

Athletic Twisting Robot Experiment (Acrylic Stick Experiment)

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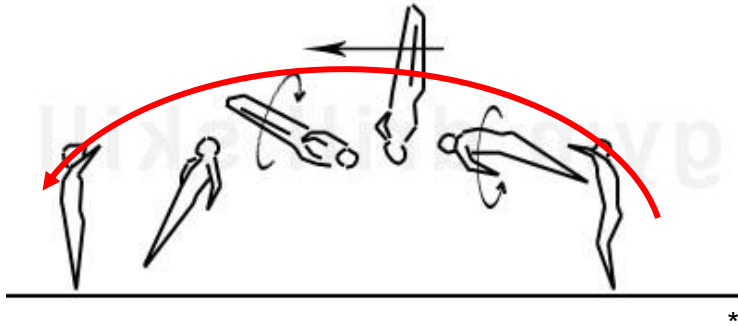
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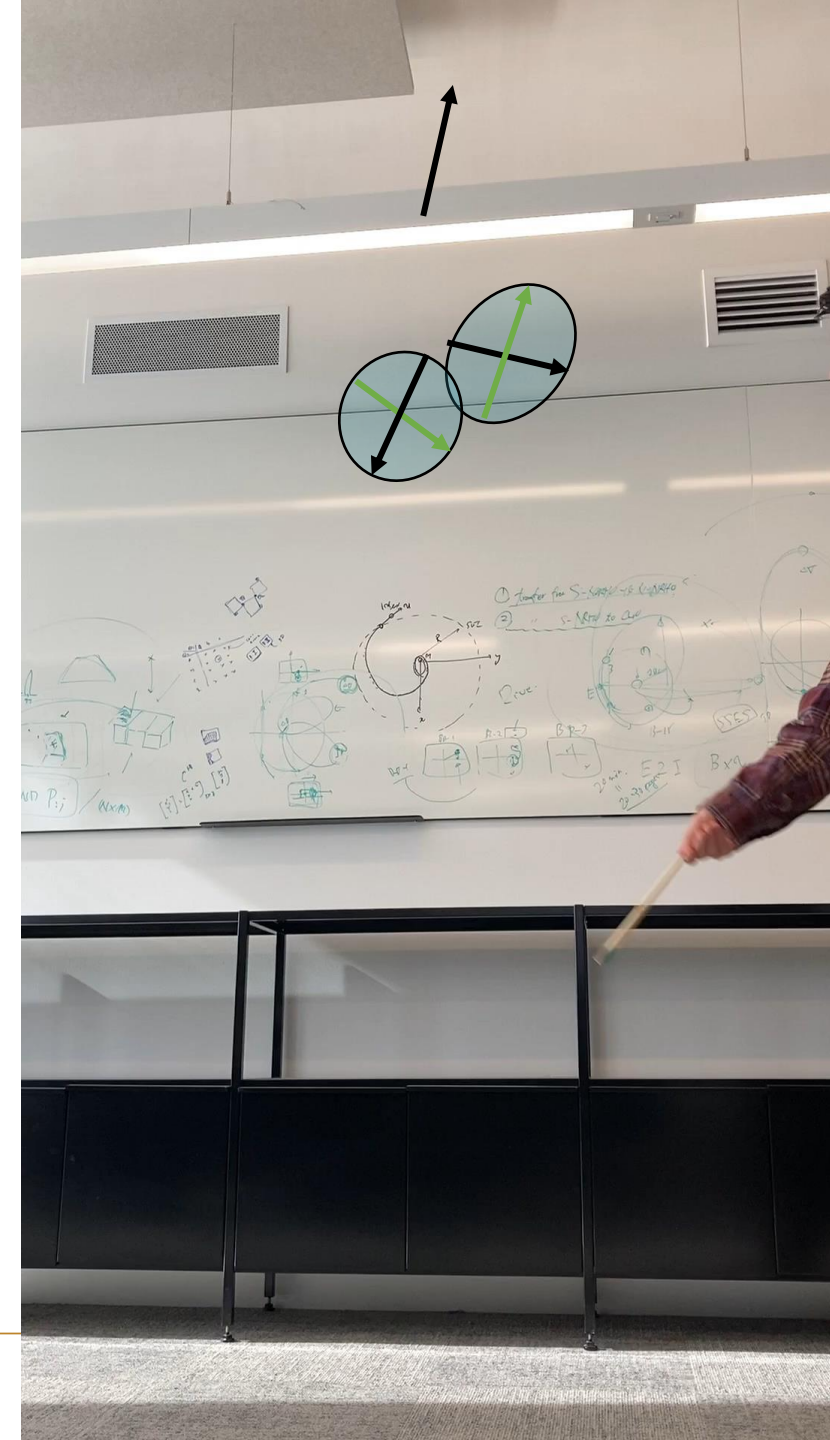
Gymnastics twist motion



