

Algorithms of walking and stability for an anthropomorphic robot

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Abstract

© Published under licence by IOP Publishing Ltd. Autonomous movement of an anthropomorphic robot is considered as a superposition of a set of typical elements of movement - so-called patterns, each of which can be considered as an agent of some multi-agent system [1]. To control the AP-601 robot, an information and communication infrastructure has been created that represents some multi-agent system that allows the development of algorithms for individual patterns of moving and run them in the system as a set of independently executed and interacting agents. The algorithms of lateral movement of the anthropomorphic robot AP-601 series with active stability due to the stability pattern are presented.

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