

FIG. 1

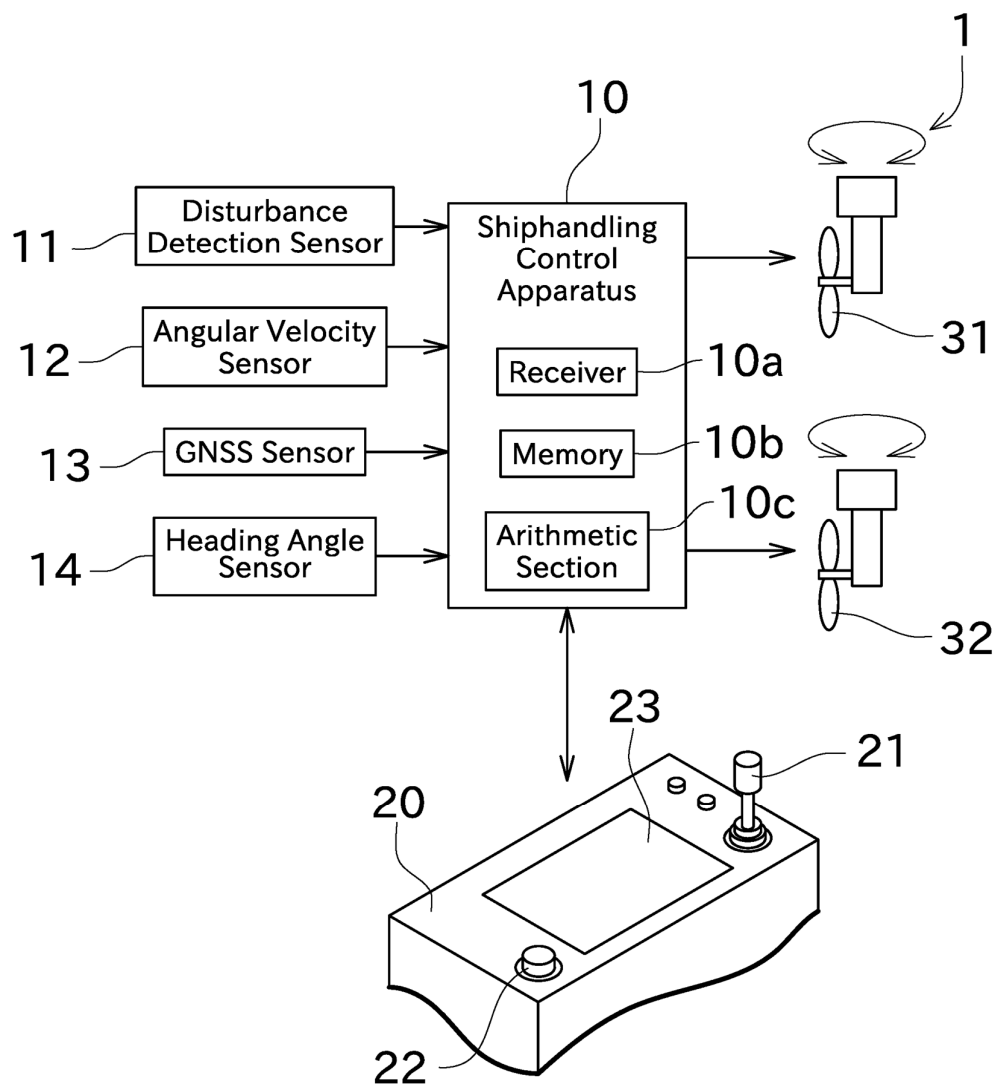
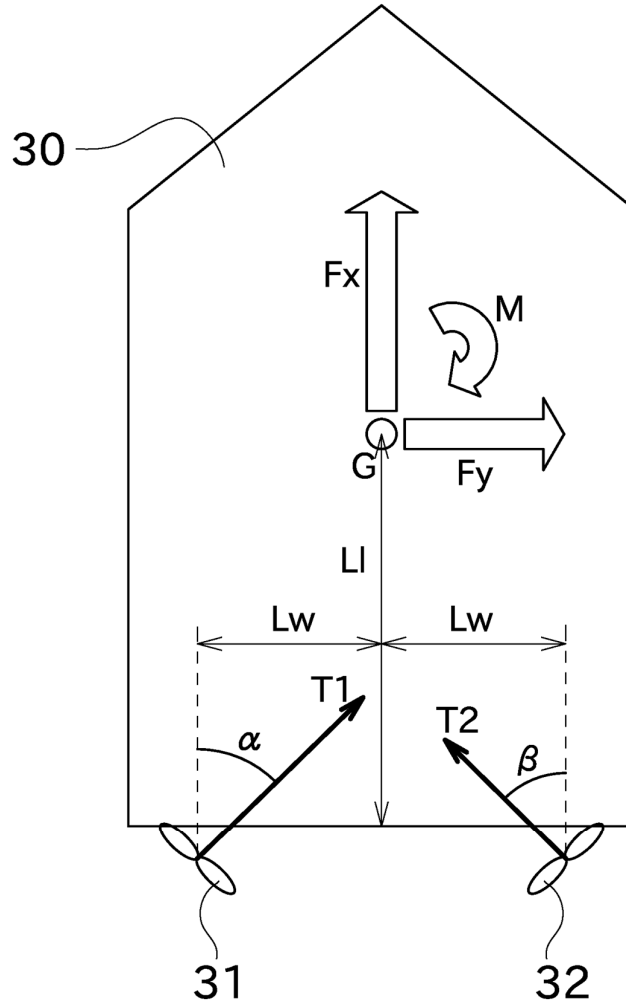


