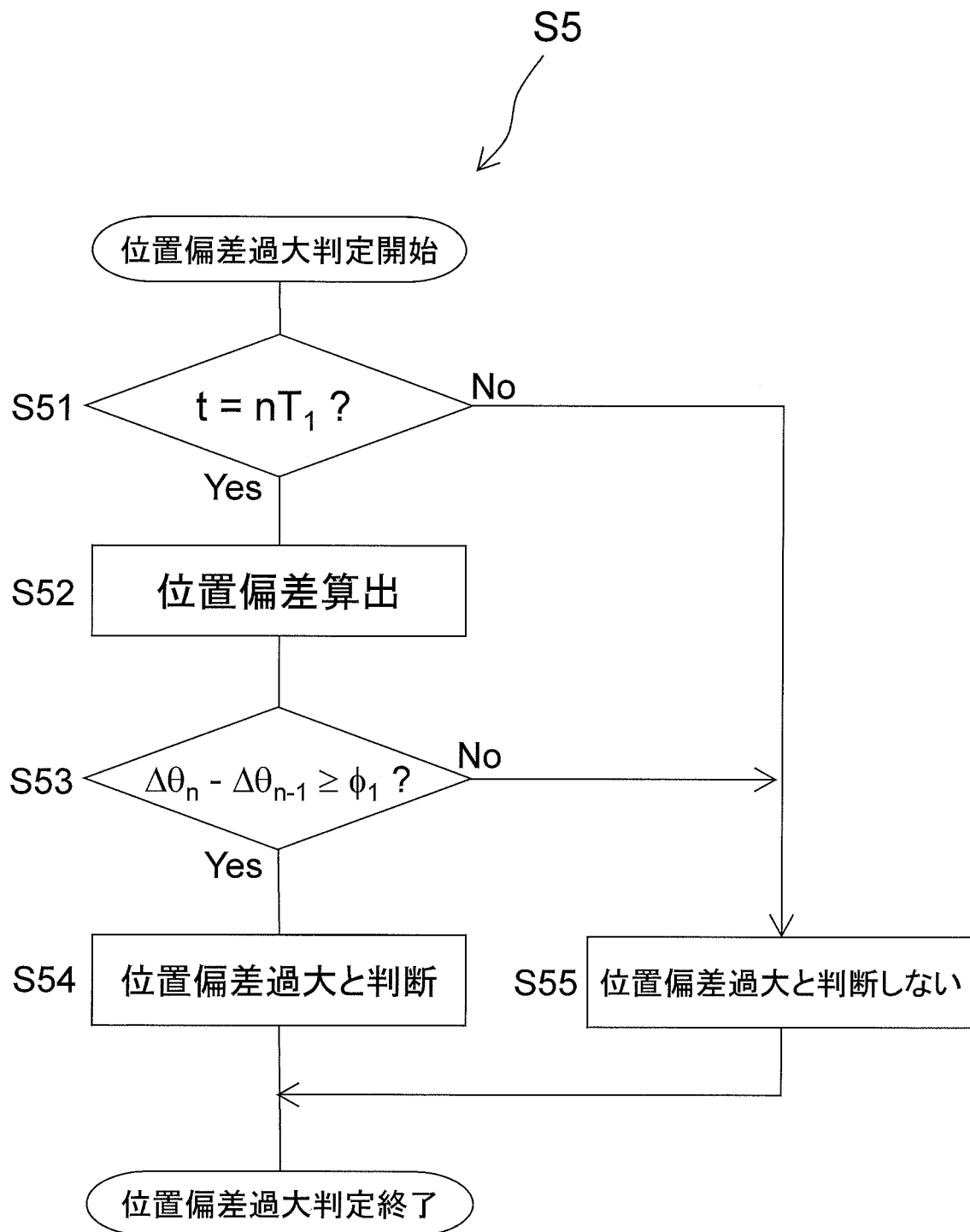
[図11]



