

We are IntechOpen, the world's leading publisher of Open Access books Built by scientists, for scientists

6,900

Open access books available

185,000

International authors and editors

200M

Downloads

Our authors are among the

154

Countries delivered to

TOP 1%

most cited scientists

12.2%

Contributors from top 500 universities



WEB OF SCIENCE™

Selection of our books indexed in the Book Citation Index
in Web of Science™ Core Collection (BKCI)

Interested in publishing with us?
Contact book.department@intechopen.com

Numbers displayed above are based on latest data collected.
For more information visit www.intechopen.com



Experimental Implementation of Lyapunov based MRAC for Small Biped Robot Mimicking Human Gait

Pavan K. Vempaty, Ka C. Cheok, and Robert N. K. Loh
Oakland University
USA

1. Introduction

The chapter presents an approach to control the biped humanoid robot to ambulate through human imitation. For this purpose a human body motion capturing system is developed using tri-axis accelerometers (attached to human legs and torso). The tilt angle patterns information from the human is transformed to control and teach various ambulatory skills for humanoid robot bipedalism. Lyapunov stability based model reference adaptive controller (MRAC) technique is implemented to address unpredictable variations of the biped system.

1.1 Background

The biped humanoid robot is one of the accelerated interests in many ongoing research projects. Biped walking is a flexible mechanism that can do dynamic maneuvers in any terrain. Yet, the walking dynamics is non-linear, has many degrees of freedom and requires the development of a complicated model to describe its walking behavior. Existing biped walking methods and control techniques based on Zero moment Point (Babkovic et al., 2007; Kim et al., 2005; Montes et al., 2005; Park, 2003; Kajita et al., 2003; Sughara et al., 2002) give precise stability control for walking robots. However these methods require precise biped walking dynamics and the biped is required to have its feet flat on the ground. Also, these methods may not guarantee a human like walking behavior.

CPG is one biologically inspired method (Kajita et al., 2002; Lee & Oh, 2007; Nakanishi et al., 2004; Righeti & Ijspeert, 2006; Ha et al., 2008; Tomoyuki et al., 2009) defined as the neurons of the nervous system that can generate rhythmic signals in different systems (ex: motors). CPG's are applied to produce several rhythmic patterns or trajectories for biped walking. In these approaches, it is challenging to find appropriate parameters to achieve a stable gait. Most of the CPG's are to be tailor made for specific applications. Moreover it is also important to develop an appropriate controller to meet with disturbances occurring in real-time.

Reinforcement learning (Benbrahim, 1996; Lee & Oh, 2007; Morimoto et al., 2004; Takanobu et al., 2005; Tomoyuki et al., 2009) is a method of learning in which the system will try to map situations to actions, so as to maximize a numerical reward signal. The system is not given any set of actions to perform or a goal to achieve; rather it should discover which

actions yield a maximum reward. Reinforcement learning provides a good approach when the robot is subject to environmental changes, but since this method learns through trial and error, it is difficult to test the performance on a real time robot.

Virtual Model control technique uses simulations of virtual mechanical components to generate actuator torques (or forces) thereby creating the illusion that the simulated components are connected to the real robot (Hu et al., 1999; Pratt et al., 2001). Even so, this method still requires other controllers in conjunction to make the Biped stability reliable.

Intelligent control techniques such as Fuzzy Logic, Neural Networks, Genetic algorithm, and other intuitive controls are useful in making intelligent decisions based on their pre existing data patterns (Benbrahim, 1996; Kun & Miller, 1996; Lee & Oh, 2007; Manoonpong et al., 2007; Miller, 1997; Morimoto et al., 2004; Park, 2003; Takanobu et al., 2005; Tomoyuki et al., 2009; Wolff & Nordin, 2003; Zhou & Meng, 2003). Since these controllers may not guarantee robustness under parameter uncertainties, these methods are useful when combined with conventional control techniques.

In recent years, biped walking through human gait imitation has been a promising approach (Calinon & Billard, 2004; Chalodnan et al., 2007; Grimes et al., 2006; Hu, 1998; Loken, 2006), since it avoids developing complex kinematics and dynamics for the human walking balance and trajectories and gives the biped humanoid robot a human like walking behavior. However, these methods along with the conventional control techniques cannot adapt their behavior when the dynamic environment around the robot changes. Therefore adaptive controllers are useful to handle the changes with respect to the dynamics of the process and the character of the disturbances (Bobasu & Popescu, 2006; Chen et al., 2006; Hu et al., 1999; Kun & Miller, 1996; Siqueira & Terra, 2006; Miller, 1997).

1.2 Current work

In this chapter we show an approach to teach the biped humanoid robot to ambulate through human imitation. For this purpose a human body motion capturing system is developed using tri-axis accelerometers (attached to human legs and torso). The tilt angle patterns information is transformed to control and teach various ambulatory skills for humanoid robot bipedalism. Lyapunov stability based model reference adaptive controller (MRAC) technique is implemented to address the dynamic characteristics and unpredictable variations of the biped system (Vempaty et al., 2007, 2009, 2010).

An Adaptive Control system is any physical system that has been designed with an adaptive viewpoint, in which a controller is designed with adjustable parameters and a mechanism for adjusting those parameters. Basically, the controller has two loops. One loop is a normal feedback with the process and the controller. The other loop is the parameter adjustment loop. Due to this ability of changing its parameters dynamically, adaptive control is a more precise technique for biped walking and stability (Section 2).

In MRAC the presence of the reference model specifies the plants desired performance. The plant (biped humanoid robot) adapts to the reference model (desired dynamics). The reference model represents the desired walking behavior of the biped robot, which is derived from the human gait, which is obtained from the human motion capturing system

This chapter shows the design and development methods of controlling the walking motion of a biped robot which mimics a human gait. This process of robot learning through imitation is achieved by a human motion capturing system. In this work, a human motion capturing suit is developed using tri-axis accelerometers that are appended to a human body (Section 4).

In order to ensure precise control and stability, adaptive controller technique is applied. The control system applied for this process is based on Model Reference Adaptive Control (MRAC) with Lyapunov stability criterion. The process of learning to walk, through imitation with MRAC is applied to a real time Humanoid Robot (Robonova) with multiple servo motors (Section 5). This process is carried out by instructing the robot to follow human walking gait with the help of the human body motion capturing system and MRAC schemes (Section 6).

2. MRAC approach for biped walking

Consider the objective of controlling a biped robot so that it imitates the movements of a person. Fig. 1 shows the basic idea where the human movement is represented by y_d and the biped movement by y . The biped motion is determined by the servo motors which are controlled by the inputs u_a .

In the present problem, we will consider the case where the servo motor has uncertainties including nonlinearities, and unknown parameter values. The overall objective is to find the adaptive u_a such that $y \rightarrow y_d$.

In this chapter, we will focus on the adaptation scheme a servo motors (Ehsani, 2007).

Fig. 2 shows the adaptive the objective where the servo motor output angular displacement θ is made to follow a required θ_d , which will be computed from the desired requirement that y tracks y_d .

Servo motor dynamics including nonlinearities and delays, which have not been widely addressed. The study presented in this chapter deals with the formulation and real-time implementation aspects of the MRAC for Biped imitating human walking motion.

