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Multi-Locomotion Robotic Systems

New Concepts of Bio-inspired Robotics



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Multi Locomotion Robotic Systems New Concepts Of Bio Inspired Robotics Author Toshio Fukuda Jun 201

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Multi-Locomotion Robotic Systems Toshio Fukuda, Yasuhisa Hasegawa, Kosuke Sekiyama, Tadayoshi Aoyama, 2012-06-15
Nowadays multiple attention have been paid on a robot working in the human living environment such as in the field of medical welfare entertainment and so on Various types of researches are being conducted actively in a variety of fields such as artificial intelligence cognitive engineering sensor technology interfaces and motion control In the future it is expected to realize super high functional human like robot by integrating technologies in various fields including these types of researches The book represents new developments and advances in the field of bio inspired robotics research introducing the state of the art the idea of multi locomotion robotic system to implement the diversity of animal motion It covers theoretical and computational aspects of Passive Dynamic Autonomous Control PDAC robot motion control multi legged walking and climbing as well as brachiation focusing concrete robot systems components and applications In addition gorilla type robot systems are described as hardware of Multi Locomotion Robotic system It is useful for students and researchers in the field of robotics in general bio inspired robots multi modal locomotion legged walking motion control and humanoid robots Furthermore it is also of interest for lecturers and engineers in practice building systems cooperating with humans

Bio-Inspired Robotics Toshio Fukuda, Fei Chen, Qing Shi, 2018-11-07 This book is a printed edition of the Special Issue Bio Inspired Robotics that was published in Applied Sciences *Bioinspired Legged Locomotion* Maziar Ahmad Sharbafi, André Seyfarth, 2017-11-21 Bioinspired Legged Locomotion Models Concepts Control and Applications explores the universe of legged robots bringing in perspectives from engineering biology motion science and medicine to provide a comprehensive overview of the field With comprehensive coverage each chapter brings outlines and an abstract introduction new developments and a summary Beginning with bio inspired locomotion concepts the book's editors present a thorough review of current literature that is followed by a more detailed view of bouncing swinging and balancing the three fundamental sub functions of locomotion This part is closed with a presentation of conceptual models for locomotion Next the book explores bio inspired body design discussing the concepts of motion control stability efficiency and robustness The morphology of legged robots follows this discussion including biped and quadruped designs Finally a section on high level control and applications discusses neuromuscular models closing the book with examples of applications and discussions of performance efficiency and robustness At the end the editors share their perspective on the future directions of each area presenting state of the art knowledge on the subject using a structured and consistent approach that will help researchers in both academia and industry formulate a better understanding of bioinspired legged robotic locomotion and quickly apply the concepts in research or products Presents state of the art control approaches with biological relevance Provides a thorough understanding of the principles of organization of biological locomotion Teaches the organization of complex systems based on low dimensional motion concepts control Acts as a guideline reference for future robots assistive devices with legged

architecture Includes a selective bibliography on the most relevant published articles

Bio-inspired Robotics Toshio Fukuda, 2018

Symbiotic Multi-Robot Organisms Paul Levi, Serge Kernbach, 2010-05-18 This book examines the evolution of self organised multicellular structures and the remarkable transition from unicellular to multicellular life It shows the way forward in developing new robotic entities that are versatile cooperative and self configuring

Bio Inspired Robotics Fouad Sabry, 2024-12-09

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Biologically Inspired Robotics Yunhui Liu, Dong Sun, 2017-12-19

Robotic engineering inspired by biology biomimetics has many potential applications robot snakes can be used for rescue operations in disasters snake like endoscopes can be used in medical diagnosis and artificial muscles can replace damaged muscles to recover the motor functions of human limbs Conversely the application of robotics technology to our understanding of biological systems and behaviors biorobotic modeling and analysis provides unique research opportunities robotic manipulation technology with optical tweezers can be used to study the cell mechanics of human red blood cells a surface electromyography sensing system can help us identify the relation between muscle forces and hand movements and mathematical models of brain circuitry may help us understand how the cerebellum achieves movement control

Biologically Inspired Robotics contains cutting edge material considerably expanded and with additional analysis from the 2009 IEEE International Conference on

