

## **Annotation**

The paper analyzes the existing methods of constructing exoskeletons, on the basis of which the features of the dynamics of the exoskeleton movement are revealed.

The paper shows the potential effectiveness of adaptive control to reduce these fluctuations in the movement of the exoskeleton, simulating human walking.

The aim of the final qualifying work is to create a model of high detail active exoskeletons equipped with high-torque electric drives.