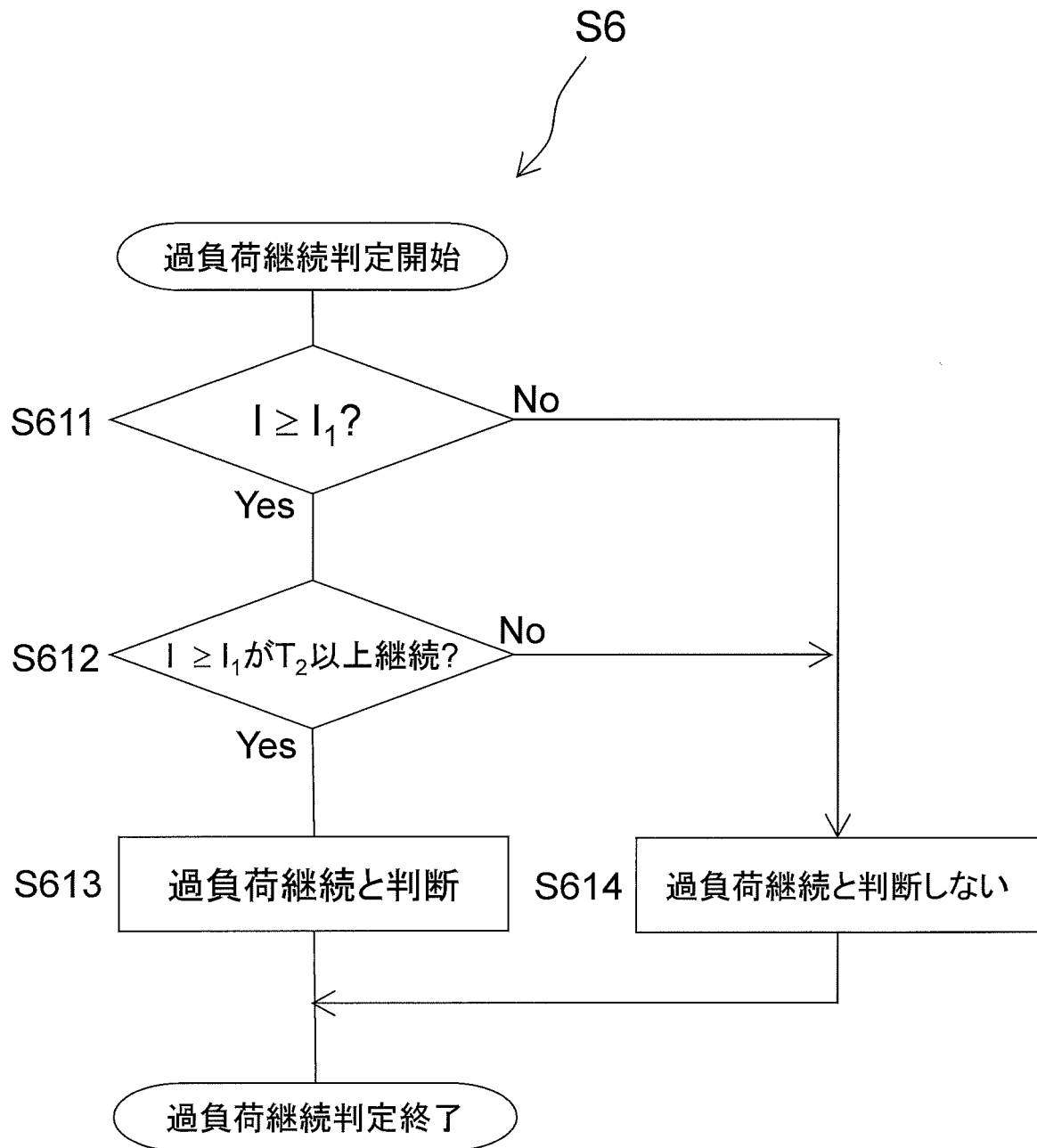
[図12]