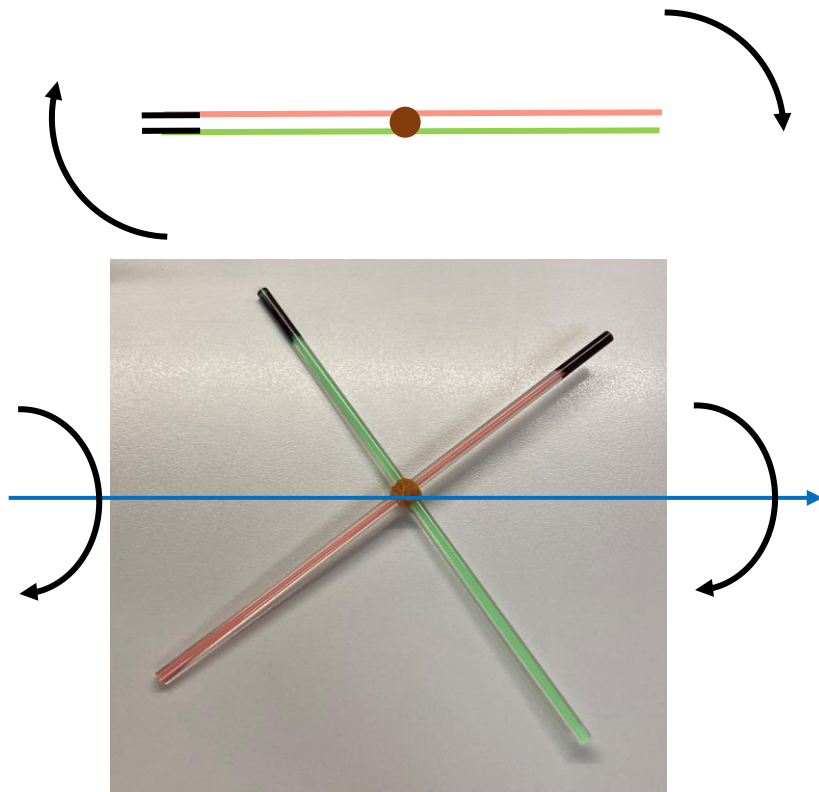
With no twist torque by kicking floor.
Twist source is in a big revolution (red) (angular momentum).
Body deformation extracts twist motion around body axis.

Expected results in ISS

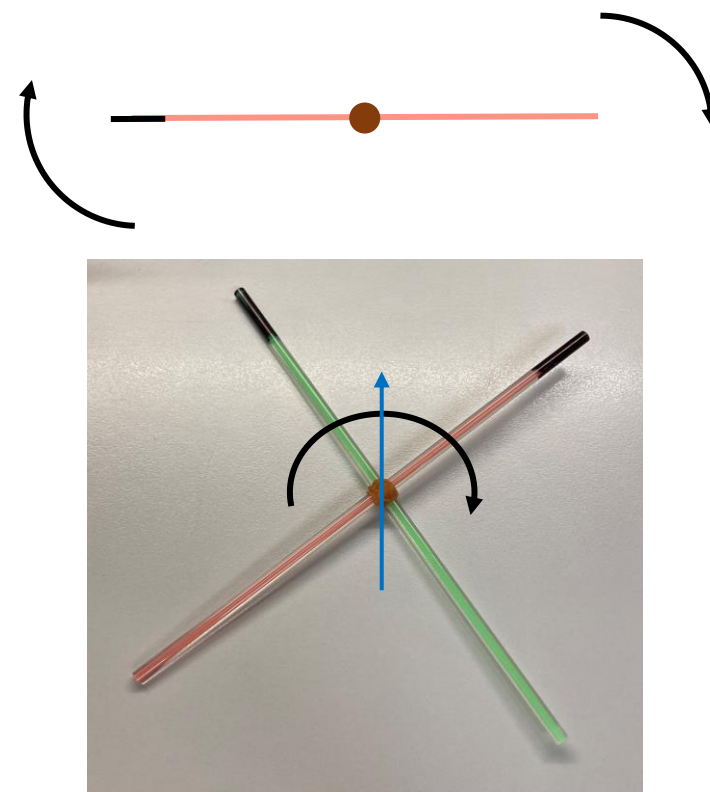
- Sticks stay **longer time at the same place**, which enables us to observe the motion longer and better.
- Comparison of experiment A and B will show the different results (**with/without twist motion**).