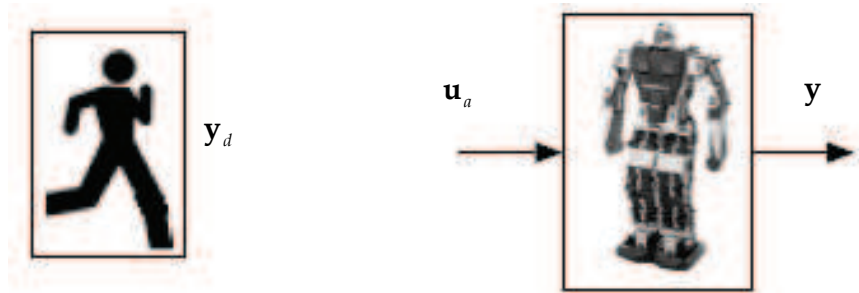


Fig. 1. Human-Robot movements interaction

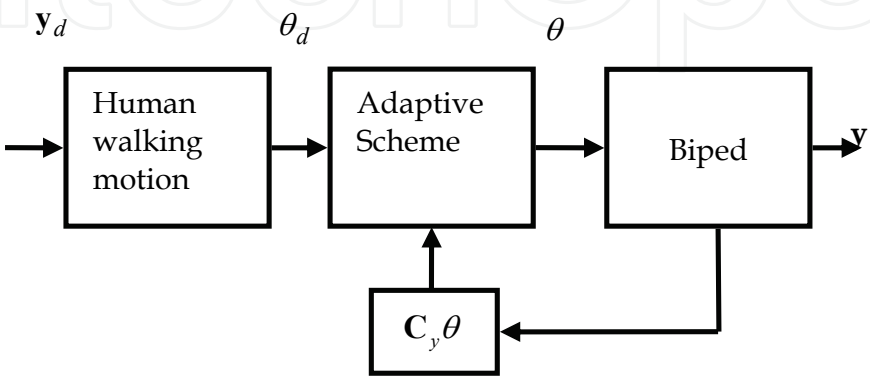


Fig. 2. MRAC for biped mimicking human gait

3. MRAC formulation

3.1 Biped servo model

The biped servo motor model is considered as a 2nd order system with 2 poles, no zero, 1 input, and 2 states described by

$$\dot{\mathbf{x}}_a = \mathbf{A}_a \mathbf{x}_a + \mathbf{B}_a \mathbf{u}_a \quad (1)$$

3.2 Reference model

The adaptive controller scheme for MRAC is shown in Fig. 3, where the reference model for the servo motor is specified by

$$\dot{\mathbf{x}}_m = \mathbf{A}_m \mathbf{x}_m + \mathbf{B}_m \mathbf{u}_m \quad (2)$$

The controller \mathbf{u}_a comprises of a state feedback and a command feedforward terms, given as

$$\mathbf{u}_a = -\mathbf{L}\mathbf{x}_a + \mathbf{N}\mathbf{u}_m \quad (3)$$

The adaptation algorithm in the MRAC will adjust the gains \mathbf{L} and \mathbf{N} based on Lyapunov stability criteria as follows.

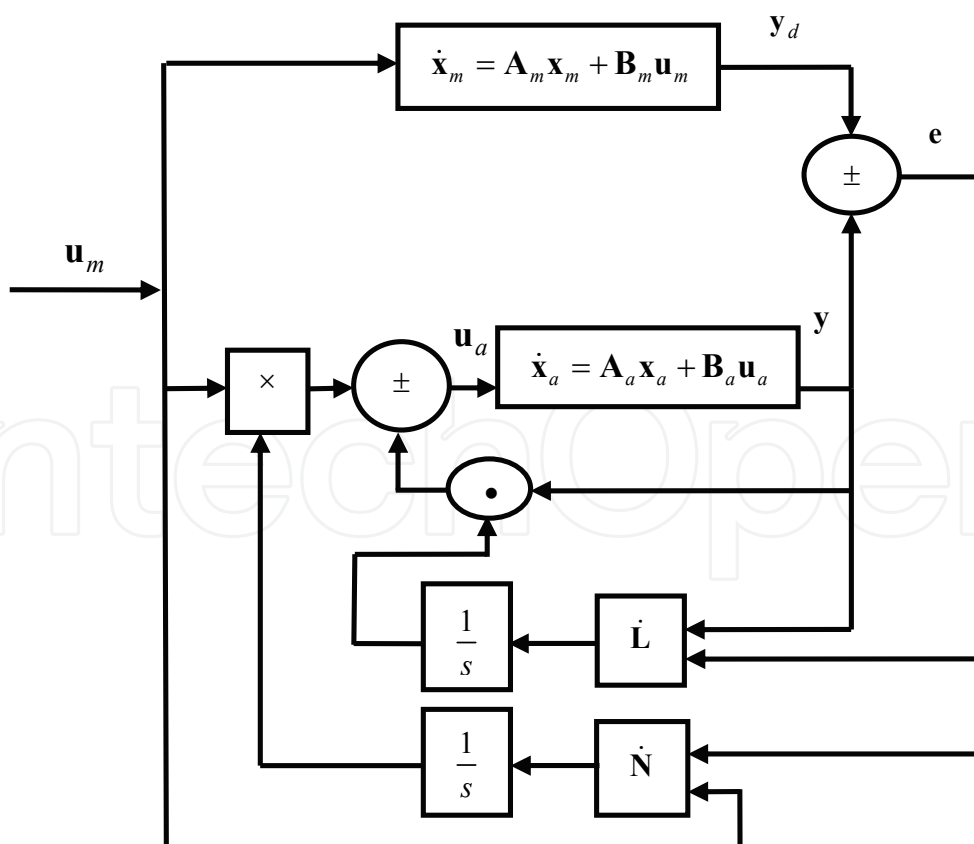


Fig. 3. Lyapunov Stability based MRAC Scheme

3.3 Error equation

Define the errors \mathbf{e} between the biped servo motor states and the desired reference human motion output states as

$$\mathbf{e} = \mathbf{x}_m - \mathbf{x}_a \quad (4)$$

$$\dot{\mathbf{e}} = \mathbf{A}_m \mathbf{e} + [\mathbf{A}_a - \mathbf{B}_a \mathbf{L} - \mathbf{A}_m] \mathbf{x}_a + [\mathbf{B}_a \mathbf{N} - \mathbf{B}_m] \mathbf{u}_m \quad (5)$$

3.4 Lyapunov stability analysis

We define the Lyapunov candidate function as

$$v = \mathbf{e}^T \mathbf{P} \mathbf{e} + \text{trace}(\mathbf{A}_m - \mathbf{A}_a - \mathbf{B}_a \mathbf{L})^T \mathbf{Q} (\mathbf{A}_m - \mathbf{A}_a - \mathbf{B}_a \mathbf{L}) + \text{trace}(\mathbf{B}_m - \mathbf{B}_a \mathbf{N})^T \mathbf{R} (\mathbf{B}_m - \mathbf{B}_a \mathbf{N}) \quad (6)$$

where $\mathbf{P} = \mathbf{P}^T > 0$, $\mathbf{Q} = \mathbf{Q}^T > 0$ and $\mathbf{R} = \mathbf{R}^T > 0$ are positive definite matrices.

$$\begin{aligned} \dot{v} &= \dot{\mathbf{e}}^T \mathbf{P} \mathbf{e} + \mathbf{e}^T \mathbf{P} \dot{\mathbf{e}} \\ &+ 2 \left(\text{trace}(\mathbf{A}_m - \mathbf{A}_a - \mathbf{B}_a \mathbf{L})^T \mathbf{Q} (\mathbf{B}_a \dot{\mathbf{L}}) \right) + 2 \left(\text{trace}(\mathbf{B}_m - \mathbf{B}_a \mathbf{N})^T \mathbf{R} (-\mathbf{B}_a \dot{\mathbf{N}}) \right) \\ &= \mathbf{e}^T \left[\mathbf{P} \mathbf{A}_m + \mathbf{A}_m^T \mathbf{P} \right] \mathbf{e} + \\ &2 \left(\text{trace}(\mathbf{A}_m - \mathbf{A}_a - \mathbf{B}_a \mathbf{L})^T (\mathbf{P} \mathbf{e} \mathbf{x}_a^T + \mathbf{Q} (\mathbf{B}_a \dot{\mathbf{L}})) \right) \\ &+ 2 \left(\text{trace}(\mathbf{B}_m - \mathbf{B}_a \mathbf{N})^T (\mathbf{P} \mathbf{e} \mathbf{u}_m^T + \mathbf{R} (-\mathbf{B}_a \dot{\mathbf{N}})) \right) \end{aligned} \quad (7)$$

From inspection, we choose

$$\begin{aligned} \mathbf{B}_a \dot{\mathbf{L}} &= \mathbf{Q}^{-1} \mathbf{P} \mathbf{e} \mathbf{x}_a^T \\ \mathbf{B}_a \dot{\mathbf{N}} &= -\mathbf{R}^{-1} \mathbf{P} \mathbf{e} \mathbf{u}_m^T \end{aligned} \quad (8)$$

So that,

$$\dot{v} = \mathbf{e}^T \left[\mathbf{P} \mathbf{A}_m + \mathbf{A}_m^T \mathbf{P} \right] \mathbf{e} \quad (9)$$

Next, choose $\mathbf{S} = \mathbf{S}^T > 0$ and solve \mathbf{P} from

$$\mathbf{P} \mathbf{A}_m + \mathbf{A}_m^T \mathbf{P} = -\mathbf{S} < 0 \quad (10)$$

We now arrive at

$$\dot{v} = -\mathbf{e}^T \mathbf{S} \mathbf{e} \quad (11)$$

It is desirable to then ensure that $\mathbf{P} \mathbf{A}_m + \mathbf{A}_m^T \mathbf{P} = -\mathbf{S} < 0$ (negative definite) where $\mathbf{S} > 0$ (positive definite). \mathbf{P} is solved from the Lyapunov equation (10).

