

## **Summer Short Exchange Training for UESTC students at UEC in 2011**

**Period:** From 22th July to 25th August 2011 (35days including trip days)

**Location :** UEC Department of Mech. Engg. & Int.Sys.  
1-5-1, Chofu, Tokyo 182-8585 Japan

### **UEC Supervisory staffs**

Prof.Aigou Ming ([ming@mce.uec.ac.jp](mailto:ming@mce.uec.ac.jp))  
Prof.Hisayuki AOYAMA ([aoyama@mce.uec.ac.jp](mailto:aoyama@mce.uec.ac.jp))

### **UESTC**

Prof. Xu Limei ([xulimei@uestc.edu.cn](mailto:xulimei@uestc.edu.cn))  
Prof.Li Hui ([kelly.li@126.com](mailto:kelly.li@126.com))

### **Number of Training student:**

Mr.Yonglong Xiao(School of Mechatronics Engineering 3rd year).  
Mr.Qiang Hu(School of Mechatronics Engineering 3rd year).  
Mr.Yaxin Li(Institute of Astronautics and Aeronautics Master 2nd year)

### **Program agenda:**

In this training program, three students from UESTC can join to the technical training courses that are provided from Dept of mech. Engg. and Int. Sys under the technical support of UEC graduate school students as following schedule.

1st week:

- Guidance for life style in UEC/Lab
- Technical and Culture tours around Tokyo
- Set up PC for linking to campus internet(email & skype)

2nd week- 3rd week:

- Introduction and training with mechatronics and robotics technology
- How to control the inverted pendulum.

4th week:

- Collaborate Project :
- (Mission: Assemble, Control and Competition of Inverted Pendulum Vehicle with Optical Line Trace Sensor.
- Make the report with motion picture and photo.

5th week

- Summarize the training results and the final presentation

In this training program, students from UESTC can enjoy to learn the basic experiments of Robotics and Mechatronics fields and get a lot of experiences to collaborate with Japanese students to make the inverted pendulum vehicle with line trace sensor



UESTC students and UEC students can collaborate to assemble Inverted Pendulum Vehicle with the original control software to show some performances to trace the line with good balance