

Conclusion

The cyclic rotary actuator was designed and made. The control algorithm of the cyclic actuator was considered. We provided experimental results on the control algorithm and the actuator. The diagrams of the cyclic mode without a load show dependents of the actuator parameters and the hysteresis loop bound conditions. We can realize the desired actuator mode by changing of this bound conditions and the cooling speed. If the conditions are the same, the each cycle of the actuator is the same and does not change by time. The next steps are investigation of the cyclic mode by load and a positioning of the shaft rotary angle. The results of this work have been applied in bionic prosthesis design in project by SPbPU.

Acknowledgements. *This work was supported by the Russian Science Foundation under Project 16-19-00129.*

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