Lyapunov stability theory ensures that the solution $\mathbf{P} > 0$ because \mathbf{A}_m is stable.

4. Human motion sensing

4.1 Human gait acquisition setup

A low cost human motion capturing system is developed using Nintendo Wii remotes (Wiimote). A Wiimote is a Bluetooth based wireless joystick with an ADXL330 tri-axis accelerometer embedded in it. An ADXL330 tri-axis accelerometer can measure acceleration with a full scale range of $\pm 3g$, and can be used to measure the tilt angles when appended to a human body. Fig. 4, shows basic human motion capturing system with Wiimotes attached to the human body. For controlling and instructing the robot on bipedalism, a minimum of five accelerometers are required, two on each leg (attached to thigh and the calf muscles), and one on the torso.

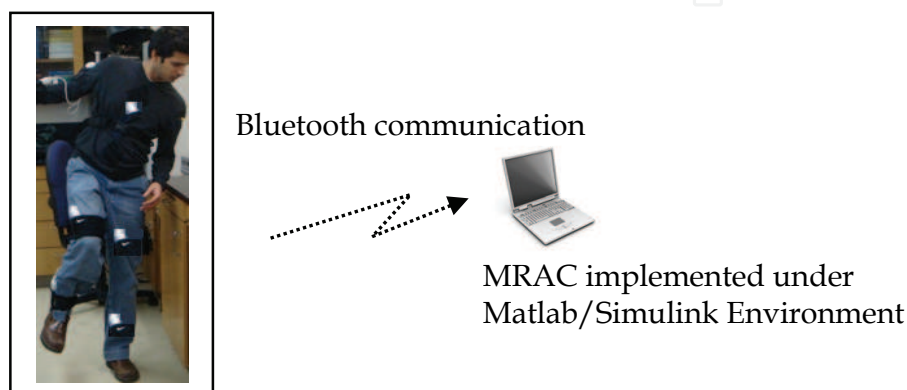


Fig. 4. Nintendo Wiimotes based human motion capturing system

4.2 Human motion data filter

Human motion data is sampled for every 300ms. The raw data captured has noise, redundancy and sensitivity. Due to this the biped may respond for every redundant movement of the human. Therefore in order to reduce this effect, a filter is designed to remove the unwanted human motion data. Fig. 5, shows the human gait data filter algorithm.

The filter basically takes the human motion data and calculates the difference of the first value $\mathbf{u}_m(i)$, with its subsequent value $\mathbf{u}_m(j)$.

The difference $Diff_{\mathbf{u}_m}$ is compared with the threshold values set as 8 degrees and 6 degrees for $PosThresUpper$ and $PosThresLower$. If the difference is satisfied by the condition, then that position data value is sent as the input command \mathbf{u}_m , else process is repeated. Fig. 6 shows the filtered data from the raw human gait data acquisition from all the 5 Wii sensors. It is clearly seen from the plots that the data that is redundant and noisy are ignored. Data is collected and processed only when there is a significant amount of change. This method also helps in sending only the useful information to the biped as well as in saving computer memory storage.

5. Real-Time Implementation

5.1 Robonova biped robot

Robonova is controlled by an Atmel ATMEGA128 8bit RISC processor, and has the capability of simultaneously controlling up to 24 servo motors. In this work, commands for the servo motors are sent from the computer under a Matlab/Simulink environment.

