Bio-inspired control of legged locomotion enhanced using minimal feedback (Technion)

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Current control methods for biped locomotion work mostly on horizontal planes, are relatively slow and non-human like. In order to be robust, these methods require large computation resources, as well as accurate sensors and actuators. The presented technology is a novel method that produces a more energy efficient walk over a wider range of slopes than available solutions. The invention is biologically inspired, thus, aside from contributing to the development of humanoid robots, it can help with robot assisted patient rehabilitation and walking platforms (exoskeletons), and with the improvement of orthotic devices.

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