

Biped Locomotion

Carmel Leslie Golliday



Biped Locomotion:

Biped Locomotion Miomir Vukobratovic, Branislav Borovac, Dusan Surla, Dragan Stokic, 2012-12-06 Here for the first time in one book is a comprehensive and systematic approach to the dynamic modeling and control of biped locomotion robots A survey is included of various approaches to the control of biped robots and a new approach to the control of biped systems based on a complete dynamic model is presented in detail The stability of complete biped system is presented for the first time as a highly nonlinear dynamic system Also included is new software for the synthesis of a dynamically stable walk for arbitrary biped systems presented here for the first time A survey of various realizations of biped systems and numerous numerical examples are given The reader is given a deep insight into the entire area of biped locomotion The book covers all relevant approaches to the subject and gives the most complete account to date of dynamic modeling control and realizations of biped systems

Biped Locomotion Miomir Vukobratovic, Branislav Borovac, Dusan Surla, Dragan Stokic, 1990-02-26 Here for the first time in one book is a comprehensive and systematic approach to the dynamic modeling and control of biped locomotion robots A survey is included of various approaches to the control of biped robots and a new approach to the control of biped systems based on a complete dynamic model is presented in detail The stability of complete biped system is presented for the first time as a highly nonlinear dynamic system Also included is new software for the synthesis of a dynamically stable walk for arbitrary biped systems presented here for the first time A survey of various realizations of biped systems and numerous numerical examples are given The reader is given a deep insight into the entire area of biped locomotion The book covers all relevant approaches to the subject and gives the most complete account to date of dynamic modeling control and realizations of biped systems

Feedback Control of Dynamic Bipedal Robot Locomotion Eric R. Westervelt, Jessy W. Grizzle, Christine Chevallereau, Jun Ho Choi, Benjamin Morris, 2018-10-03 Bipedal locomotion is among the most difficult challenges in control engineering Most books treat the subject from a quasi static perspective overlooking the hybrid nature of bipedal mechanics Feedback Control of Dynamic Bipedal Robot Locomotion is the first book to present a comprehensive and mathematically sound treatment of feedback design for achieving stable agile and efficient locomotion in bipedal robots In this unique and groundbreaking treatise expert authors lead you systematically through every step of the process including Mathematical modeling of walking and running gaits in planar robots Analysis of periodic orbits in hybrid systems Design and analysis of feedback systems for achieving stable periodic motions Algorithms for synthesizing feedback controllers Detailed simulation examples Experimental implementations on two bipedal test beds The elegance of the authors approach is evident in the marriage of control theory and mechanics uniting control based presentation and mathematical custom with a mechanics based approach to the problem and computational rendering Concrete examples and numerous illustrations complement and clarify the mathematical discussion A supporting Web site offers links to videos of several experiments along with MATLAB code for several of the models This one of a kind book builds a solid understanding of the

theoretical and practical aspects of truly dynamic locomotion in planar bipedal robots

Control Design and Robustness Measurement for Biped Locomotion Ming-Yang Cheng, 1996 Control of dynamic biped locomotion is a difficult and challenging problem In the past two decades a lot of research has been reported in this area Most design methods are based on careful analysis and the use of linearized models While the biped is a complicated nonlinear system the validity of a linearized model may become questionable if the biped state is too far from the operation point The problem becomes even more difficult if the assumption of smooth level ground surface is relaxed Analytical techniques may not be applicable or may be inefficient To solve the problem this study investigates a different approach for the design of biped controllers The new technique consists of two parts The first one is the search of control and trajectory parameters using the Genetic Algorithm GA and the second is the selection of a good set of parameters using a newly developed robustness measure The Genetic Algorithm is a powerful searching scheme To apply it to control design the design problem is formulated as a parameter search problem The GA searches for appropriate values of control parameters and the nominal trajectory to yield good control performance From among the many sets of control and trajectory parameters obtained a robustness measure is used to select the best set Equations needed for evaluating this robustness measure of biped locomotion are derived from the Poincare Map method The study of biped locomotion stability is reduced to one for the fixed point of a Poincare Map The robustness measure is the maximum modulus of the eigenvalues of the linearized Poincare Map The new technique that combines the Genetic Algorithm and the Poincare Map method is applied to designs for biped locomotion on flat as well as less structured surfaces A surface is treated as a combination of surfaces with different slopes The biped robot makes a transition from one surface to another The control parameters and nominal trajectory suitable for each specific slope are stored in a database for control usage Simulation experiments have been performed and results show that the controllers developed are able to achieve successful biped locomotion on less structured surfaces In this study only the motion in the sagittal plane is considered To apply the proposed technique to practical design further study on biped robots with the ability to change walking direction and to start from a standstill position needs to be performed