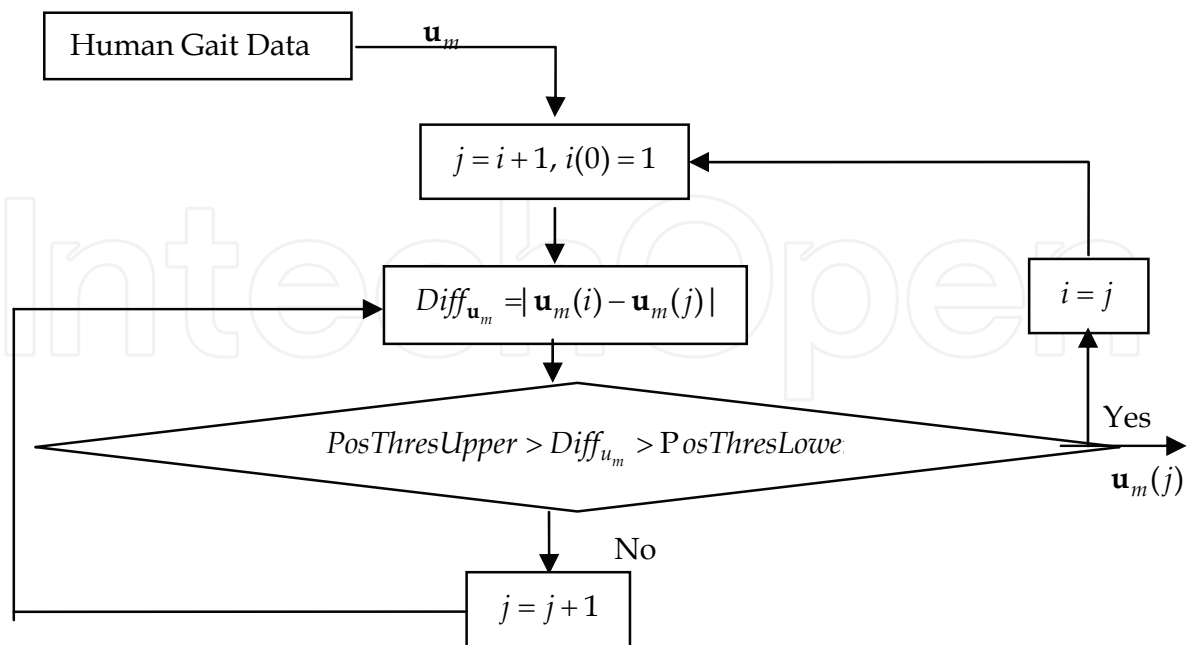


Fig. 5. Filter algorithm for human motion data

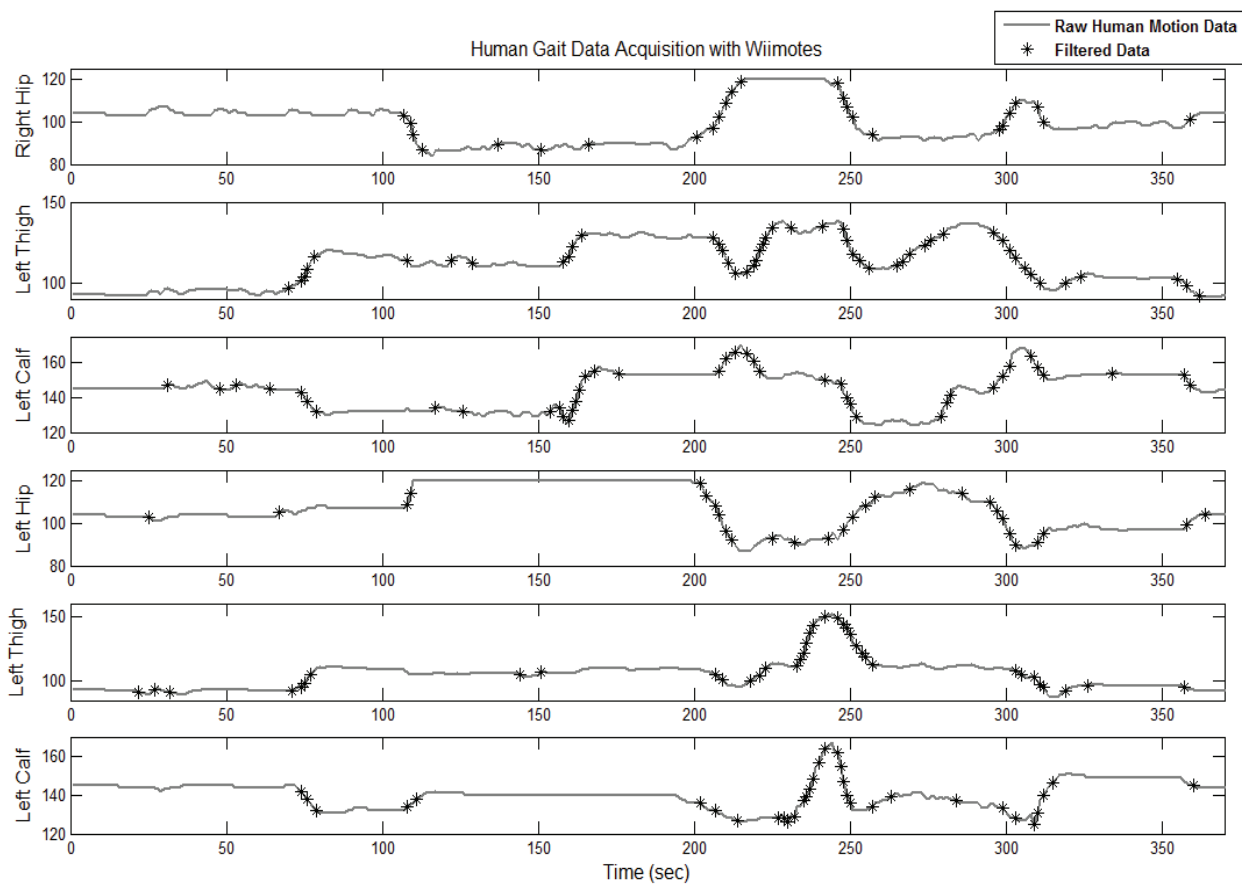


Fig. 6. Ouput of the human motion data filter

Commands for 16 servo motors are issued to the ATMEGA processor via RS232 interface. Five tri-axis ADXL335 ($\pm 3g$ acceleration) accelerometers appended on to its legs (thigh and calf muscles) and onto its torso for position feedback. Fig. 7, shows the basic control and communication setup for Robonova-Computer interaction (Zannatha & Limon, 2009).

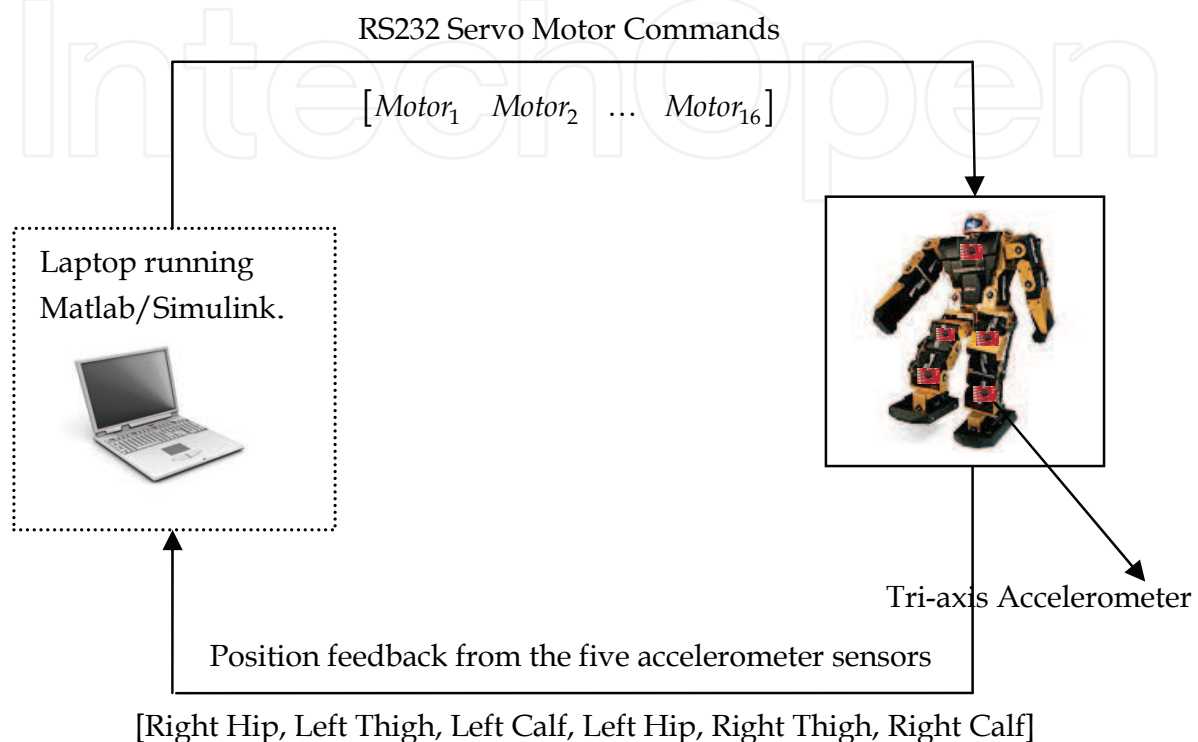


Fig. 7. Biped-Computer Interaction and Interface setup

5.2 Computation of the human movements

Desired human motion data from the Wii device is represented as

$$\mathbf{y}_d = [\theta_{Thigh\ Right} \quad \theta_{Calf\ Right} \quad \theta_{Thigh\ Left} \quad \theta_{Calf\ Left} \quad \theta_{Torso}]_{Human}^T \quad (12)$$

Output \mathbf{y} is constructed from the biped's accelerometer sensors as,

$$\mathbf{y} = [\theta_{Thigh\ Right} \quad \theta_{Calf\ Right} \quad \theta_{Thigh\ Left} \quad \theta_{Calf\ Left} \quad \theta_{Torso}]_{biped}^T = C_y \theta \quad (13)$$

The desired output will be to have $\mathbf{y} \rightarrow \mathbf{y}_d$.

5.2.1 Dynamics of the servo motors

The biped output states $\mathbf{x}_a = \theta$ are the biped servomotor angular displacements. The objective is to derive \mathbf{u}_a which will drive $\theta \rightarrow \theta_d$.

It follows that (1) can be decoupled into individual motors represented by the second order dynamics given as

$$\begin{aligned}\mathbf{x}_a &= [x_{a1} \ x_{a2} \ x_{a3} \ x_{a4} \ x_{a5} \ x_{a6} \ x_{a7} \ x_{a8}]^T \\ \mathbf{u}_a &= [u_{a1} \ u_{a2} \ u_{a3} \ u_{a4} \ u_{a5} \ u_{a6} \ u_{a7} \ u_{a8}]^T \\ \mathbf{A}_a &= \text{diag}\{a_{a1} \ a_{a2} \ a_{a3} \ a_{a4} \ a_{a5} \ a_{a6} \ a_{a7} \ a_{a8}\} \\ \mathbf{B}_a &= \text{diag}\{b_{a1} \ b_{a2} \ b_{a3} \ b_{a4} \ b_{a5} \ b_{a6} \ b_{a7} \ b_{a8}\}\end{aligned}$$

\mathbf{A}_a and \mathbf{B}_a are the uncertain parameter vectors and the states \mathbf{x}_a and the control \mathbf{u}_a are accessible.

5.2.2 Configuration of MRAC for biped servo motors

From (3), the controller \mathbf{u}_a comprises a state feedback and a command feedforward terms. Where,

$$\begin{aligned}\mathbf{L} &= \text{diag}\{l_1 \ l_2 \ l_3 \ l_4 \ l_5 \ l_6 \ l_7 \ l_8\} \\ \mathbf{N} &= \text{diag}\{n_1 \ n_2 \ n_3 \ n_4\}\end{aligned}\quad (14)$$

Where \mathbf{u}_m is the command input to the MRAC system. The controller gains \mathbf{L} and \mathbf{N} are to be tuned, so that the closed-loop system

$$\dot{\mathbf{x}}_a = (\mathbf{A}_a - \mathbf{B}_a \mathbf{L})\mathbf{x}_a + \mathbf{B}_a \mathbf{N} \mathbf{u}_m \quad (15)$$

behaves with the characteristics of the reference model defined by (2).

From the Lyapunov design 3.1.3, the gains (14) are adjusted according to

$$\begin{aligned}\dot{l}_i &= \frac{1}{b_{ai}q_i} p_i (\theta_{di} - x_{ai}) x_{ai} \\ \dot{n}_i &= -\frac{1}{b_{ai}r_i} p_i (\theta_{di} - x_{ai}) u_{mi}\end{aligned}\quad (16)$$

The convergence analysis for tuning p, q and r is discussed by (Vempaty et al., 2010).

