Legged Robots That Balance Artificial Intelligence Book Mediafile Free File Sharing

legged robots - computer and information science *- legged robots research on legged machines can lead to the construction of useful legged vehicles and help us to understand legged locomotion in animals. marc h. raibert why study legged machines? aside from the sheer thrill of creating machines that actually run, there are two serious reasons for ex- ...* ***361 legged robot 16. legged robots - intranet deib*** *- 361 legged robot 16. legged robots shuuji kajita, bernard espiau in this chapter, we introduce legged robots. after introducing the history of legged robot research in sect.16.1, we start to discuss hopping robots and analyze a simple passive walker as a typical cycling walking robot in sect.16.2; the poincaré map is one* ***modeling and control of legged robots - mit csail*** *- modeling and control of legged robots summary introduction the promise of legged robots over standard wheeled robots is to provide im-proved mobility over rough terrain. this promise builds on the decoupling between the environment and the main body of the robot that the presence of articulated legs allows, with two consequences.* ***an overview of legged robots - semantic scholar*** *- an overview of legged robots j. a. tenreiro machado1 and manuel f. silva1 1 department of electrical engineering institute of engineering of porto, porto, portugal {jtm,mss}@isep.ipp abstract — the objective of this paper is to present the evolution and the state-of-the- art in the area of legged locomotion systems.* ***a navigation and control strategy for miniature legged robots*** *- a navigation and control strategy for miniature legged robots konstantinos karydis,y ioannis poulakakis,z and herbert g. tanner z abstract—the paper reports on a model-based control strategy for miniature legged robots tasked with navigation in cluttered environments. our approach uses a new model for crawling locomotion, in order to* ***step climbing cooperation primitives for legged robots ...*** *- step climbing cooperation primitives for legged robots with a reversible connection carlos s. casarez1 and ronald s. fearing2 abstract—cooperation primitives for climbing steps were developed for a system of two 10 cm long velociroach hexapedal legged robots with a removable connection. when performed sequentially, the set of primitives allow ...* ***principles of robot locomotion*** *- legged robot locomotion mechanisms are often inspired by biological systems, which are very successful in moving through a wide area of harsh environments. figure 1 shows some locomotion mechanisms found in nature, of course there are many more, for example the six legged walking of a stick insect, which is often a paradigm for six legged robots.* ***hybrid zero dynamics control of legged robots*** *- 292 part | ii control chapter 4.7 hybrid zero dynamics control of legged robots aaron d. ames∗∗and ioannis poulakakis†† ∗∗mechanical and civil engineering and control and dynamical systems, california institute of technology (caltech), united states ††department of mechanical engineering, university of delaware, newark, de, united states* ***motion planning for legged and humanoid robots*** *- legged vehicles have attracted interest for many high-mobility applications, such as military troop support and logistics in rocky, steep, and forested terrain, scientific exploration of cliffs, mountains, and volcanoes on earth and other planets, and search and rescue. humanoid robots have additional applications in homes and offices as* ***motion planning for legged robots on varied terrain*** *- states of contact) just like a legged robot takes a sequence of steps [2]. in fact, for a legged robot to navigate among movable obstacles, it may be necessary to consider both walking and manipulation together [66]. 1.2 motion planning for legged robots on rough terrain, the walking motion of legged robots like athlete and hrp-2 is governed* ***design principles for a family of direct-drive legged robots*** *- kenneally et al.: design principles for family of direct-drive legged robots 901 fig. 1. the dd robots discussed in this letter: delta hopper (left), minitaur (center), and jerboa (right).of general-purpose dd legged robots using conventional rotary actuators2. the most salient contribution of this letter is a compara-* ***series elastic actuators for legged robots - ihmc*** *- series elastic actuators for legged robots jerry e. pratta, benjamin t. kruppb ainstitute for human and machine cognition, 40 south alcaniz street, pensacola, fl, usa 32502 byobotics, inc, 1776 mentor avenue, cincinnati, oh, usa 45212 abstract series elastic actuators provide many benefits in force control of robots in unconstrained environments.