Assessing Bipedal Locomotion: Towards Replicable Benchmarks for Robotic and Robot-Assisted Locomotion Diego Torricelli, Jan Veneman, Jose Gonzalez-Vargas, Katja Mombaur, C. David Remy, 2019-12-24

Biped Robots Armando Carlos De Pina Filho, 2011-02-04

Biped robots represent a very interesting research subject with several particularities and scope topics such as mechanical design gait simulation patterns generation kinematics dynamics equilibrium stability kinds of control adaptability biomechanics cybernetics and rehabilitation technologies We have diverse problems related to these topics making the study of biped robots a very complex subject and many times the results of researches are not totally satisfactory However with scientific and technological advances based on theoretical and experimental works many researchers have collaborated in the evolution of the biped robots design looking for to develop autonomous systems as well as to help in rehabilitation

technologies of human beings Thus this book intends to present some works related to the study of biped robots developed by researchers worldwide

Design and Control of a Biped Locomotion in a Pneumatic Humanoid Robot Pramin Artrit, University of Salford, 2004

ROBOT2013: First Iberian Robotics Conference Manuel A. Armada, Alberto Sanfeliu, Manuel Ferre, 2013-11-12 This book contains the proceedings of the ROBOT 2013 FIRST IBERIAN ROBOTICS CONFERENCE and it can be said that included both state of the art and more practical presentations dealing with implementation problems support technologies and future applications A growing interest in Assistive Robotics Agricultural Robotics Field Robotics Grasping and Dexterous Manipulation Humanoid Robots Intelligent Systems and Robotics Marine Robotics has been demonstrated by the very relevant number of contributions Moreover ROBOT2013 incorporates a special session on Legal and Ethical Aspects in Robotics that is becoming a topic of key relevance This Conference was held in Madrid 28 29 November 2013 organized by the Sociedad Espa ola para la Investigaci n y Desarrollo en Rob tica SEIDROB and by the Centre for Automation and Robotics CAR Universidad Polit cnica de Madrid UPM and Consejo Superior de Investigaciones Cient ficas CSIC along with the co operation of Grupo Tem tico de Rob tica CEA GTRob Sociedade Portuguesa de Robotica SPR Asociaci n Espa ola de Promoci n de la Investigaci n en Agentes F sicos RedAF and partially supported by Comunidad de Madrid under RoboCity2030 Programme

Contemporary Robotics Aleksandar Rodic, 2009-12-01 This book book is a collection of 18 chapters written by internationally recognized experts and well known professionals of the field Chapters contribute to diverse facets of contemporary robotics and autonomous systems The volume is organized in four thematic parts according to the main subjects regarding the recent advances in the contemporary robotics The first thematic topics of the book are devoted to the theoretical issues This includes development of algorithms for automatic trajectory generation using redundancy resolution scheme intelligent algorithms for robotic grasping modelling approach for reactive mode handling of flexible manufacturing and design of an advanced controller for robot manipulators The second part of the book deals with different aspects of robot calibration and sensing This includes a geometric and treshold calibration of a multiple robotic line vision system robot based inline 2D 3D quality monitoring using picture giving and laser triangulation and a study on prospective polymer composite materials for flexible tactile sensors The third part addresses issues of mobile robots and multi agent systems including SLAM of mobile robots based on fusion of odometry and visual data configuration of a localization system by a team of mobile robots development of generic real time motion controller for differential mobile robots control of fuel cells of mobile robots modelling of omni directional wheeled based robots building of hunter hybrid tracking environment as well as design of a cooperative control in distributed population based multi agent approach The fourth part presents recent approaches and results in humanoid and bioinspirative robotics It deals with design of adaptive control of anthropomorphic biped gait building of dynamic based simulation for humanoid robot walking building controller for perceptual motor control dynamics of humans and biomimetic approach to control

mechatronic structure using smart materials

Computer-television Analysis of Biped Locomotion In-Sheng

Cheng,1974

Fast Motions in Biomechanics and Robotics Moritz Diehl,Katja Mombaur,2007-07-13

In the past decades much progress has been made in the field of walking robots The current state of technology makes it possible to create humanoid robots that nearly walk like a human being climb stairs or avoid small obstacles However the dream of a robot running as fast and as elegantly as a human is still far from becoming reality Control of such fast motions is still a big technological issue in robotics and the maximum running speed of contemporary robots is still much smaller than that of human track runners The conventional control approach that most of these robots are based on does not seem to be suitable to increase the running speeds up to a biological level In order to address this challenge we invited an interdisciplinary community of researchers from robotics biomechanics control engineering and applied mathematics to come together in Heidelberg at the Symposium Fast Motions in Biomechanics and Robotics Optimization Feedback Control which was held at the International Science Forum IWH on September 7 9 2005 The number of participants in this symposium was kept small in order to promote discussions and enable a fruitful exchange of ideas