FIG. 2



$$F_x = T_1 \cdot \cos \alpha + T_2 \cdot \cos \beta \quad \dots (1)$$

$$F_y = T_1 \cdot \sin \alpha - T_2 \cdot \sin \beta \quad \dots (2)$$

$$M = -L_I \cdot T_1 \cdot \sin \alpha + L_w \cdot T_1 \cdot \cos \alpha + L_I \cdot T_2 \cdot \sin \beta - L_w \cdot T_2 \cdot \cos \beta \quad \dots (3)$$

FIG. 3

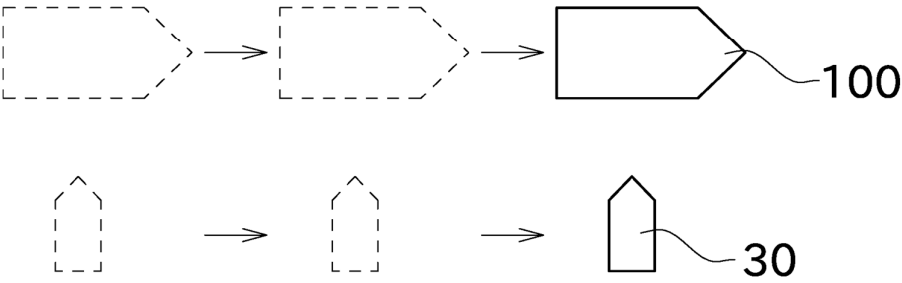


FIG. 4

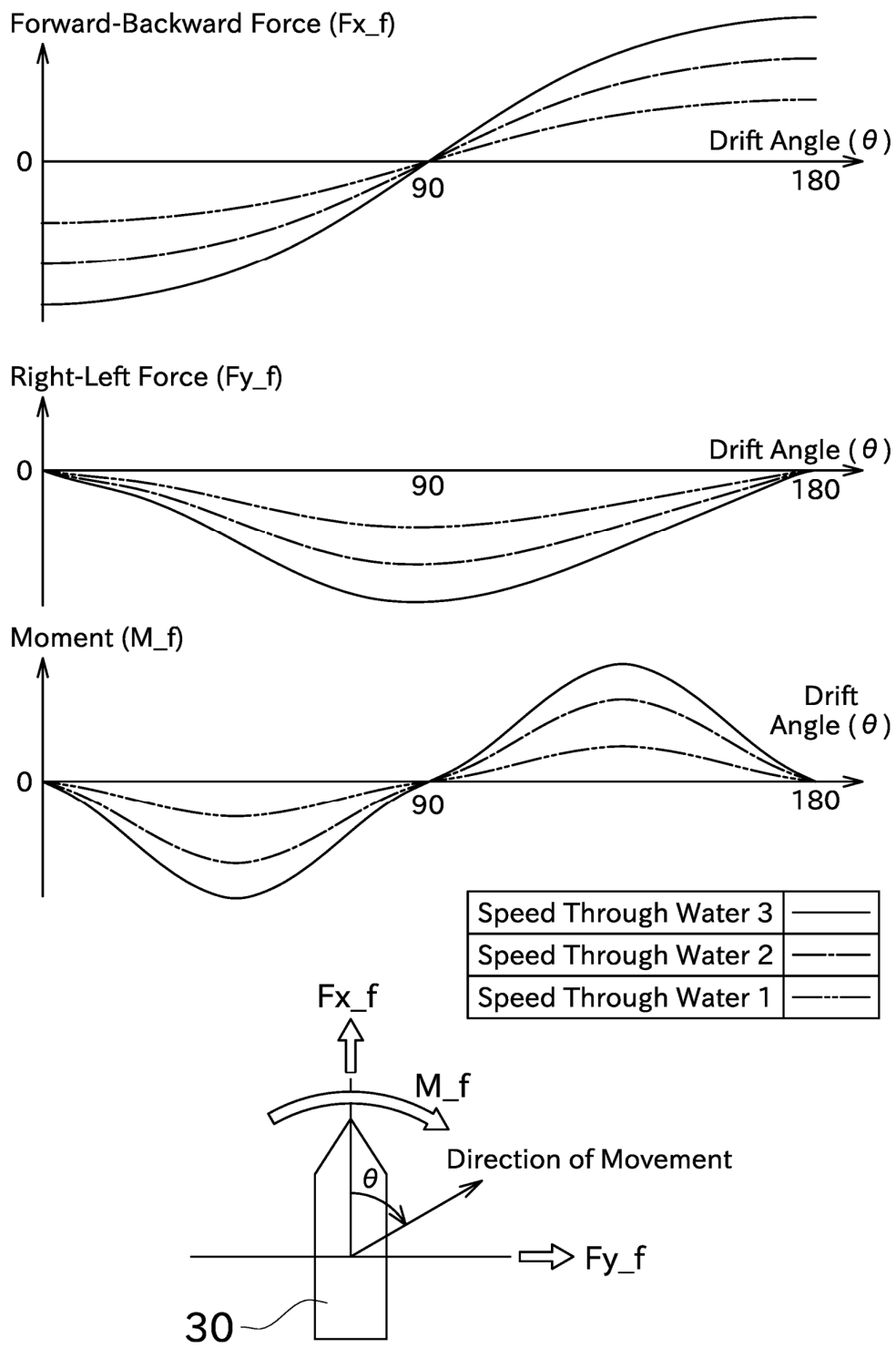


FIG. 5

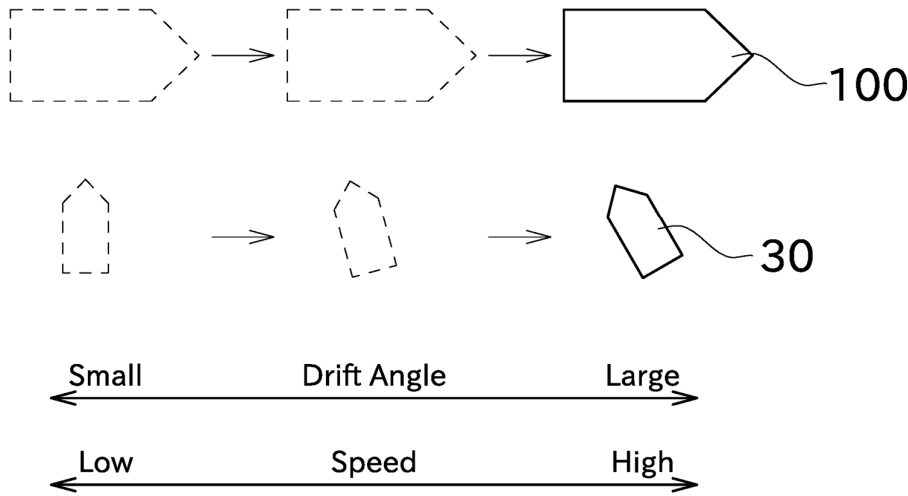
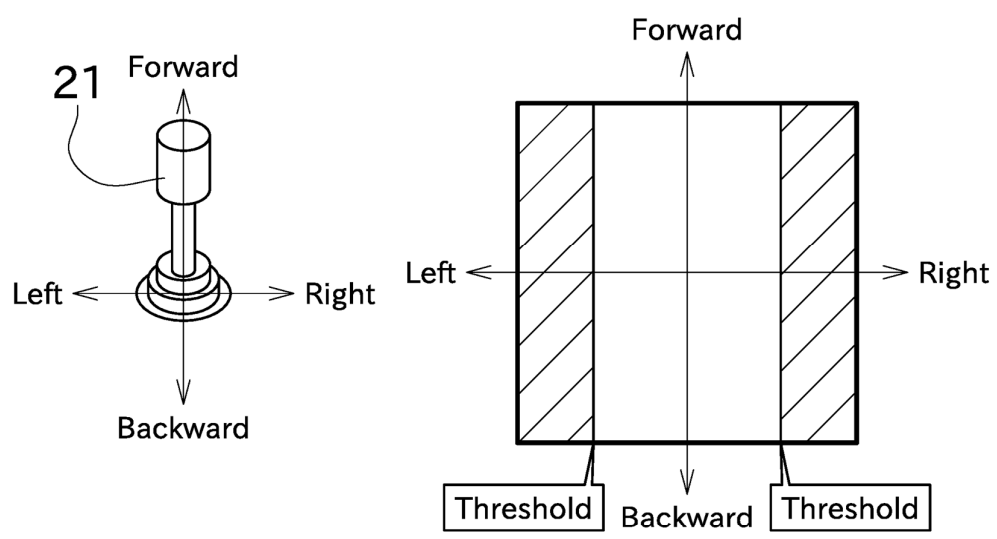
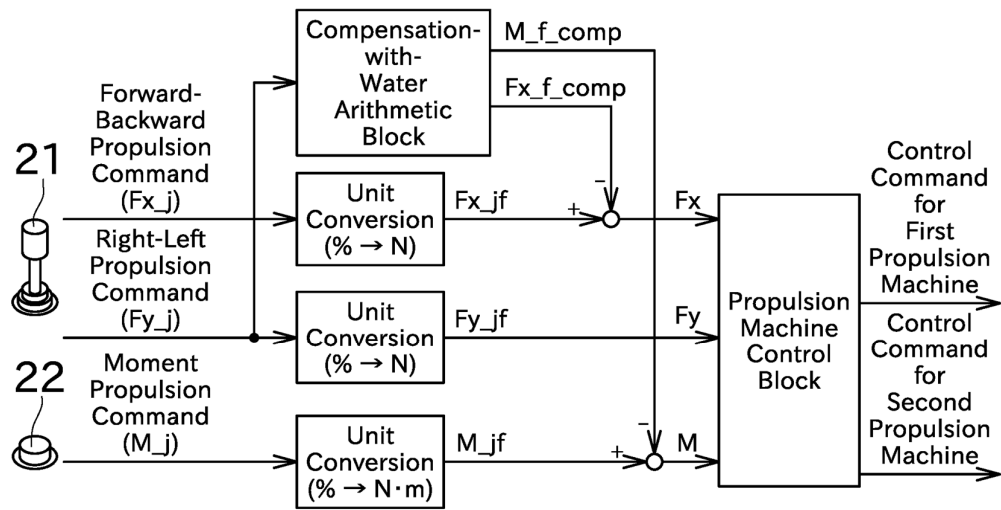


