

1. Record Nr.	UNINA9910830291003321
Titolo	Hybrid control and motion planning of dynamical legged locomotion // Nasser Sadati [and three others]
Pubbl/distr/stampa	Piscataway, J : , : IEEE Press, , [2012]
ISBN	1-118-39372-4 1-118-39374-0 1-283-59324-6 9786613905697 1-118-39370-8
Descrizione fisica	1 online resource (286 pages)
Collana	IEEE press series on systems science and engineering ; ; 2
Altri autori (Persone)	SadatiNasser
Disciplina	629.8/932 629.8932
Soggetti	Mobile robots Robots - Motion Walking
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di bibliografia	Includes bibliographical references and index.
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Sommario/riassunto

"This book provides a comprehensive presentation of issues and challenges faced by researchers and practicing engineers in motion planning and hybrid control of dynamical legged locomotion. The major features range from offline and online motion planning algorithms to generate desired feasible periodic walking and running motions and low-level control schemes, including within-stride feedback laws, continuous time update laws and event-based update laws, to asymptotically stabilize the generated desired periodic orbits. This book describes the current state of the art and future directions across all domains of dynamical legged locomotion so that readers can extend proposed motion planning algorithms and control methodologies to other types of planar and 3D legged robots"--
"This book provides a comprehensive presentation of issues and challenges faced by researchers and practicing engineers in motion planning and hybrid control of dynamical legged locomotion"--