Fuzzy Evolutionary Computation Witold

Pedrycz,2012-12-06

As of today Evolutionary Computing and Fuzzy Set Computing are two mature well developed and highly advanced technologies of information processing Each of them has its own clearly defined research agenda specific goals to be achieved and a well set algorithmic environment Concisely speaking Evolutionary Computing EC is aimed at a coherent population oriented methodology of structural and parametric optimization of a diversity of systems In addition to this broad spectrum of such optimization applications this paradigm offers an important ability to cope with realistic goals and design objectives reflected in the form of relevant fitness functions The GA search which is often regarded as a dominant domain among other techniques of EC such as evolutionary strategies genetic programming or evolutionary programming delivers a great deal of efficiency helping navigate through large search spaces The main thrust of fuzzy sets is in representing and managing nonnumeric linguistic information The key notion whose conceptual as well as algorithmic importance has started to increase in the recent years is that of information granularity It somewhat concurs with the principle of incompatibility coined by L A Zadeh Fuzzy sets form a vehicle helpful in expressing a granular character of information to be captured Once quantified via fuzzy sets or fuzzy relations the domain knowledge could be used efficiently very often reducing a heavy computation burden when analyzing and optimizing complex systems

Springer Handbook of

Robotics

Bruno Siciliano,Oussama Khatib,2008-05-20

With the science of robotics undergoing a major transformation just now Springer's new authoritative handbook on the subject couldn't have come at a better time Having broken free from its origins in industry robotics has been rapidly expanding into the challenging terrain of unstructured environments Unlike other handbooks that focus on industrial applications the Springer Handbook of Robotics incorporates these new developments Just like all Springer Handbooks it is utterly comprehensive edited by internationally renowned experts and

replete with contributions from leading researchers from around the world The handbook is an ideal resource for robotics experts but also for people new to this expanding field

Contemporary Computing Srinivas Aluru, Sanghamitra Bandyopadhyay, Umit V. Catalyurek, Devdatt Dubhashi, Phillip H. Jones, Manish Parashar, Bertil Schmidt, 2011-07-06 This volume constitutes the refereed proceedings of the Fourth International Conference on Contemporary Computing IC3 2010 held in Noida India in August 2011 The 58 revised full papers presented were carefully reviewed and selected from 175 submissions

Toward a Coherent Framework for the Control of Planar Biped Locomotion Eric R. Westervelt, 2003

Variable Structure Control of Biped Locomotion Chieng-San Churng, 1991

Toward Development of Biped Locomotion Controls Carmel Leslie Golliday, 1975

Artificial Neural Networks — ICANN 2002 Jose R. Dorronsoro, 2003-08-03 The International Conferences on Artificial Neural Networks ICANN have been held annually since 1991 and over the years have become the major European meeting in neural networks This proceedings volume contains all the papers presented at ICANN 2002 the 12th ICANN conference held in August 28-30 2002 at the Escuela T ecnica Superior de Inform atica of the Universidad Aut onoma de Madrid and organized by its Neural Networks group ICANN 2002 received a very high number of contributions more than 450 Almost all papers were revised by three independent reviewers selected among the more than 240 serving at this year s ICANN and 221 papers were nally selected for publication in these proceedings due to space considerations quite a few good contributions had to be left out I would like to thank the Program Committee and all the reviewers for the great collective e ort and for helping us to have a high quality conference

Computer Implementation of a Parametric Model for Biped Locomotion Kinematics Thomas Charles Hartrum, 1973

Journal of Dynamic Systems, Measurement, and Control , 1996

Unveiling the Energy of Verbal Beauty: An Mental Sojourn through **Biped Locomotion**

In a global inundated with displays and the cacophony of immediate transmission, the profound energy and psychological resonance of verbal art usually disappear in to obscurity, eclipsed by the constant assault of noise and distractions. Yet, located within the musical pages of **Biped Locomotion**, a captivating function of literary beauty that impulses with raw thoughts, lies an unique journey waiting to be embarked upon. Composed by a virtuoso wordsmith, this interesting opus instructions visitors on a mental odyssey, gently exposing the latent possible and profound impact stuck within the elaborate web of language. Within the heart-wrenching expanse of this evocative analysis, we can embark upon an introspective exploration of the book is main styles, dissect their interesting writing model, and immerse ourselves in the indelible effect it leaves upon the depths of readers souls.

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