

Balancing of the anthropomorphous robot walking

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Abstract

Anthropomorphic robots are designed a human environment operates: buildings and structures, cabs and etc. The movement of these robots is carried out by walking which provides high throughput to overcome natural and manmade obstacles. The article presents some algorithm results for dynamic walking on the anthropomorphic robot AR601 example. The work is performed according to the Russian Government Program of Competitive Growth of Kazan Federal University.

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