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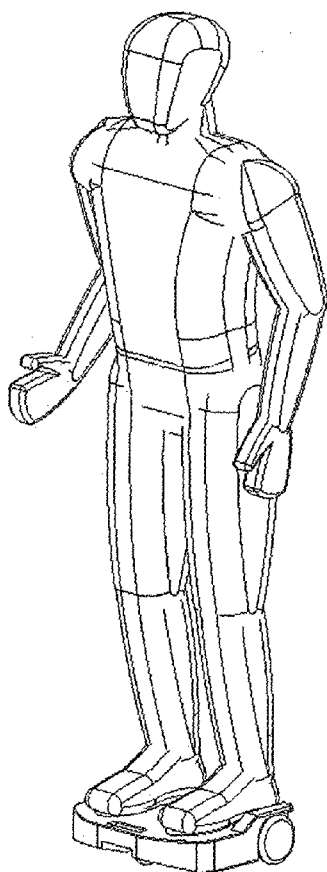


Figure 1

(57) Abstract: A controller for kinesthetic control is described to compute, from the 4 force sensing elements in the platform, the locus of the centre of gravity of the user on the platform, deducing the 3 basic modes of changes to the user's centre of gravity and orientation, with enhancements to correct for dynamic errors during motion. Beginning with a user's neutral stance, the body may; be shifted forward or backwards; be shifted sideways to the left or right; be twisted clockwise or anticlockwise. The controller counters the changes in centre of gravity caused by the input specification from the user by controlling the forward or lateral accelerations which reverse shifts the centre of gravity, and in so doing ensures the centre of gravity does not deviate from a defined zone of stable operation.



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