5.3 Simulation of biped servo motor model

Consider one of the biped servo motor models, derived based on the system identification analysis. The corresponding model is given from (1)

$$\mathbf{A}_a = \begin{bmatrix} 0 & 1 \\ -a_{a2} & -a_{a1} \end{bmatrix}, \mathbf{B}_a = \begin{bmatrix} 0 \\ b_{a1} \end{bmatrix}, \mathbf{x}_a = \begin{bmatrix} x_{a1} \\ x_{a2} \end{bmatrix}, \mathbf{C}_a = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \quad (17)$$

Where, $a_{a1} = -4, a_{a2} = -2$, and $b_{a1} = 2.28$.

We would like (17) to behave with characteristics of the reference model (2) defined as

$$\mathbf{A}_m = \begin{bmatrix} 0 & 1 \\ -a_{m2} & -a_{m1} \end{bmatrix}, \mathbf{B}_m = \begin{bmatrix} 0 \\ b_{m1} \end{bmatrix}, \mathbf{x}_m = \begin{bmatrix} x_{m1} \\ x_{m2} \end{bmatrix}, \mathbf{C}_m = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \quad (18)$$

Where, $a_{m1} = -4, a_{m2} = -8$, and $b_{m1} = 8$.

The adaptation of the biped servo model to the reference model is shown in Fig. 8.

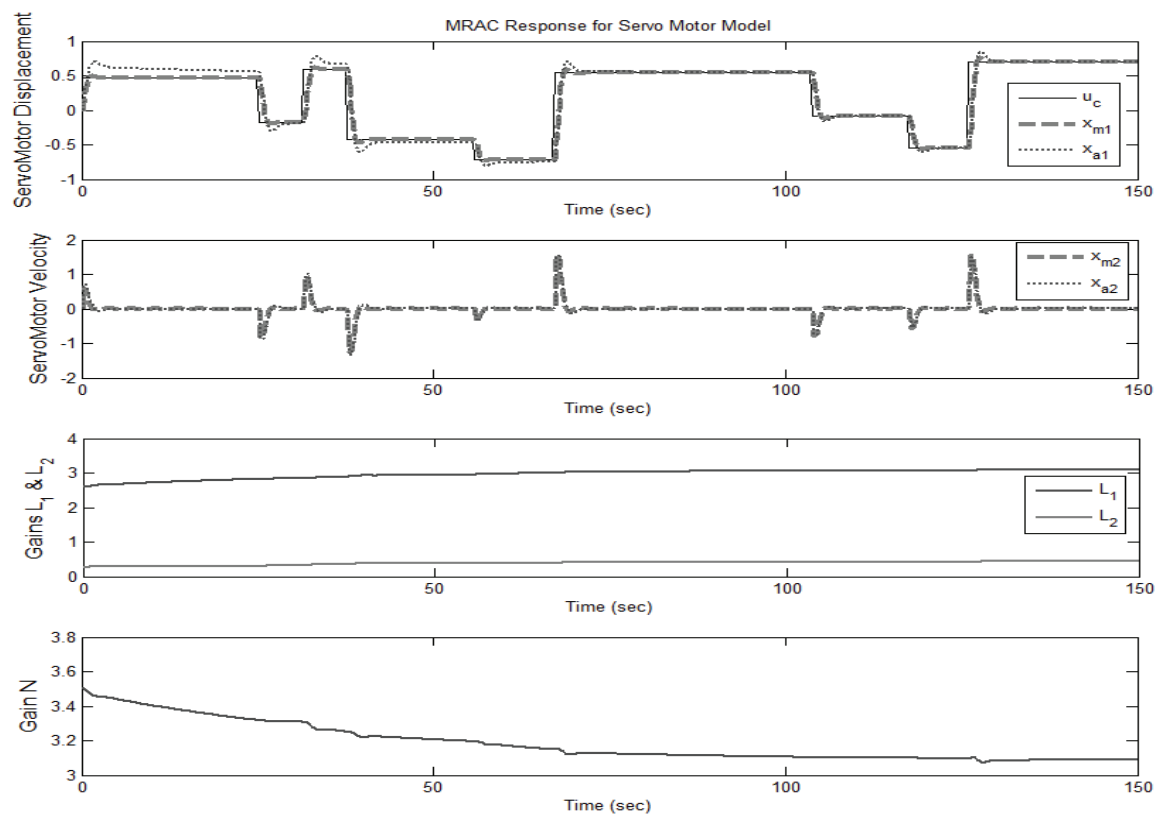


Fig. 8. MRAC response of the biped servo motor model

The coefficients a_{m1}, a_{m2} , and b_m represent the desirable characteristics for the model. It is clear from Fig. 8 that l_1, l_2 , and n_1 are tuned so that, from (2), (15) and (4) we infer,

$$A_a - B_a L \rightarrow A_m, \quad B_a N \rightarrow B_m, \text{ and } e \rightarrow 0$$

6. Experiment and results

6.1 Closed-loop setup

The process of a robot learning to walk by mimicking human gait is discussed in this section. Fig. 9, shows the human-robot interaction setup with MRAC scheme. Human movements from the Wiimotes are transferred to Matlab/Simulink; these angles are transformed and calibrated with the accelerometer feedback angles coming from the Robonova. The angles coming from the human motion change from 10 to 190; these signals are scaled between -1 and 1 to avoid singularities in the computation of MRAC. The five angles derived from the human movements are sent to the MRAC as the command input signals. In this experiment $\theta_{TorsO_{Human}}$ and $\theta_{TorsO_{Biped}}$ are set to be constant. The output of the MRAC with the five control signals is transformed to the corresponding individual servo signals to the Robonova via serial port, and the position of the biped feedback to the controller is transformed via a Kalman filter to reduce the sensor noise. MRAC is implemented individually to the servo motors defined by (12). The tracking responses of each servo motor are monitored with $\pm 5\%$ tolerance limit. After the tracking

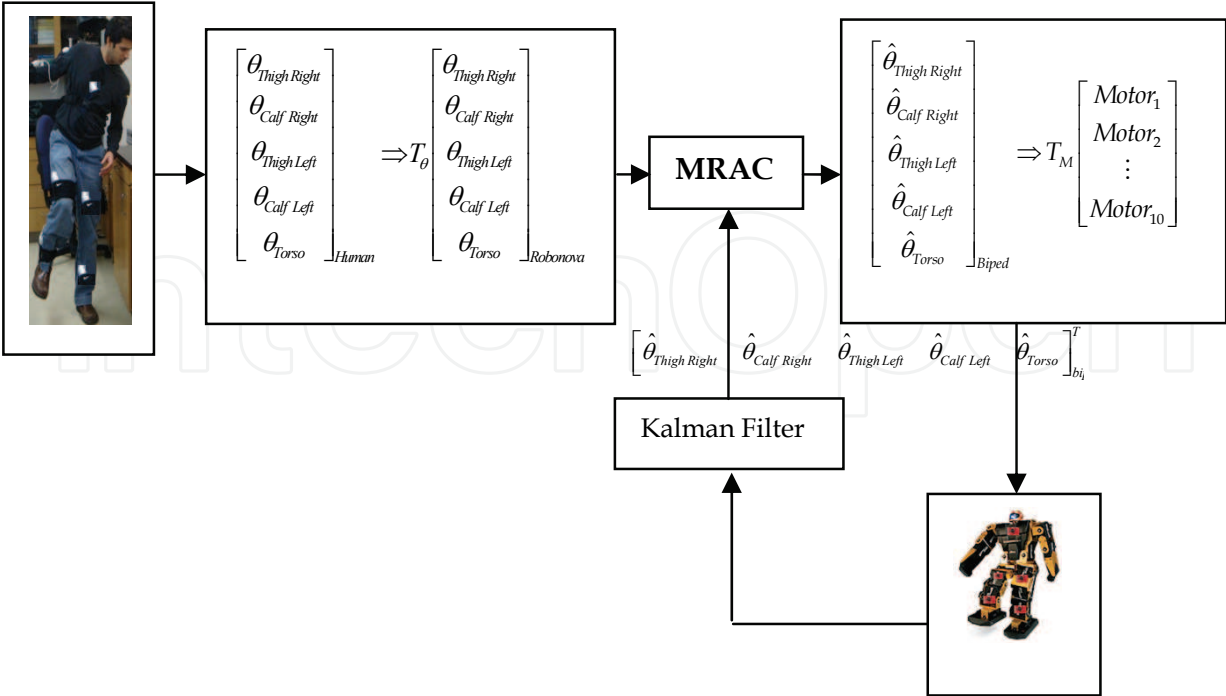


Fig. 9. Closed-loop setup for biped walker imitating human gait with MRAC

requirement is reached, the next input command is issued to the controller and the process repeats.