Robotics and Biomimetics ROBIO These 16 chapters cover both biomimetics and biorobotic modeling analysis taking readers through an exploration of biologically inspired robot design and control micro nano bio robotic systems biological measurement and actuation and applications of robotics technology to biological problems Contributors examine a wide range of topics including A method for controlling the motion of a robotic snake The design of a bionic fitness cycle inspired by the jaguar The use of autonomous robotic fish to detect pollution A noninvasive brain activity scanning method using a hybrid sensor A rehabilitation system for recovering motor function in human hands after injury Human like robotic eye and head movements in human machine interactions A state of the art resource for graduate students and researchers

Biologically Inspired Approaches for Locomotion, Anomaly Detection and Reconfiguration for Walking Robots Bojan Jakimovski, 2011-08-20 The increasing presence of mobile robots in our everyday lives introduces the requirements for their intelligent and autonomous features Therefore the next generation of mobile robots should be more self capable in respect to increasing of their functionality in unforeseen situations decreasing of the human involvement in their everyday operations and their maintenance being robust fault tolerant and reliable in their operation Although mobile robotic systems have been a topic of research for decades and aside the technology improvements nowadays the subject on how to program and making them more autonomous in their operations is still an open field for research Applying bio inspired organic approaches in robotics domain is one of the methodologies that are considered that would help on making the robots more autonomous and self capable i e having properties such as self reconfiguration self adaptation self optimization etc In this book several novel biologically inspired approaches for walking robots multi legged and humanoid domain are introduced and elaborated They are related to self organized and self stabilized robot walking anomaly detection within robot systems using self adaptation and mitigating the faulty robot conditions by self reconfiguration of a multi legged walking robot The approaches presented have been practically evaluated in various test scenarios the results from the experiments are discussed in details and their practical usefulness is validated

Locomotion Control for Complex Behaviour of Bio-inspired Multi-legged Robotic Systems, 2017 **Bio-inspired Emergent Control of Locomotion Systems** Mattia Frasca, Paolo Arena, Luigi

Fortuna, 2004 This book deals with locomotion control of biologically inspired robots realized through an analog circuit paradigm as cellular nonlinear networks It presents a general methodology for the control of bio inspired robots and several case studies as well as describes a new approach to motion control and the related circuit architecture Bio inspired Emergent Control of Locomotion Systems provides researchers with a guide to the fundamentals of the topics Moreover neuro biologists and physiologists can use the book as a starting point to design artificial structures for testing their biological hypotheses on the animal model Microbiorobotics Minjun Kim, Anak Agung Julius, 2012-03-08 Microbiorobotics is a new engineering discipline that inherently involves a multidisciplinary approach mechanical engineering cellular biology mathematical modeling control systems synthetic biology etc Building robotics system in the micro scale is an engineering

task that has resulted in many important applications ranging from micromanufacturing techniques to cellular manipulation. However, it is also a very challenging engineering task. One of the reasons is because many engineering ideas and principles that are used in larger scales do not scale well to the micro scale. For example, locomotion principles in a fluid do not function in the same way, and the use of rotational motors is impractical because of the difficulty of building the required components. Microrobotics is an area that is acknowledged to have massive potential in applications from medicine to manufacturing. This book introduces an interdisciplinary readership to the toolkit that microorganisms offer to microengineering. The design of robots, sensors, and actuators faces a range of technology challenges at the micro scale. This book shows how biological techniques and materials can be used to meet these challenges. World-class multidisciplinary editors and contributors leverage insights from engineering, mathematical modeling, and the life sciences, creating a novel toolkit for microrobotics.

Symbiotic Multi-Robot Organisms Paul Levi, Serge Kernbach, 2010. This book examines the evolution of self-organized multicellular structures and the remarkable transition from unicellular to multicellular life. It shows the way forward in developing new robotic entities that are versatile, cooperative, and self-configuring.

