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bipedal locomotion is among the most difficult challenges in control engineering most books treat the subject from a quasi static perspective overlooking the hybrid nature of bipedal mechanics feedback control of dynamic bipedal robot locomotion is the first book to present a comprehensive and mathematically sound treatment of feedback design for achieving stable agile and efficient locomotion in bipedal robots in this unique and groundbreaking treatise expert authors lead you systematically through every step of the process including mathematical modeling of walking and running gaits in planar robots analysis of periodic orbits in hybrid systems design and analysis of feedback systems for achieving stable periodic motions algorithms for synthesizing feedback controllers detailed simulation examples experimental implementations on two bipedal test beds the elegance of the authors approach is evident in the marriage of control theory and mechanics uniting control based presentation and mathematical custom with a mechanics based approach to the problem and computational rendering concrete examples and numerous illustrations complement and clarify the mathematical discussion a supporting site offers links to videos of several experiments along with matlab code for several of the models this one of a kind book builds a solid understanding of the theoretical and practical aspects of truly dynamic locomotion in planar bipedal robots

covers receipts and expenditures of appropriations and other funds

this text will serve as a quick reference and review for residents as well as practising physicians it also offers information needed in related professions

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