Although Lyapunov guarantees stability of the system under control, it never guarantees a precise tracking performance. For this, Lyapunov based MRAC schemes should be incorporated with other control schemes.

In this experiment, in order for the biped to meet the real-time response, an integrator is implemented at the command input u_a .

This approach is used in instructing the robot in walking. Here, the robot derives its dynamic and kinematic movements from the human dynamic and kinematic movements.

6.2 Output results of the MRAC based biped walker imitating human gait

Following are the results of the MRAC for a 2-step walking cycle of the biped imitating human gait. Fig. 10-13 show the MRAC outputs when the biped responds to the human gait data.

7. Conclusion

The experimental results verify the MRAC approach for the biped walker imitating the human gait under a real-time environment. The model reference adaptive control system for the servo motor control is derived and successfully implemented with Matlab/Simulink. It has been shown that the application of MRAC for biped walking indeed makes the humanoid robot adapt to whatever reference that is provided.

Therefore, it can be concluded that the use of MRAC for biped walking makes it easy to develop and control a biped system. Tracking performance and learning based on neural networks shall be included in future research.

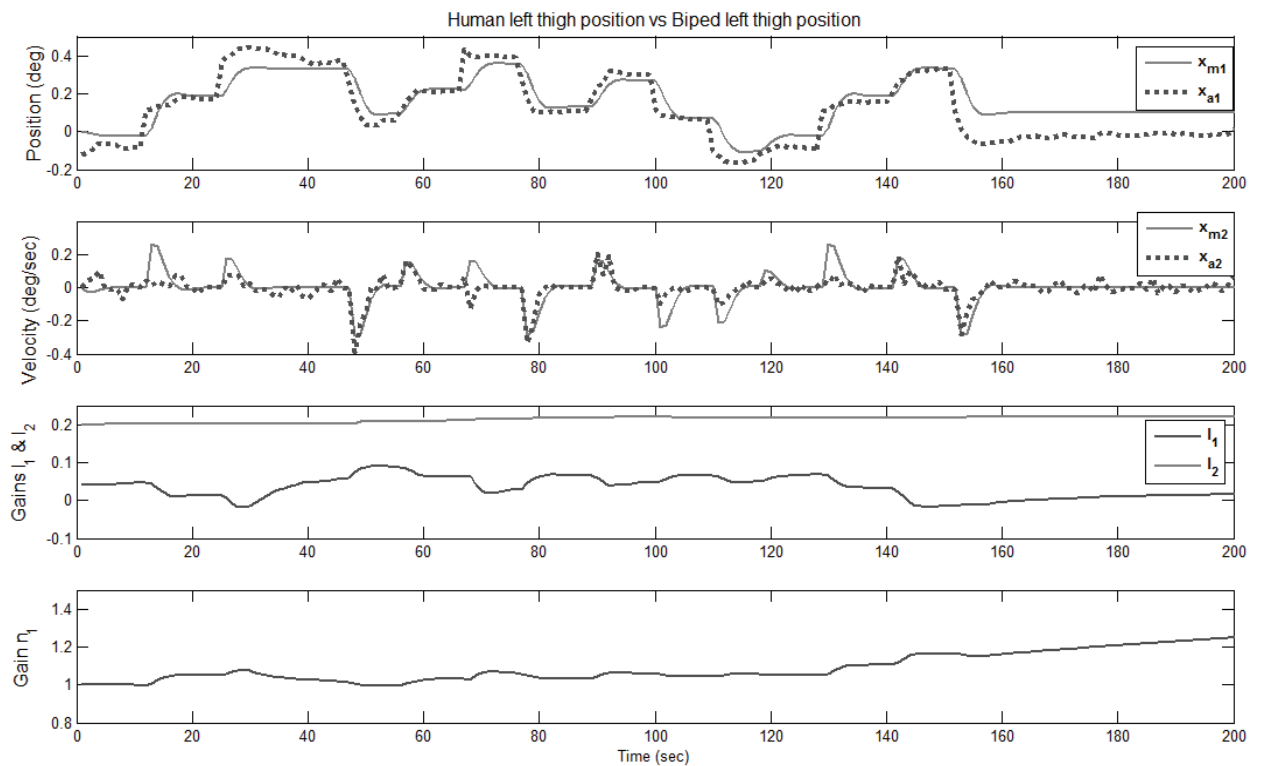


Fig. 10. Closed-loop MRAC biped response to human left thigh motion

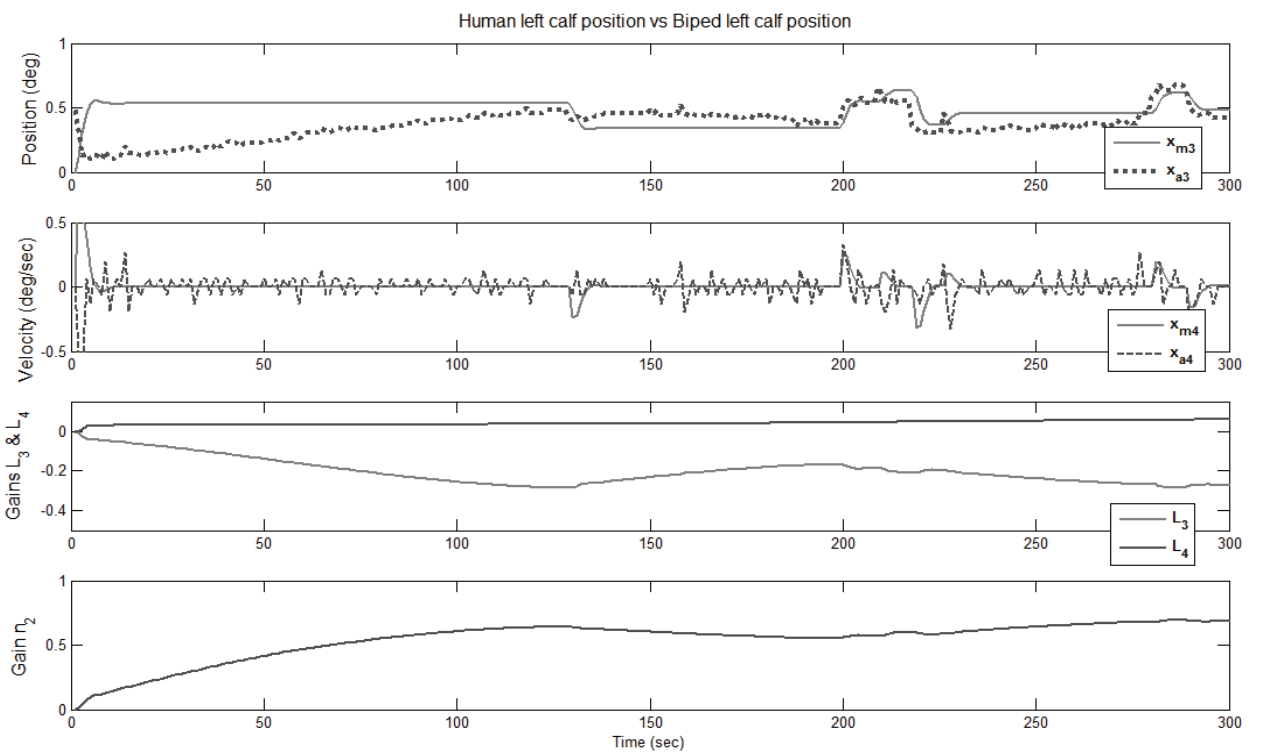


Fig. 11. Closed-loop MRAC biped response to human left calf motion

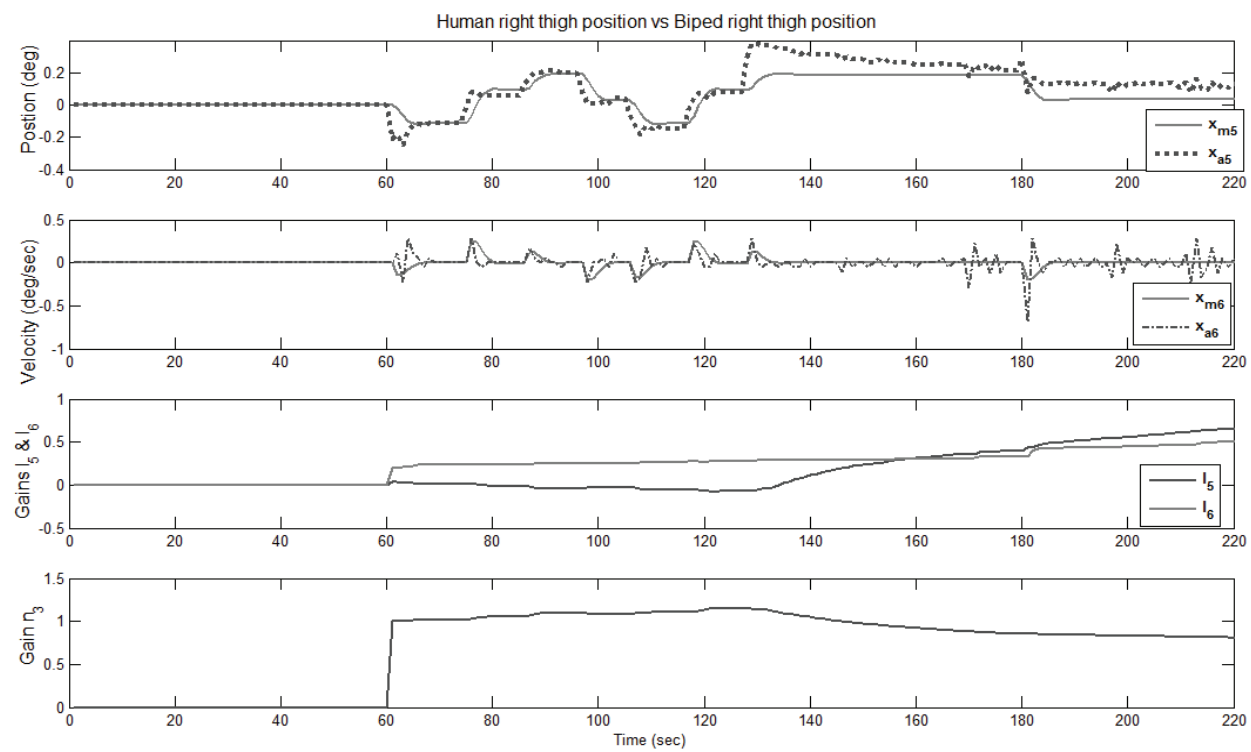


Fig. 12. Closed-loop MRAC biped response to human right thigh motion

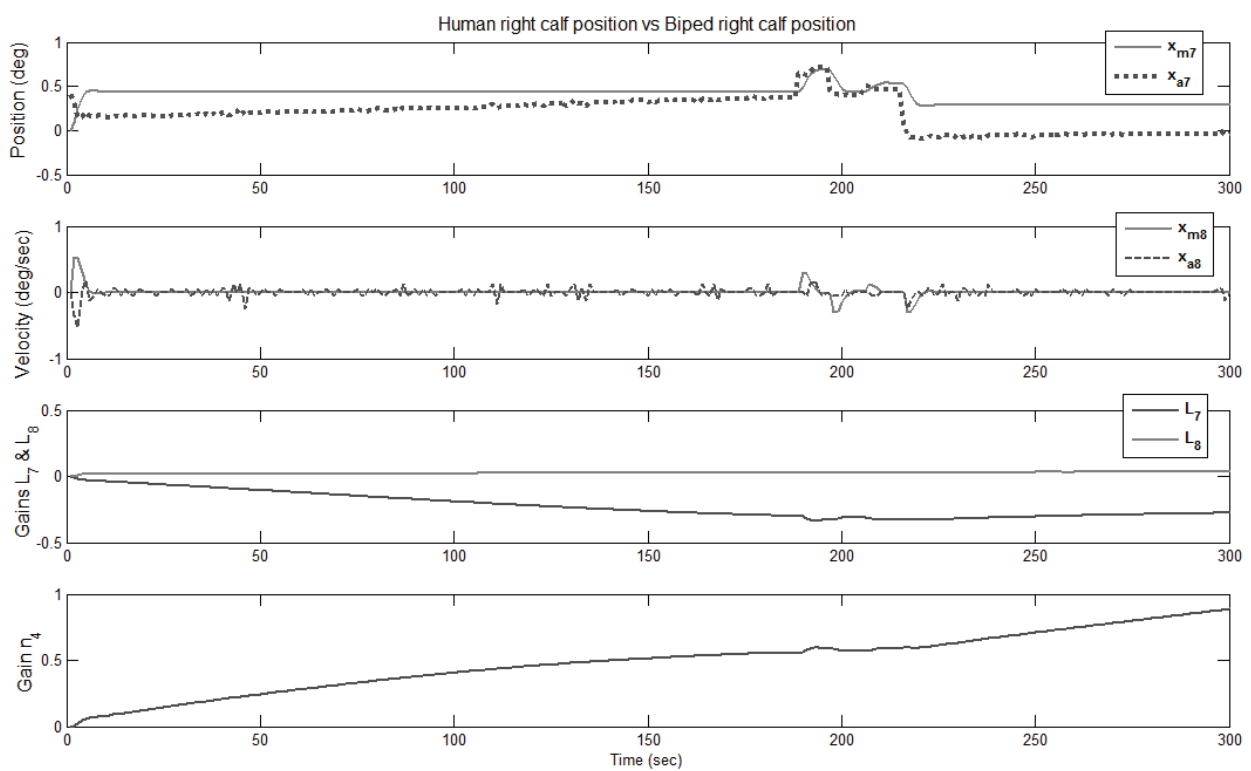


Fig. 13. Closed-loop MRAC biped response to human right calf motion

8. References

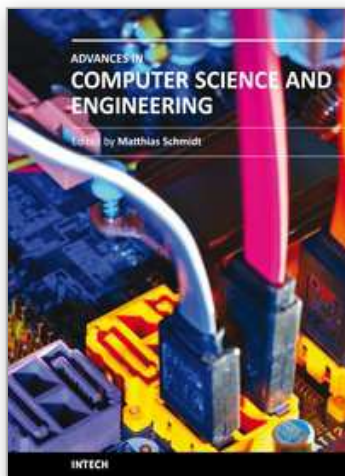
- A. A. G. Siqueira & M. H. Terra, "Nonlinear H_∞ control applied to biped robots," *Proceedings of IEEE Intl. Conf. on Control Applications*, pp. 2190-2195, 2006.
- A. L. Kun & W. Miller, "Adaptive dynamic balance of a biped robot using neural networks," *Proceedings of IEEE Intl. Conference on Robotics and Automation*, 1996.
- Asai Takanobu, Sakuma Jun, & Kobayashi Shigenobu, "Reinforcement learning for biped walking using human demonstration towards the human like walking of biped robot," *Chino Shisutemu Shinpojiumu Shiryo*, vol. 32, pp. 393-398, 2005.
- Changjiu Zhou & Qingchun Meng, "Dynamic balance of a biped robot using fuzzy reinforcement learning agents," *Fuzzy sets and systems archive*, vol. 134, issue 1, pp. 169-187, 2003.
