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The team engineered the robot as simply a torso and two legs, and designed the system specifically to test lower-body tasks, such as locomotion and balance. As with its full-body counterpart, Little HERMES is designed for teleoperation, with an

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operator suited up in a vest to control the robot's actions.

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Locomotion over different terrain
types, whether flat or uneven, is very
important for a wide range of service
operations in robotics. Potential

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Wheeled-legged hexapod robots have been designed to solve these locomotion tasks. Given the wide range of feasible operations, one of the key operation planning issues is related to ...

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Gonzalez¹, Victor Barasuol, Marco
Frigerio², Roy Featherstone³, Darwin
G. Caldwell³, Claudio Semini¹

Abstract—The ability of legged systems to traverse highly-constrained environments depends by and large on the performance of their motion and balance controllers. This paper

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