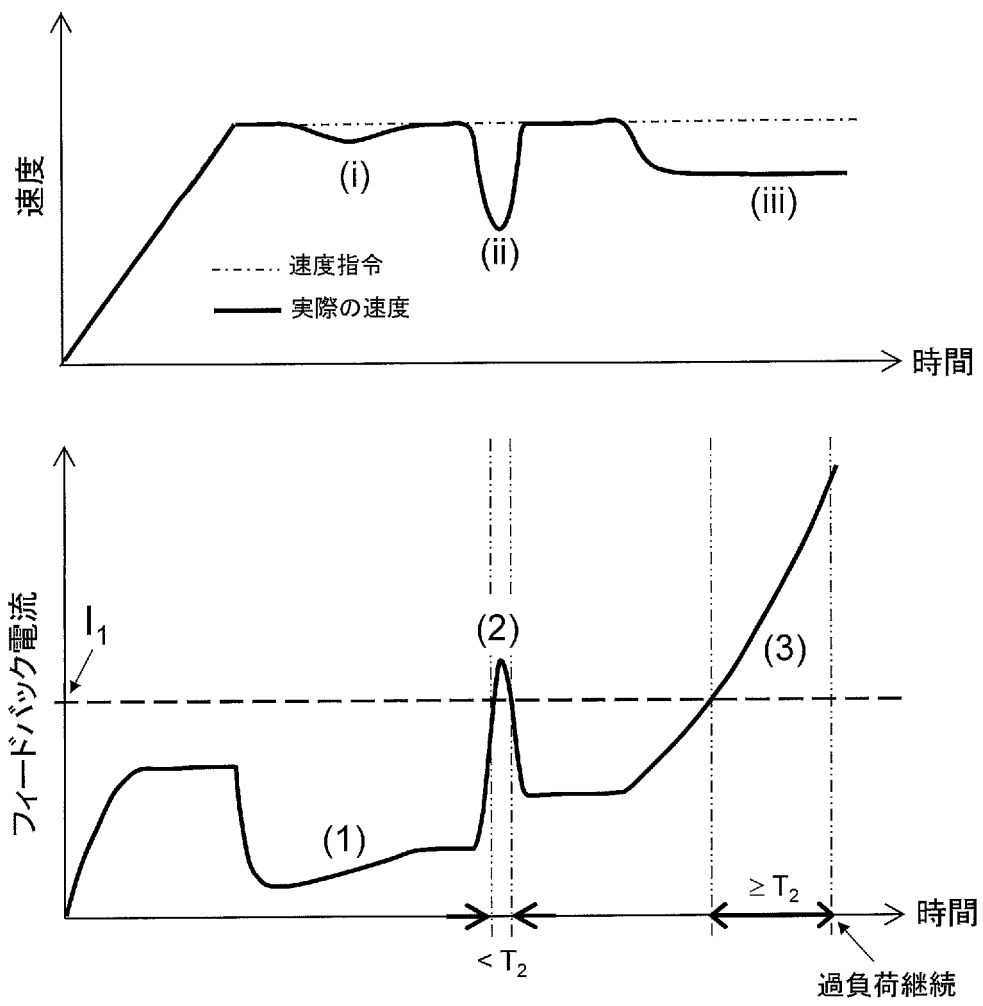
[図13]



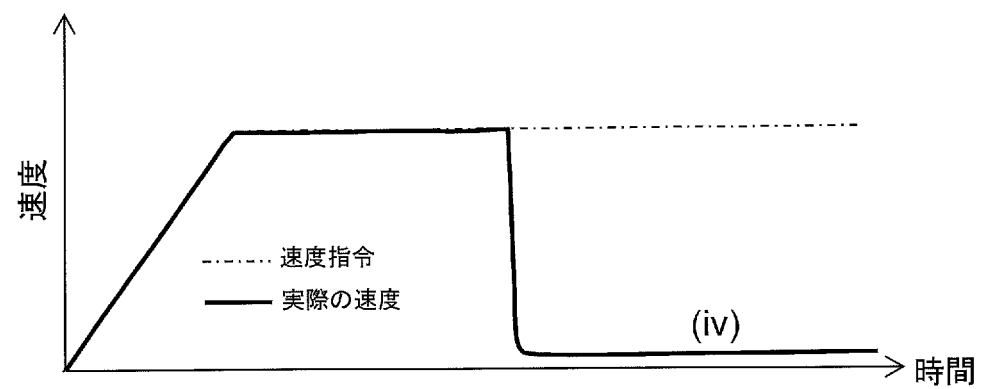
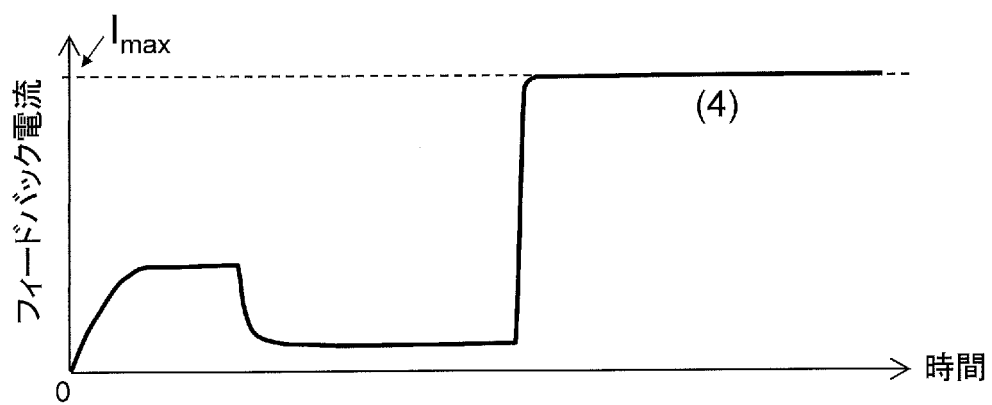
[図14]