* ***design principles for a family of direct-drive legged robots*** *- legged robots at the 2 - 5kg scale, whose dynamic perfor-mance (according to various measures detailed below) is comparable to or in some cases better than more established geared machines. these robots: delta hopper (a monoped with three active dof/leg), penn jerboa (a tailed biped with one active dof/leg) [10] and minitaur (a quadruped* ***16-782 planning & decision-making in robotics case study ...*** *- •planning for legged robots. carnegie mellon university 17 little dog demo [vernaza et al., '09] •little dog robot needs to traverse a fully-known terrain •planning –plans footsteps first with an anytime variant of a* –compute com of the robot afterwards to support execution.* ***dynamic locomotion with one, four and six-legged robots*** *- running robots, and developed one-, two- and four-legged running robots, whose performance is still largely unsurpassed and forms the yardstick by which robots are still measured today. his first monopods provided proof of the basic principles at work – the importance of properly built mechanical* ***automated gait adaptation for legged robots*** *- automated gait adaptation for legged robots abstract gait parameter adaptation on a physical robot is an error-prone, tedious and time-consuming process. in this paper we present a system for gait adaptation in our rhex series of hexapedal robots that renders this arduous process nearly*

autonomous. ***symmetry method for limit cycle walking of legged robots*** *- symmetry method for limit cycle walking of legged robots by seyed hamed razavi a dissertation submitted in partial ful llment of the requirements for the degree of doctor of philosophy (applied and interdisciplinary mathematics) in the university of michigan 2016 doctoral committee: professor anthony bloch, co-chair professor jessy grizzle, co ...* ***[18] raibert, m. h., "legged robots that balance." cam ...*** *- robots with better mechanical characteristics, particularly for interactions with the natural environment. viii. references [1] alexander, r. mcneill, "elastic mechanisms in animal movement", cambridge university press, 1988. [2] angle, c.m. and brooks, r.a., "small planetary rov-ers", ieee international workshop on intelligent robots* ***proprioceptive actuator design in the mit cheetah: impact ...*** *- proprioceptive actuator design in the mit cheetah: impact mitigation and high-bandwidth physical interaction for dynamic legged robots patrick m. wensing 1, albert wang , sangok seok2, david otten3, jeffrey lang3, and sangbae kim1 abstract—designing an actuator system for highly-dynamic* ***build a heavy-duty six-legged walking robot*** *- 340 build a heavy-duty six-legged walking robot figure 22.6 cutting and drilling guide for the six legs. 14" x 57/64" x 9/16" x 1/16" channel stock 1/2" 4 3/4" side view* ***goat: a legged robot with 3d agility and virtual compliance*** *- goat: a legged robot with 3d agility and virtual compliance simon kalouche abstract—today's cutting-edge in dynamic legged robots use leg topologies which enable agile behaviors such as running and jumping but most of these dynamic behaviors occur primarily in the robot's sagittal plane. navigating complex environments, however, requires the* ***a template for miniature legged robots in quasi-static motion*** *- a template for miniature legged robots in quasi-static motion 3 an e ective means for linking autonomous motion plan-ning of such platforms with physically implementable control strategies. we anticipate that this model will be successful in describing the horizontal-plane behav-ior of robots morphologically similar to the octoroach,* ***detection of slippery terrain with a heterogeneous team of ...