- D B. Grimes, R. Chalodhorn, & P. N. Rao, "Dynamic imitation in a humanoid robot through nonparametric probabilistic inference," *Proceedings of Robotics: Science and Systems*, 2006.
- D. Kim, S.-J. Seo, & G.-T. Park, "Zero-moment point trajectory modeling of a biped walking robot using an adaptive neuro-fuzzy system," *Proceedings of IEE Int. Conf. on Control Theory Appl.*, vol.152, No.4, July 2005.
- Eugen Bobasu & Dan Popescu, "Adaptive nonlinear control algorithms of robotic manipulators," *Proceedings of the 7th WSEAS International Conference on Automation & Information*, pp. 83-88, 2006.
- Hamid Benbrahim, "Biped dynamic walking using reinforcement learning," *Doctoral Thesis*, University of New Hampshire, Manchester, USA. 1996.
- H. Montes, S. Nabulsi, & M. Armada, "Detecting Zero-Moment Point in Legged Robot," *Proceedings of the 7th Int. Conf. CLAWAR*, ISBN 978-3-540-29461-0, pp. 229-236, 2005.
- Jerry Pratt, Chee-Meng Chew, Ann Torres, Peter Dilworth, & Gill Pratt, "Virtual model control: an intuitive approach for bipedal locomotion," *Proceedings of the International Journal of Robotics Research*, vol. 20, no. 2, pp. 129-143, 2001.
- Jianjuen Hu, "Learning control of bipedal dynamic walking robots with neural networks," *Doctoral Thesis*, Massachusetts Institute of Technology, Cambridge, USA, 1998.
- Jianjuen Hu, Jerry Pratt, Chee-Meng Chew, Hugh Herr, & Gill Pratt, "Adaptive virtual model control of a bipedal walking robot," *Proceedings of the International Journal on Artificial Intelligence Tools*, vol. 8, no. 3, pp. 337-348, 1999.
- J. Lee & J. H. Oh, "Biped walking pattern generation using reinforcement learning," *Proceedings of IEEE-RAS Intl. on Humanoid Robots*, pp. 416-421, 2007.
- J.M. Zannatha & R.C. Limon, "Forward and inverse kinematics for a small-sized humanoid robot," *Proceedings of IEEE Intl. Conf. on Electric, Communications, and Computers*, pp. 111-118, 2009.
- Jong Hyeon Park, "Fuzzy-Logic zero-moment-point trajectory generation of reduced trunk motions of biped robot," *Fuzzy Sets Syst.* 134, pp 189-203, 2003.
- Jun Morimoto, Gordan Cheng, Christopher G. Atkeson, & Grath Zeglen, "A simple reinforcement learning algorithm for biped walking," *Proceedings of the IEEE Conference on Robotics and Automation*, vol. 3, pp. 3030-3035, 2004.
- Jun Nakanishi, Jun Morimoto, Gen Endo, Gordon Cheng, Stefen Schaal, & Mitsuo Kawato, "Learning from demonstration and adaptation of biped locomotion with dynamical movement primitives," *Proceedings of the 4th IEEE /RAS International Conference on Humanoid Robotics*, vol. 2, pp. 925-940, 2004.