FIG. 6



Joystick Operable Range	
Range for instructing High-Speed Lateral Movement Mode	

FIG. 7



$$Fx = Fx_{jf} - Fx_{f_comp}$$

$$Fy = Fy_{jf}$$

$$M = M_{jf} - M_{f_comp}$$

FIG. 8

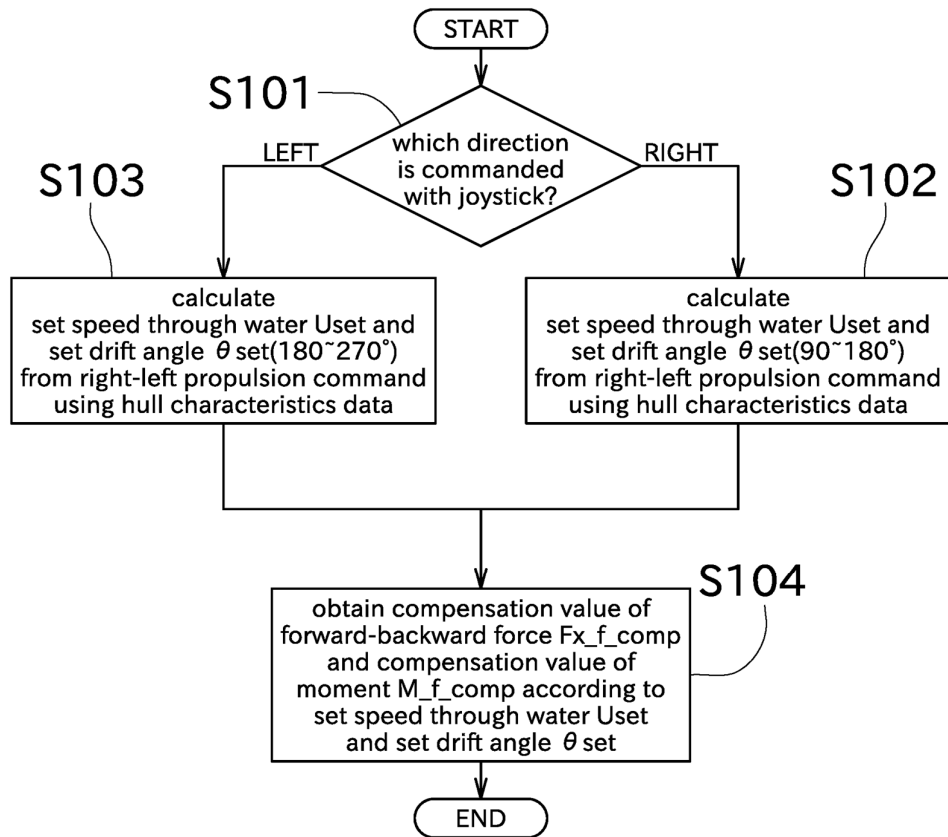


FIG. 9

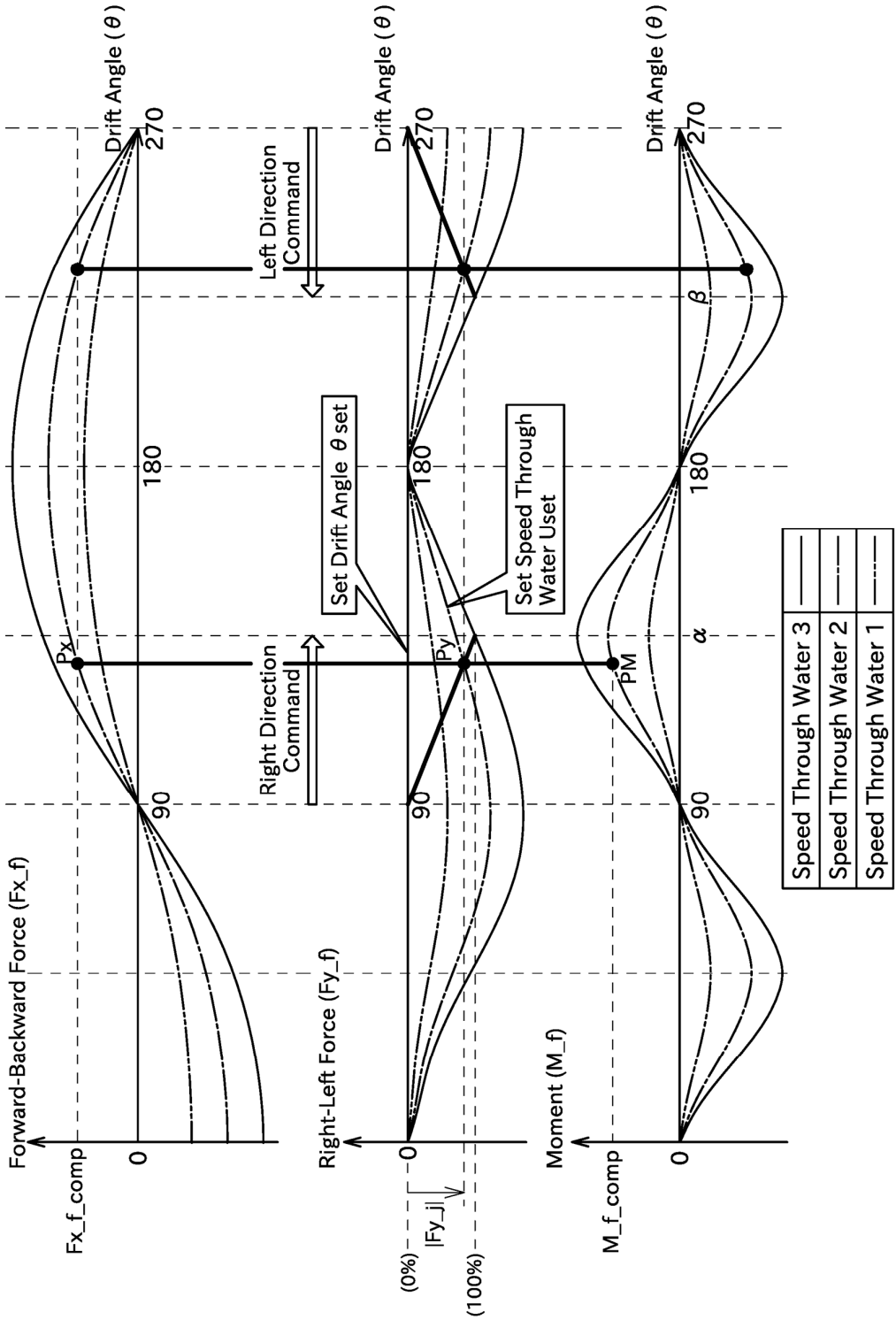
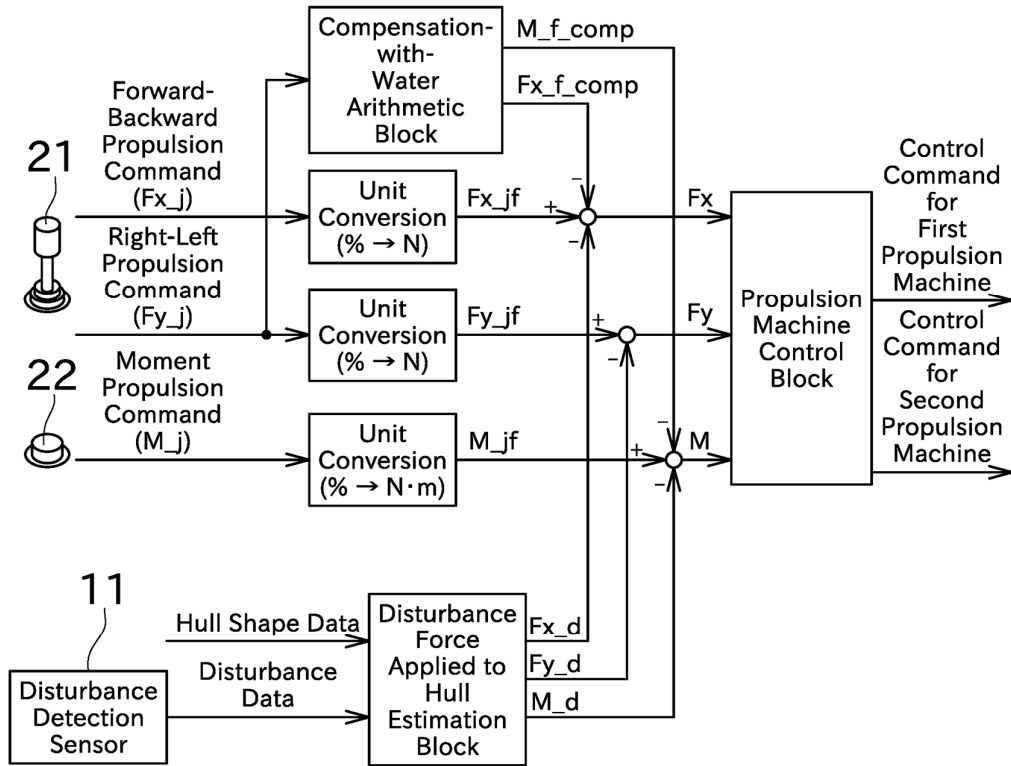