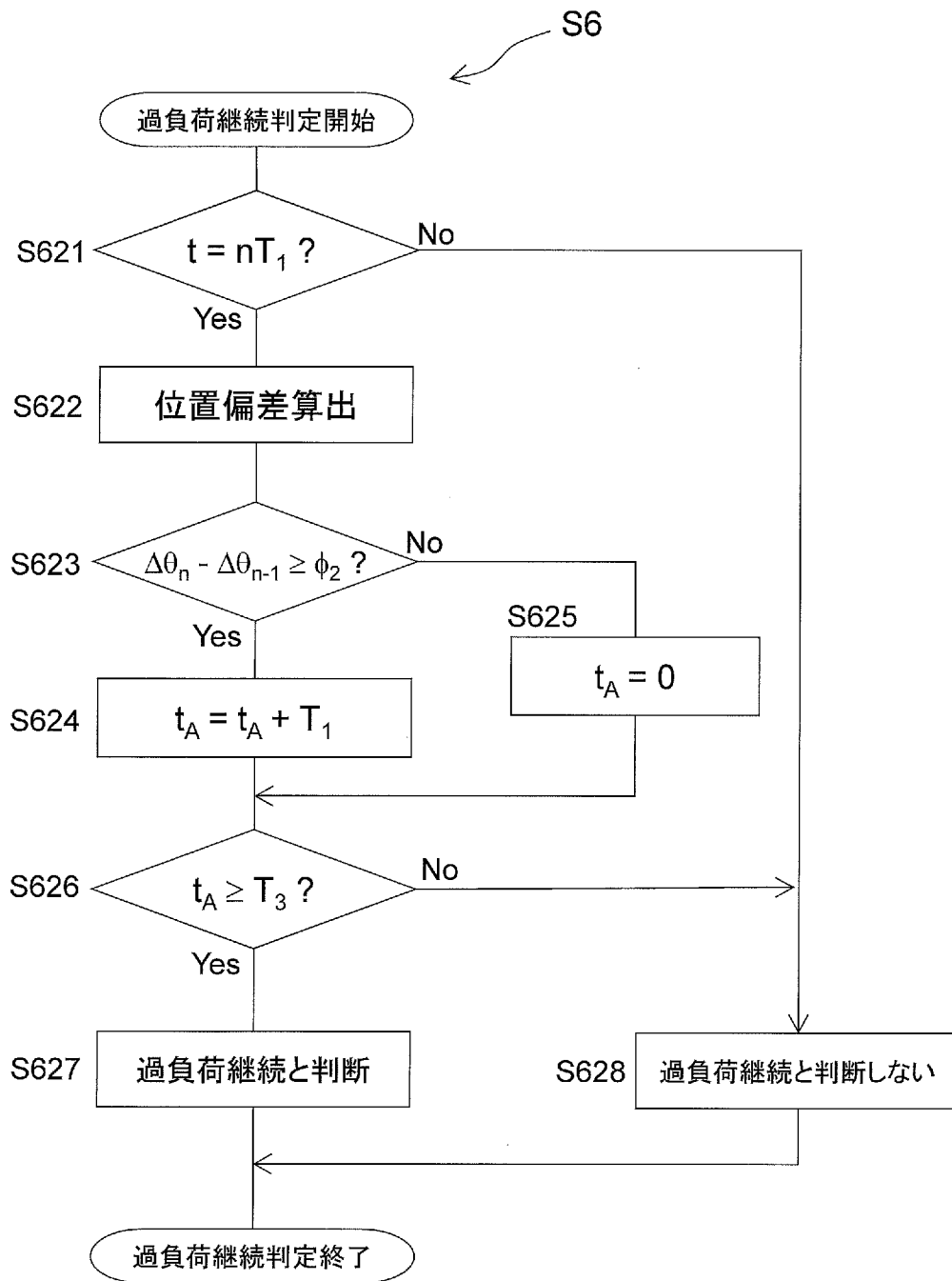
[図15]



[図16]



[図17]



[図18]

