



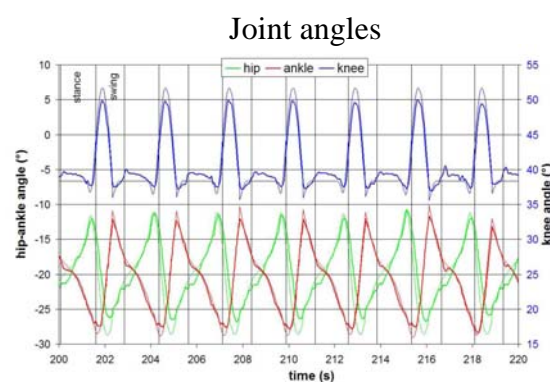
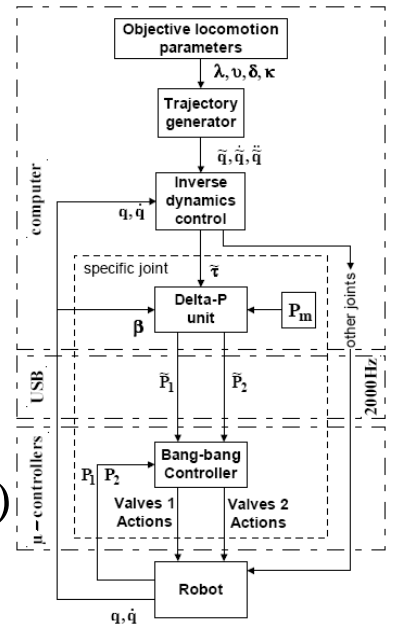
Biped robot LUCY

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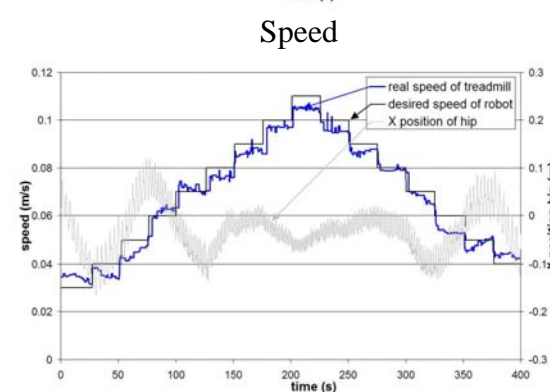
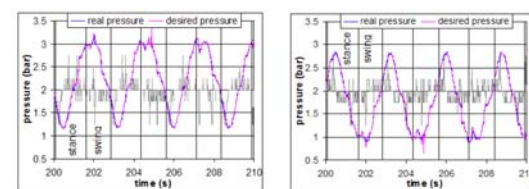
Locomotion Control Architecture for the Pneumatic Biped Lucy consisting of a Trajectory Generator and Joint Trajectory Tracking Controller

Control architecture:

- Trajectory generator
(based on inverted pendulum model, objective locomotion parameters can be changed)
- Joint trajectory tracking controller
(controls pressure inside muscles)
- Compliance controller



Pressure knee joint left



Step length