FIG. 10



$$F_x = F_{x_jf} - F_{x_f_comp} - F_{x_d}$$

$$F_y = F_{y_jf} - F_{y_d}$$

$$M = M_jf - M_f_comp - M_d$$

FIG. 11

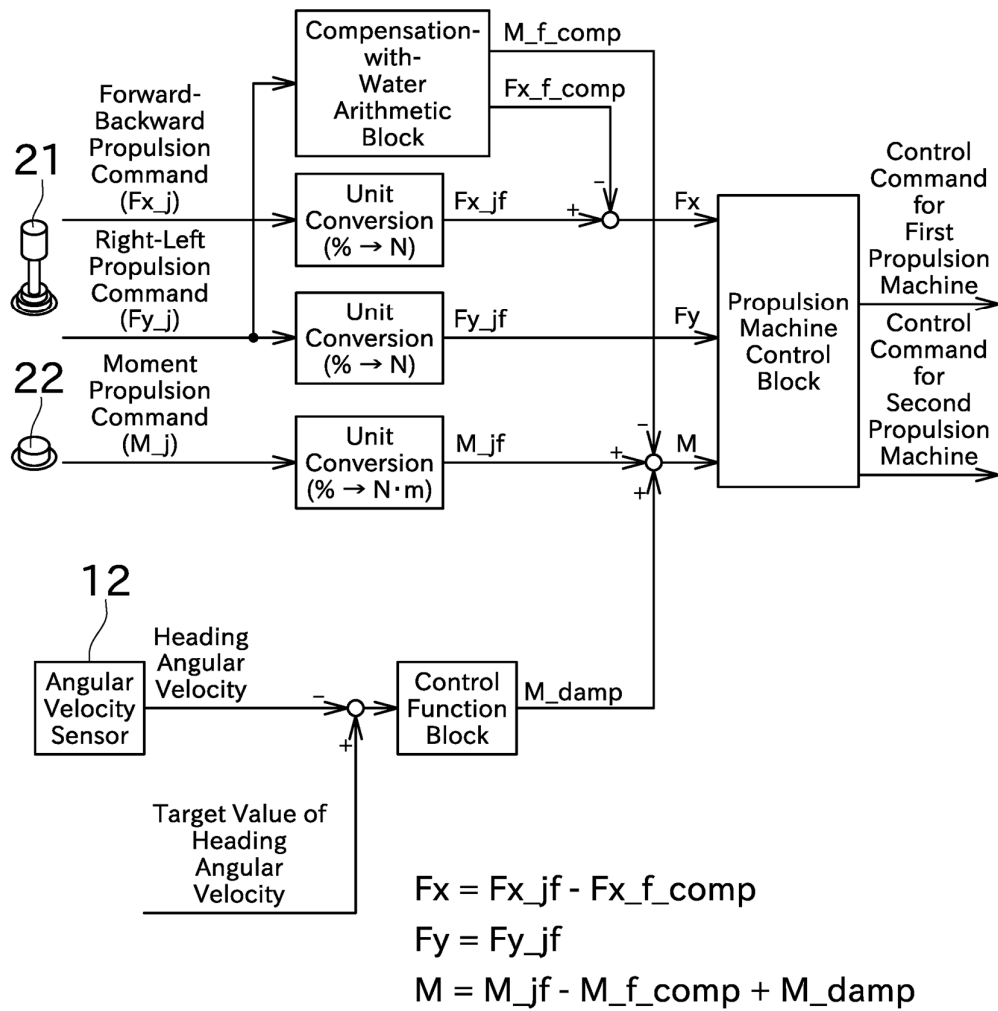
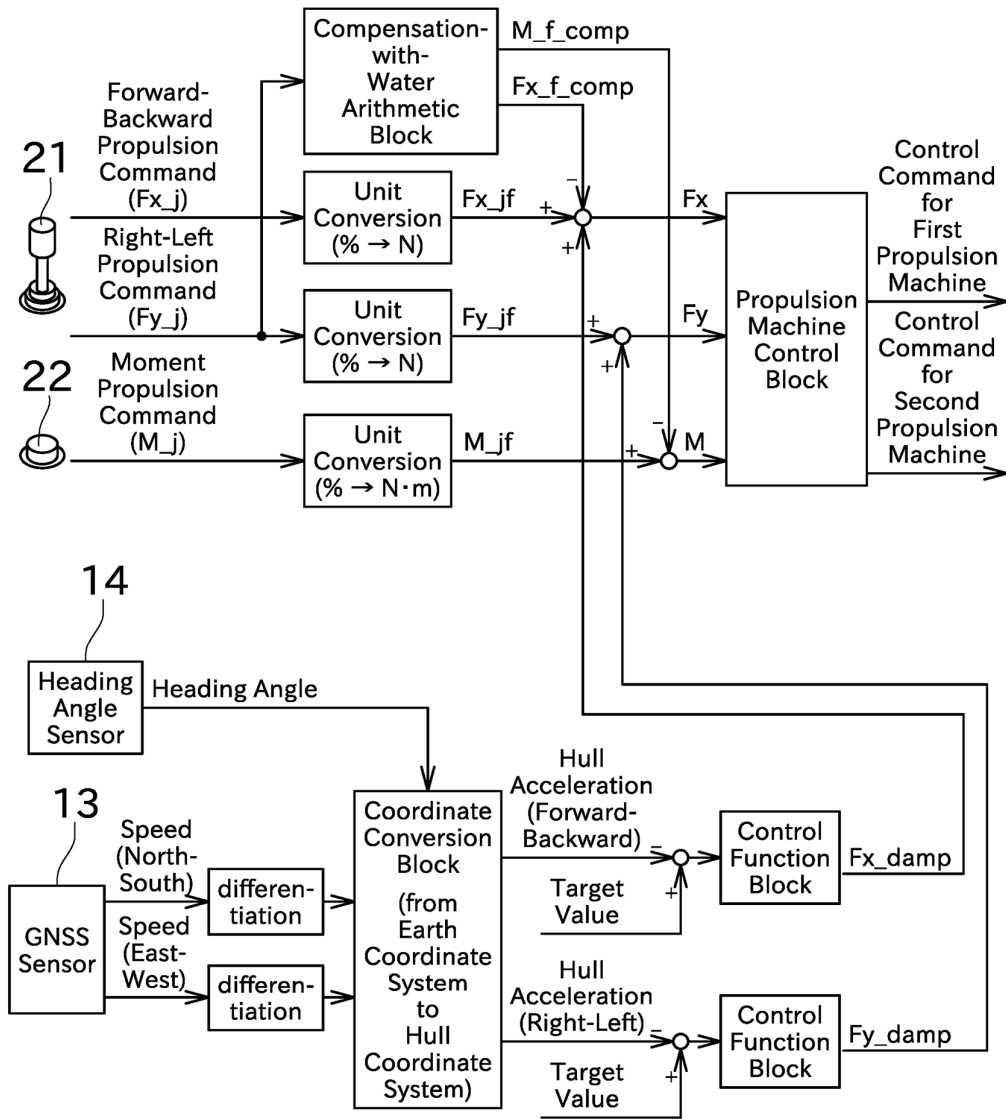