- K. Babkovic, L. Nagy, D. Krkljes, & B. Borovac, "Inverted Pendulum with a Sensored Foot," *Proceedings of IEEE Intl. Symposium on Intelligent Systems and Informatics*, pp. 183-187, 2007.
- Kevin Loken, "Imitation-based learning of bipedal walking using locally weighted learning," MS Thesis, The university of British Columbia, Vancouver, Canada, 2006.
- Kristen Wolff & Peter Nordin, "Evolutionary learning from first principles of biped walking on a simulated humanoid robot," *Proceedings of the business and Industry Symposium of the Simulation Technologies Conference ASTC'03*, pp. 31-36, March 30th – April 3rd 2003.
- L. Righeti & A. Ijspeert, "Programming central pattern generators: an application to biped locomotion control," *Proceedings of IEEE Intl. Conf. on Robotics and Automation*, pp. 1585-1590, 2006.
- M. S. Ehsani, "Adaptive control of servo motor by MRAC method," *Proceedings of IEEE Intl. Conf. on Vehicle Power and Propulsion*, pp. 78-83, 2007.
- Pavan K. Vempaty, Ka C. Cheok, & Robert N. K. Loh, "Model Reference Adaptive Control for Actuators of a Biped Robot Locomotion," *Proceedings of the World Congress on Engineering and Computer Science (WCECS)*, vol II, pp. 983-988, San Francisco, USA, Oct 20-22, 2009.
- Poramate Manoonpong, Tao Geng, Toman Kulvicius, Bernd Porr, & Florentin Worgotter, "Adaptive, Fast Walking in a Biped robot under neuronal control and learning," *PLoS Computational Biology*, 2007.
- Rawichote Chalodnan, David B. Grimes, & Rajesh P. N. Rao, "Learning to walk through imitation," *Proceedings to the 20th International Joint Conference on Artificial Intelligence*, pp. 2084-2090, 2007.
- S. Calinon & A. Billard, "Stochastic gesture production and recognition model for a humanoid robot," *Proceedings of IEEE Intl. Conf. on Intelligent Robots and Systems*, pp. 2769-2774, 2004.
- Seungsuk Ha, Youngjoon Han, & Hernsoo Hahn, "Adaptive gait pattern generation of biped robot based on human's gait pattern analysis," *Proceedings of the International Journals of Mechanical System Science and Engineering*, vol. 1, no. 2, pp. 80-85, 2008.
- Shuuji Kajita, Fumio Kanehiro, Kenhi Kaneko, Kiyoshi Fujiwara, Kazuhito Yokoi, & Hirohisa Hirukawa, "A realtime pattern generator for biped walking," *Proc. of IEEE Int. Conf. on Robotics & Automation*, vol. 1, pp. 31-37, 2002.
- Shuuji Kajita, Fumio Kanehiro, Kenji Kaneko, Kiyoshi Fujiwara, Kensuke Harada, Kazuhito Yokoi & Hirohisa Hirukawa, "Biped walking pattern generation by using preview control of zero-moment point," *Proc. of IEEE Int. Conf. on Robotics & Automation*, vol. 2, pp. 1620-1626, 2003.
- T. Sugihara, Y. Nakamura, & H. Inoue, "Realtime humanoid motion generation through ZMP manipulation based on inverted pendulum control," *Proceedings of the Intl. Conf. on Robotics and Automation, ICRA*, pp. 1404-1409, 2002.
- T. Tomoyuki, Y. Azuma, & T. Shibata, "Acquisition of energy-efficient bipedal walking using CPG-based reinforcement learning," *Proceedings of IEEE/RSJ Intl. Conf. on Intelligent Robots and Systems*, pp. 827-832, 2009.
- W. Miller, "Dynamic balance of a biped walking robot: Adaptive gait modulation using CMAC neural networks," *Neural Systems for Robotics*, Academic Press, 1997.

- Y. Chen, Z. Han, & H. Tang, "Direct adaptive control for nonlinear uncertain system based on control Lyapunov function method," *Journal of Systems Engineering and Electronics*, vol. 17, pp. 619-623, 2006.

IntechOpen

IntechOpen



Advances in Computer Science and Engineering

Edited by Dr. Matthias Schmidt

ISBN 978-953-307-173-2

Hard cover, 462 pages

Publisher InTech

Published online 22, March, 2011

Published in print edition March, 2011

The book *Advances in Computer Science and Engineering* constitutes the revised selection of 23 chapters written by scientists and researchers from all over the world. The chapters cover topics in the scientific fields of Applied Computing Techniques, Innovations in Mechanical Engineering, Electrical Engineering and Applications and Advances in Applied Modeling.

How to reference

In order to correctly reference this scholarly work, feel free to copy and paste the following:

Pavan K. Vempaty, Ka C. Cheok, and Robert N. K. Loh (2011). Experimental Implementation of Lyapunov based MRAC for Small Biped Robot Mimicking Human Gait, *Advances in Computer Science and Engineering*, Dr. Matthias Schmidt (Ed.), ISBN: 978-953-307-173-2, InTech, Available from:
<http://www.intechopen.com/books/advances-in-computer-science-and-engineering/experimental-implementation-of-lyapunov-based-mrac-for-small-biped-robot-mimicking-human-gait>

INTECH
open science | open minds

InTech Europe

University Campus STeP Ri
Slavka Krautzeka 83/A
51000 Rijeka, Croatia
Phone: +385 (51) 770 447
Fax: +385 (51) 686 166
www.intechopen.com

InTech China

Unit 405, Office Block, Hotel Equatorial Shanghai
No.65, Yan An Road (West), Shanghai, 200040, China
中国上海市延安西路65号上海国际贵都大饭店办公楼405单元
Phone: +86-21-62489820
Fax: +86-21-62489821

© 2011 The Author(s). Licensee IntechOpen. This chapter is distributed under the terms of the [Creative Commons Attribution-NonCommercial-ShareAlike-3.0 License](https://creativecommons.org/licenses/by-nc-sa/3.0/), which permits use, distribution and reproduction for non-commercial purposes, provided the original is properly cited and derivative works building on this content are distributed under the same license.

IntechOpen

IntechOpen