

The Quadruped Robot "Tekken-I"

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- Autonomous adaptation to irregular terrain
- Motion generation and adaptation based on biological concepts
- CPG (Central Pattern Generator) and reflexes
- Rolling motion feedback to CPG
- All parameters are fixed for kinds of irregular terrain



The "Scout II" Quadruped Robot

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- Excitation of passive dynamics to produce stable dynamic locomotion
- One active degree of freedom per leg (rotary motor)
- One passive degree of freedom per leg (prismatic spring)
- Capable of the Bound symmetric gait
- Capable of the Half-Bound asymmetric gait