Design of Oscillatory Movement for Ground-based Locomotion and Synchronized Movement in Bioinspired Robotics Wei Zhou, 2022. Animals in nature move through the rhythmic oscillation of their appendages and bodies. Similar oscillatory motion is a hallmark of bioinspired robots, which seek to embed biological principles into the design, sensing, and control of robots. While there is a robust theory of nonlinear oscillatory systems, there still exist fundamental gaps in knowledge when considering robotic locomotion. For example, ground-based robots make intermittent contact with the ground to propel themselves forward or to turn, and such making and breaking of contact between the oscillatory actuation source and the environment can lead to novel locomotion challenges. Additionally, when multiple robots are moving together, the coordination of rhythmic gaits such as through synchronization may lead to beneficial group movement. However, the methods to design such synchronized locomotion are not altogether straightforward, especially when considering potential communication limitations between robots. This dissertation addresses specific problems in oscillatory locomotion of bioinspired robots. In the first study, the author developed an inchworm-inspired robot that can push and pull against the ground with simple feet to propel itself. The author studied how basic feedforward oscillatory actuation of the feet leads to non-trivial locomotion dynamics through foot slipping and stochastic foot-ground contact mechanics. In follow-up work, the author demonstrated enhanced capabilities of this robot, such as turning, that was achieved through incorporation of soft materials in the design process. In the third study, the author studied the collective behavior of simple three-link swimming robots that are controlled through feedforward oscillatory actuation. Oscillatory phase differences between neighboring robots lead to intermittent collisions that drive the group into a stable spatial configuration by lateral and longitudinal movement. We derive conditions for group spacing and density based on phase variation, examine the effective interaction potential between neighboring robots, and identify a

compatibility condition for robots to safely swim in close proximity without collisions In the last study the author enables the oscillatory motion of robots in a collective to be generated through nonlinear limit cycle dynamics The author finds that intermittent contact between robots leads to overall group synchronization of oscillatory swimming gaits which reduces contact forces between robots and enables high density configurations A phase oscillator model of this process is developed and the author derives the theoretical conditions for group synchronization observing good agreement between experiments and the theoretical model This work enables the author to demonstrate in experiment the swimming synchronization of four three link robots that do not communicate with each other but instead leverage the nonlinear dynamics of the nonlinear oscillator control system Ultimately the work the author presents in this thesis leads to new understanding of how oscillatory motion is influenced by intermittent nonlinear interactions with the environment and between robots

Bio-Inspired Self-Organizing Robotic Systems Yan Meng, Yaochu Jin, 2011-05-08 Self organizing approaches inspired from biological systems such as social insects genetic molecular and cellular systems under morphogenesis and human mental development has enjoyed great success in advanced robotic systems that need to work in dynamic and changing environments Compared with classical control methods for robotic systems the major advantages of bio inspired self organizing robotic systems include robustness self repair and self healing in the presence of system failures and or malfunctions high adaptability to environmental changes and autonomous self organization and self reconfiguration without a centralized control Bio inspired Self organizing Robotic Systems provides a valuable reference for scientists practitioners and research students working on developing control algorithms for self organizing engineered collective systems such as swarm robotic systems self reconfigurable modular robots smart material based robotic devices unmanned aerial vehicles and satellite constellations

Bio-Inspired Locomotion Control of Limbless Robots Guoyuan Li, Houxiang Zhang, Jianwei Zhang, 2023-01-30 This book presents a bio inspired hierarchical control scheme step by step toward developing limbless robots capable of 3D locomotion fast reflex response as well as sophisticated reaction to environmental stimuli This interdisciplinary book introduces how to combine biological concept with locomotion control of limbless robots The special features of the book include limbless locomotion classification and control design of biological locomotor and the integration of sensory information into the locomotor using artificial intelligence methods and on site demonstrations of limbless locomotion in different scenarios The book is suitable for readers with engineering background especially for researchers focused on bio inspired robots

Advances in Bio-Inspired Robots Taewon Seo, Dongwon Yun, Gwang-Pil Jung, 2021-11-26 This book covers three major topics specifically Biomimetic Robot Design Mechanical System Design from Bio Inspiration and Bio Inspired Analysis on A Mechanical System The Biomimetic Robot Design part introduces research on flexible jumping robots snake robots and small flying robots while the Mechanical System Design from Bio Inspiration part introduces Bioinspired Divide and Conquer Design Methodology Modular Cable Driven Human Like Robotic Arm and Wall Climbing Robot Finally in the Bio Inspired