Experiment A



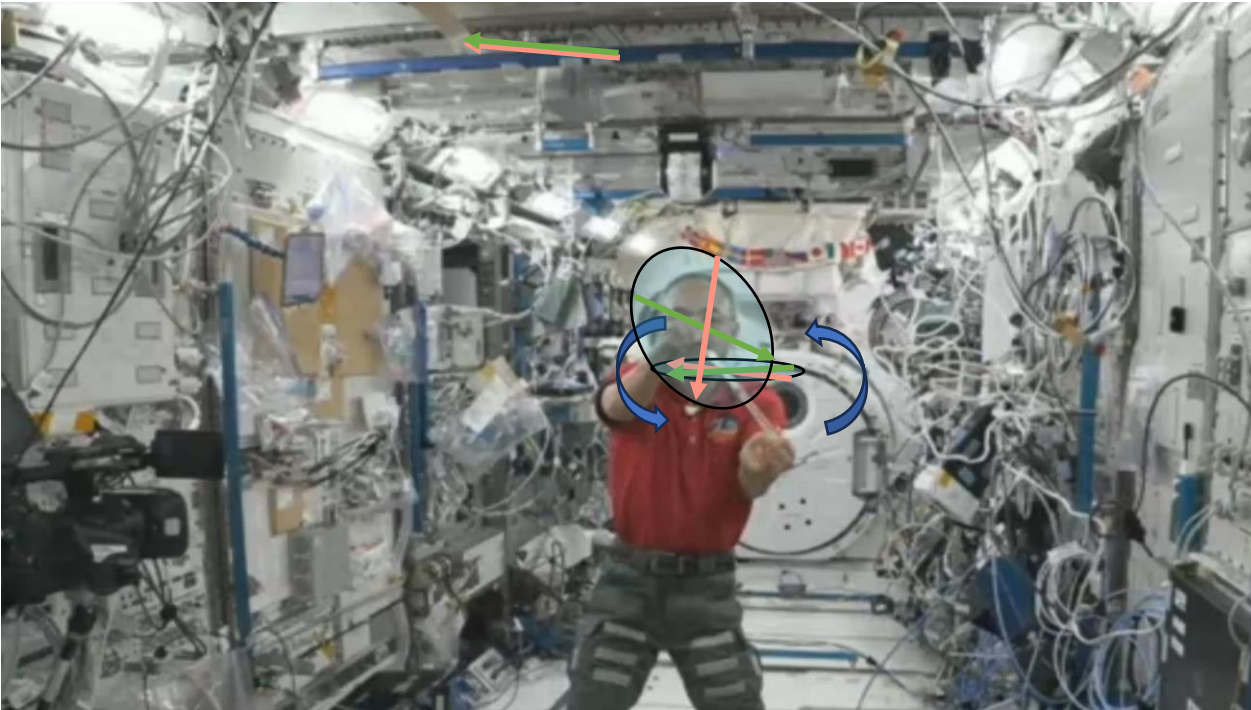
Experiment B



- When the blue rotation axis **lies in the body-cross plane** (the plane that looks like the letter X) through deformation, **twist motion appears**. (Experiment A)
- When the blue rotation axis remains **normal to body-cross plane** through deformation, **nothing happens**. (Experiment B)