*** *- detection of slippery terrain with a heterogeneous team of legged robots duncan w. haldane*, peter fankhauser*, roland siegwart, and ronald s. fearing´ abstract—legged robots come in a range of sizes and capabilities. by combining these robots into heterogeneous teams, joint locomotion and perception tasks can be achieved by* ***gait generation and optimization for legged robots*** *- gait generation and optimization for legged robots joel d. weingarteny martin buehlerx richard e. groffy daniel e. koditscheky jweingar@umich buehler@cimgill regroff@umich kod@umich ydepartment of electrical engineering and computer science, the university of michigan* ***legged robots — an overview*** *- legged robots, as one kind of mobile robots, can be used for tasks too dangerous or difficult for human to perform, eg, planetary exploration, disaster salvation and anti-terrorism action. consequently, the issues of legged robots, including mechanical structure, stability analysis and* ***locomotion trajectory generation for legged robots*** *- legged robots. chapter 2 comes up with algorithms for con guration selection for legged robots that makes generating walking paths easy. most multi-modal plan-ners are capable of planning paths between two con gurations in discrete modes by taking into account the contact constraints. in case of high dimensional robots,* ***legged robot using hydro-muscles*** *- wheeled robots may be much easier to design and may operate faster than legged robots at this time, wheeled robots are limited to traversing flat floors and ramps. performing human like actions such as climbing stairs, navigating over obstacles, or traversing rough and uneven terrain is beyond the scope of wheeled robotics, but not legged robotics.* ***deep convolutional terrain assessment for visual reactive ...*** *- deep convolutional terrain assessment for visual reactive footstep correction on dynamic legged robots octavio villarreal1, victor barasuol1, marco camurri1;4, michele focchi1, luca franceschi2, massimiliano pontil2, darwin g. caldwell3 and claudio semini1 abstract—in this work an on-line, dynamic foothold correc- tion strategy based on visual feedback for legged robots is* ***two benchmarks for optimization of legged robots – hybrid ...*** *- because legged systems have discretely changing equations of motion, i.e., a hybrid system, such optimizations are challenging. if the optimization is incorrectly formu-lated it can produce infeasible or non-optimal results. there is a need to create benchmarks that can be used to test optimization softwares and techniques for legged robots. in ...* ***mechanical antagonism in legged robots*** *- mechanical antagonism in legged robots andy abate, jonathan w. hurst, and ross l. hatton robotics program, school of mechanical, industrial, and manufacturing engineering oregon state university, corvallis, oregon 97331–6001 email: fabatea, jhurst, ross.hattong@oregonstate abstract—in this work, we use first principles of kinematics to* ***an historical perspective of legged robots - researchgate*** *- an historical perspective of legged robots manuel f. silva*, j. a. tenreiro machado department of electrical engineering, institute of engineering of porto, rua dr. antónio bernardino de almeida ...* ***real-time motion planning of legged robots: a model ...*** *- legged robots [3–7]. however, the simplification generally comes at the cost of limiting the maneuverability. this, in turn, can reduce the reachable set of solutions and renders the task synergy synthesis approaches overly conservative. in contrast to the task decomposition approach, single task formulation offers the potential to treat the ...* ***additive manufacturing for agile legged robots with ...*** *- additive manufacturing for agile legged robots with hydraulic actuation claudio semini , jake goldsmith , diego manfredi y, flaviana calignano , elisa paola ambrosioy, jukka pakkaneny, darwin g ...* ***legged robot state-estimation through combined forward ...*** *- legged robots, unlike ground, flying, and underwater plat-forms, are in direct and switching contact with the environ-ment. leg odometry involves estimating relative transforma-tions and velocity using kinematic and contact information, which can be noisy due to the encoder*

noise and foot slip [9]. typically, legged robots are equipped with ... ***a 3d simulator of multiple legged robots based on usarsim*** *- (e.g., legged or snake-like robots) and in 3d environments, a 2d simulator may be too simplistic to correctly model some behaviors. a 3d simulator for mobile robots must also correctly simulate the dynamics of the robots and of the objects in the environment, thus allowing for a cor-rect evaluation of robot behaviors in the environment.* ***legged robots on rough terrain: experiments in adjusting ...*** *- legged vehicles may someday travel on terrain that is too rough for wheeled and tracked vehicles of comparable size. to travel on rough terrain, legged vehicles will have to use the best footholds they can reach, even those which are isolated or hidden by obstacles.