Analysis on A Mechanical System part research contents on the control strategy of Surgical Assistant Robot modeling of Underwater Thruster and optimization of Humanoid Robot are introduced *Biologically Inspired Robotics* Yunhui Liu, 2017 Robotic engineering inspired by biology biomimetics has many potential applications robot snakes can be used for rescue operations in disasters snake like endoscopes can be used in medical diagnosis and artificial muscles can replace damaged muscles to recover the motor functions of human limbs Conversely the application of robotics technology to our understanding of biological systems and behaviors biorobotic modeling and analysis provides unique research opportunities robotic manipulation technology with optical tweezers can be used to study the cell mechanics of human red blood cells a surface electromyography sensing system can help us identify the relation between muscle forces and hand movements and mathematical models of brain circuitry may help us understand how the cerebellum achieves movement control *Biologically Inspired Robotics* contains cutting edge material considerably expanded and with additional analysis from the 2009 IEEE International Conference on Robotics and Biomimetics ROBIO These 16 chapters cover both biomimetics and biorobotic modeling analysis taking readers through an exploration of biologically inspired robot design and control micro nano bio robotic systems biological measurement and actuation and applications of robotics technology to biological problems Contributors examine a wide range of topics including A method for controlling the motion of a robotic snake The design of a bionic fitness cycle inspired by the jaguar The use of autonomous robotic fish to detect pollution A noninvasive brain activity scanning method using a hybrid sensor A rehabilitation system for recovering motor function in human hands after injury Human like robotic eye and head movements in human machine interactions A state of the art resource for graduate students and researchers in th **Multi-body Dynamic Modeling of Multi-legged Robots** Abhijit Mahapatra, Shibendu Shekhar Roy, Dilip Kumar Pratihar, 2020-02-27 This book describes the development of an integrated approach for generating the path and gait of realistic hexapod robotic systems It discusses in detail locomotion with straight ahead crab and turning motion capabilities in varying terrains like sloping surfaces staircases and various user defined rough terrains It also presents computer simulations and validation using Virtual Prototyping VP tools and real world experiments The book also explores improving solutions by applying the developed nonlinear constrained inverse dynamics model of the system formulated as a coupled dynamical problem based on the Newton Euler NE approach and taking into account realistic environmental conditions The approach is developed on the basis of rigid multi body modelling and the concept that there is no change in the configuration of the system in the short time span of collisions **BiLBIQ: A Biologically Inspired Robot with Walking and Rolling Locomotion** Ralf Simon King, 2012-11-06 The book BiLBIQ A biologically inspired Robot with walking and rolling locomotion deals with implementing a locomotion behavior observed in the biological archetype *Cebrennus villosus* to a robot prototype whose structural design needs to be developed The biological sample is investigated as far as possible and compared to other evolutionary solutions within the framework of nature s inventions Current achievements in

robotics are examined and evaluated for their relation and relevance to the robot prototype in question An overview of what is state of the art in actuation ensures the choice of the hardware available and most suitable for this project Through a constant consideration of the achievement of two fundamentally different ways of locomotion with one and the same structure a robot design is developed and constructed taking hardware constraints into account The development of a special leg structure that needs to resemble and replace body elements of the biological archetype is a special challenge to be dealt with Finally a robot prototype was achieved which is able to walk and roll inspired by the spider *Cebrennus villosus* From Cell to Robot Jörg Bandura, 2015-12-02 Bionics or biomimetics is an interdisciplinary scientific approach to apply naturally developed biological systems methods and solutions to the study and design of technology as an exclusive mutuality between life sciences and technology sciences such as robotics Robots are artificial agents which have much in common with biological agents in case of the need to adapt to their environment Soft robots have a rather flexible skin or shape propulsing itself with some type of crawling movement and are able to deform and adapt to obstacle which is advantageous over classical wheeled or legged propulsion Most of bio inspired climbing robots have the disadvantage of using legs for locomotion The idea is to find a new biological model for a bio inspired robotic locomotion device Surprisingly single cells such as amoebae or animal tissue cells have a deformable shape and the ability to crawl on surfaces by adhesion A perfect model for a new bio inspired locomotion device This book demonstrates that it is possible to transfer the biophysical locomotion mechanism of cell migration to a computational simulation model of a soft robot with a crawling cell like locomotion

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