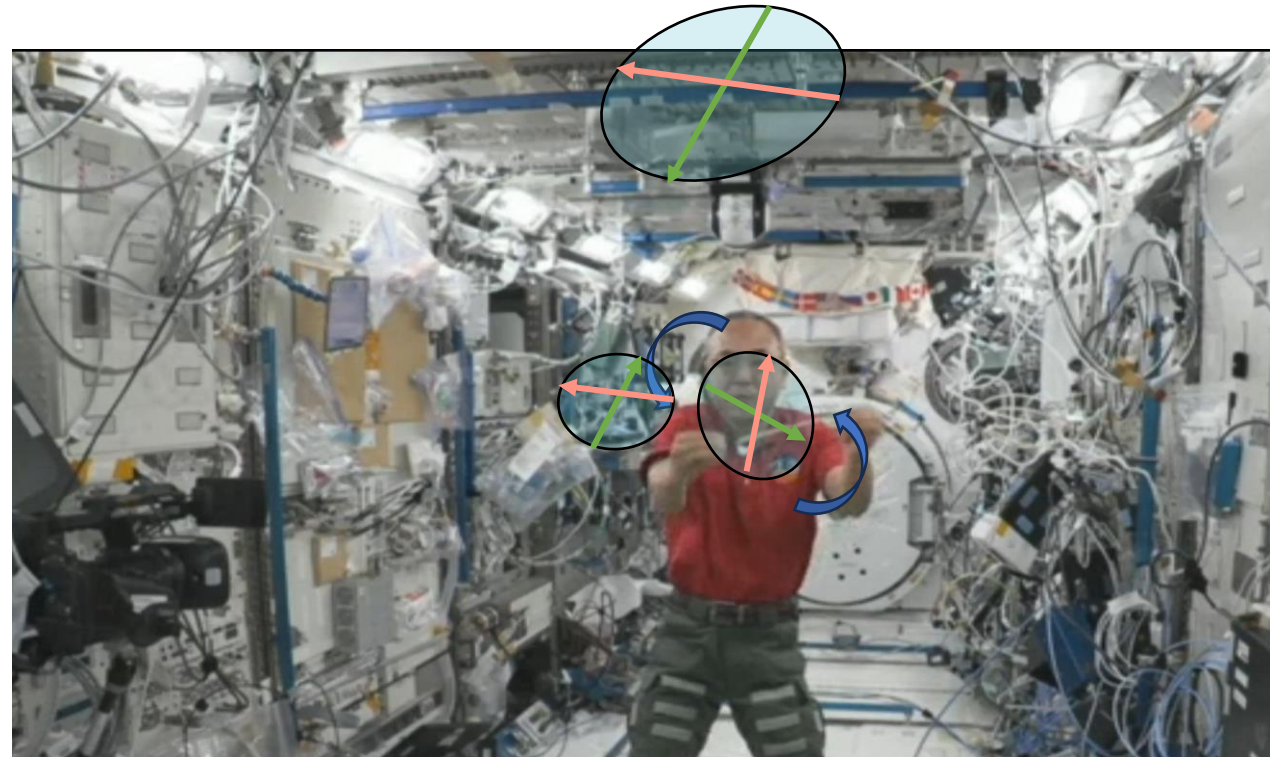
Experiment A

- Once sticks are deployed, **the rotation axis remains in the body-cross plane.**
- A twist motion appears (The body-cross plane is rotating, so looks like both **a line and X.**)



Experiment B

- Once sticks are deployed, **the rotation axis becomes orthogonal to the body-cross plane.**
- The body-cross plane continues to face the camera, so **always looks like X.**



Summary

Results

- **We could see the twist motion for longer than on the ground and different motions between experiment A and B**, although it was not perfect.
- It was hard to see the twist motion easily in real-time due to the fast rotation speed (shown video is in $0.1 \times$ original speed).
- The unintended translation motion was acting. Even though it was small, **sticks moved fast due to the microgravity**.

Lessons Learned

- Hard to perform it in a microgravity environment, the better releasing way should be considered.
- **The one of sticks should be shorter than the other**, which makes them similar to the human body and arms.

Acknowledgement

I appreciate all who supported me throughout this experiment.