FIG. 12



$$Fx = Fx_{jf} - Fx_{f_comp} + Fx_{damp}$$

$$Fy = Fy_{jf} + Fy_{damp}$$

$$M = M_{jf} - M_{f_comp}$$

FIG. 13

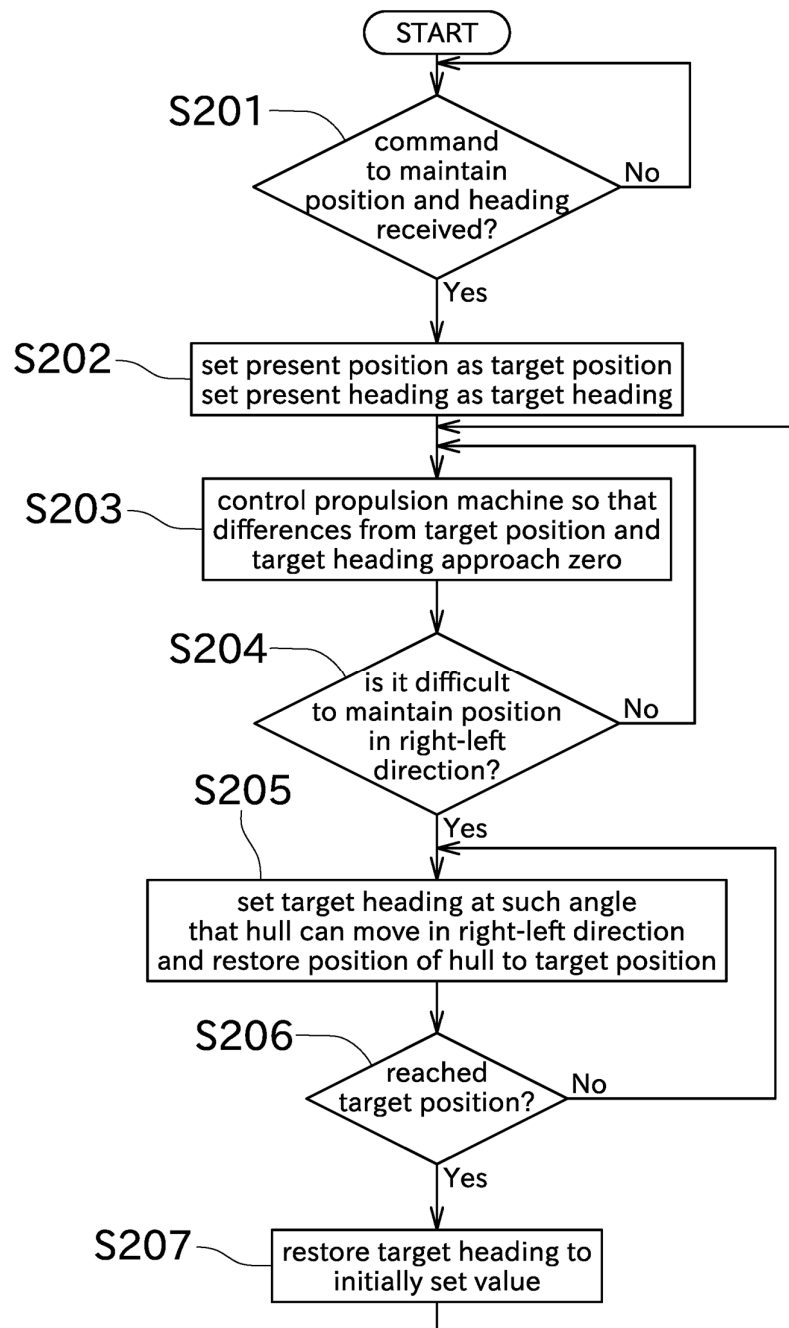


FIG. 14

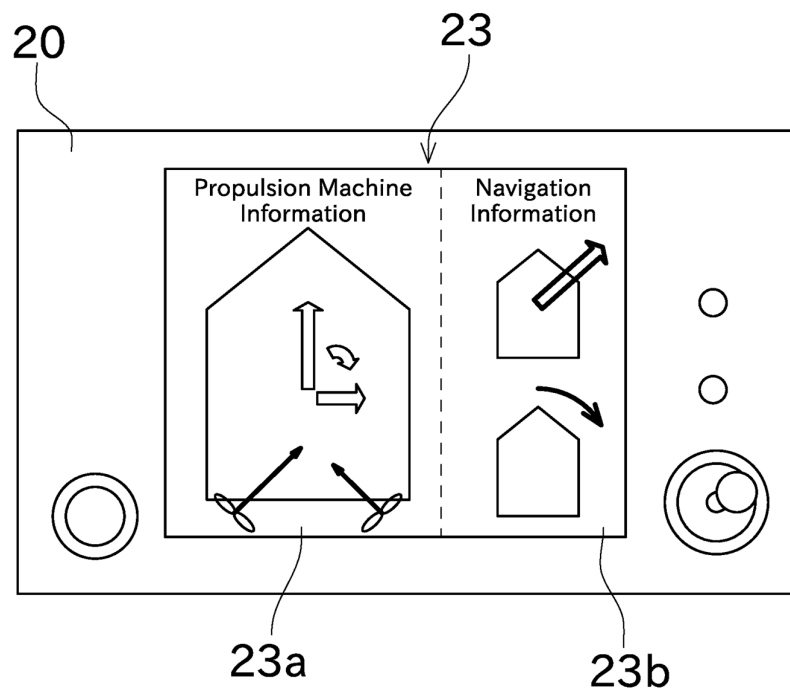


FIG. 15