* ***adaptive legged robots through exactly constrained and non ...*** *- o. y. kanner et al.: adaptive legged robots through exactly constrained and non-redundant design figure 1. classification of legged robots by the number of stance actuators and the number of controllable body degrees of freedom.* ***toward step-by-step synthesis of stable gaits for ...*** *- — many control policies developed for legged robots are based on control of an underlying, simplified version of the dynamics of the robot. a good example is the linear inverted pendulum model (lipm) which has become the standard control template for zmp-based rigid robots. for compliant* ***kinematic calibration and sensor fusion for legged robots*** *- kinematic calibration and sensor fusion for legged robots michael bloesch, marco hutter, peter fankhauser, and roland siegwart´ autonomous systems lab, eth zurich, tannenstrasse 3, 8092 zurich, switzerland¨* ***week 2: legged robotics & kinematics amr - autonomous ...*** *- introduction to autonomous mobile robots, r. siegwart, i. nourbakhsh, d. scaramuzza, the mit press, 2011. marco hutter margarita chli, paul furgale, martin rufli, davide scaramuzza, roland siegwart 1 week 2: legged robotics & kinematics amr - autonomous mobile robots legged robotics and kinematics |* ***motor sizing for legged robots using dynamic task ...*** *- motor sizing for legged robots using dynamic task specification abstract we explore an approach to incorporating task and motor thermal dynamics in the selection of actuators for legged robots, using both analytical and simulation methods. we develop a motor model with a thermal* ***an evolutionary approach to gait learning for four-legged ...*** *- an evolutionary approach to gait learning for four-legged robots sonia chernova, manuela veloso computer science department carnegie mellon university fsoniac, velosog@csu abstract— developing fast gaits for legged robots is a dif-ficult task that requires optimizing parameters in a highly irregular, multidimensional space. in* ***design for 3d agility and virtual compliance using ...*** *- design for 3d agility and virtual compliance using proprioceptive force control in dynamic legged robots a dissertation submitted to the robotics institute, school of computer science at carnegie mellon university in partial fulfillment of the requirements for the degree of master of science cmu-ri-tr-16-39 simon kalouche october 2016* ***dynamic traversal of large gaps by insects and legged ...*** *- for both legged animals and robots, the primary focus of mechanical feedback studies has been how leg morphology and mechanics interact with simple ground to assist locomotion [6337, , 65]. in complex 3d terrains where obstacles could be larger than the animal or robot, the body of a small legged animal or* ***towards versatile legged robots through active - researchgate*** *- towards versatile legged robots through active impedance control claudio semini, victor barasuol, thiago boaventura, marco frigerio, michele focchi, darwin g. caldwell, jonas buchli* ***optimal gaits and motions for legged robots*** *- optimal gaits and motions for legged robots weitao xi and c. david remy, member, ieee abstract—in this paper, we explore the potential of trajectory optimization for unspecified contact sequences as a tool to identify optimal gaits and motions for legged robots. this work is based on a recently proposed method that states the* ***task-based limb optimization for legged robots*** *- task-based limb optimization for legged robots sehoon ha 1, stelian coros2, alexander alspach , joohyung kim 1, katsu yamane abstract—the design of legged robots is often inspired by animals evolved to excel at different tasks.* ***gait generation for legged robots - robotics institute*** *- bipeds and legged mechanisms that run quickly require this speed in order to remain stable. an important distinction in the taxonomy of legged robots is between statically and dynamically stable mechanisms. a legged robot exhibitsstatic stability by keeping, at least, three feet planted on the ground and maintaining the center of gravity* ***history of robotics: timeline*** *- the technology of robots and predicted the rise of a powerful robot industry. [2] the term robotics refers to the study and use of robots; it came about in 1941 and was first adopted by isaac asimov, a scientist and writer. it was asimov who also proposed the following “laws of robotics” in his short story runaround in 1942. 1942*

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