

Title	時間対称な制御入力信号と引き込み効果に基づく 2脚ロボットの高効率かつ頑健な歩容生成
Author(s)	顔, 聡
Citation	
Issue Date	2023-03
Type	Thesis or Dissertation
Text version	ETD
URL	<a href="http://hdl.handle.net/10119/18419">http://hdl.handle.net/10119/18419</a>
Rights	
Description	Supervisor:浅野 文彦, 先端科学技術研究科, 博士

氏名	YAN, Cong		
学位の種類	博士 (情報科学)		
学位記番号	博情第 493 号		
学位授与年月日	令和 5 年 3 月 24 日		
論文題目	Efficient and Robust Gait Generation for Biped Robots Based on Time-symmetric Control Input Signals and Entrainment Effects		
論文審査委員	浅野 文彦	北陸先端科学技術大学院大学	准教授
	平石 邦彦	同	教授
	池 勇勳	同	准教授
	徳田 功	立命館大学	教授
	原田 祐志	愛知工業大学	准教授

## 論文の内容の要旨

Bipedal robots can operate in more restricted environments than multi-legged and wheeled robots, and most conventional bipedal robots are driven by actuators at each joint with precise joint angle control to follow a target trajectory for walking motion. In typical motion control methods for bipedal robots, the ZMP (zero moment point), the point at which the combined forces of gravity and inertia are projected onto the road, is the standard for stable walking, but it is commonly noted that this control method does not make excellent use of its own EI (embodied intelligence) to improve walking efficiency and to obtain a natural gait. Moreover, the robot requires precise real-time feedback control to achieve stable walking in a fully-actuated manner, which results in huge energy loss and cannot be sustained for long periods of time in real-world environments. Therefore, in recent years, numerous researchers have focused on how to use body dynamics to control robots to maintain efficient motion. The most significant challenge in this research direction is to improve walking efficiency while having available robustness.

By exploiting the dynamics dictated by the robot's body structure, the robot can not only considerably improve the efficiency of its motion but also considerably reduce its computational effort and thus the difficulty of control. Nonetheless, the fundamental problem with this approach is that the expected behavior of the system is highly dependent on environmental conditions, which leads to a lack of robustness. For example, a passive walking robot could use its body dynamics to walk down a slope in a deep natural way without any input. However, it can only function under the constraints of a suitable slope angle and ground friction. Another example is the CPG (central pattern generator), a local oscillatory network composed of neurons, which generates stable phase-locking relationships through mutual inhibition between neurons and produces rhythmic movements at relevant parts of the soma through self-excited oscillations. The CPG-based approach to motion control simulates the temporal sequencing of animal walking, which is a more natural approach for robotic motion control problems. However, an extremely large number of term conditions typically require attention when constructing CPG models, resulting in control methods that are still not concise enough.

In this paper, the author aims to explore more underlying mechanisms of walking and achieve a more simple and more efficient method of motion control for bipedal robots. We can draw on two signal systems acquired by humans during evolution, namely the first and the second signal system. A similar classification of signal systems can be made for the generation of robotic motion. The former is used to reliably generate and maintain elementary

motions, while the latter is used to adapt flexibly to complex environments where each system operates in a shared and coordinated manner. First, a minimalist compass-like bipedal robot where only the hip torque can be applied, so the robot is an underactuated system. Here the bipedal robot can be made to walk efficiently and stably on downhill as well as horizontal surfaces by means of entrainment effects, using a reasonable feedforward input waveform (e.g., a sine wave). It can be regarded as the motion generation of the control signal (first signal system) generated at the level of human reflexes without any feedback control, which greatly reduces the cost of control. At the same time, step length, walking frequency, and walking speed, which are important indicators of walking within the entrainment range, can be simply tuned by controlling the parameters.

To ensure the practical feasibility of the proposed method, it is necessary to conduct an experimental study to verify whether entrainment effects can successfully control a robot to generate dynamic walking in a realistic environment. A bipedal walker was designed and fabricated to allow for practical experiments. The control method is consistent with that used in the simulation, where a designed planetary gear mechanism is used to complete gait generation on a horizontal road surface by feeding a preset feed-forward waveform through a hip-only servo motor. It should be noted that in order to avoid gait failure due to foot scuffing while swinging the leg, the rotator foot is designed to circumvent it. Although the 1:1 entrainment between the input waveform frequency and the actual walk frequency is only achieved due to hardware conditions, the experimental results are in good agreement with the numerical simulations.

In order to pursue higher walking performance, such as high-speed walking, and to obtain the highest energy utilization while limiting the walking speed, the author performs a global optimization of the control parameters, as well as the physical parameters of the robot itself, by means of Bayesian optimization. The results show that the fastest walking speed occurs in a 2:1 entrainment waveform when only the control parameters are changed, while the fastest walking speed can be achieved in a 1:1 entrainment waveform after optimizing the foot shape, which indicates that the structural design of the robot itself, such as the foot shape and the overall center of gravity distribution, is also important. The results for walking efficiency show that while maintaining a walking speed of 0.5 [m/s] or more, SR can be as low as 0.007 (lower values indicate higher walking efficiency) by the proposed control method, which is much lower than the current robots by conventional control methods and even better than humans.

In bipedal dynamic walking, one also usually expects the gait to converge to a limit cycle gait. From another point of view, the most basic requirement for achieving stable bipedal walking is not to fall, which requires a large BOA (basin of attraction) to tolerate disturbances. Chaotic oscillators tend to have larger basins of attraction compared to the limit cycle. Correspondingly, it is hypothesized in this paper that a properly generated chaotic bipedal gait due to entrainment effects may be more robust to perturbations such as walking on uneven ground. Based on this consideration, a chaotic gait is generated by employing a typical chaotic oscillator Rössler attractor. It was shown that the chaotic bipedal gait has a larger BOA than the limiting periodic walk with the same input strength, and the domain of stable walking was further explored by varying the control parameters of the chaotic bipedal gait.

Work so far has focused on exploring the robot's walking conditions under the first signal system and generating relatively stable and efficient gaits. The judgment of more complex road conditions requires advanced signal processing capabilities corresponding to a second signaling system. The present work lays the groundwork

for further research, not only by enabling bipedal walking on uneven ground with extremely simple control methods but also by showing the positive side of chaos in dynamic walking and providing a new perspective on the stability of bipedal gait.

Keywords: Bipedal robot, Passive walking, Entrainment, Rimless wheel, Semicircular feet, Chaotic gait, Stability, Efficiency

## 論文審査の結果の要旨

脚移動ロボットのリミットサイクル歩容生成においては、適切な駆動力を印加することで立脚中期のポテンシャル・バリアを突破し、かつ支持脚交換の衝突で失う運動エネルギーを回復する必要がある。一定トルクでもこれらの条件を達成することは可能であるが、固有の振幅や周期をもたない信号であるため、生成される歩容の頑健性は期待できない。以上を踏まえ本論文は、思考を経由しない単純な、しかし固有の振幅と周期をもつフィードフォワード型の信号、特に 1 歩分の時間積分値がゼロとなる立脚中期を中心とした時間的対称性を有する制御入力信号により駆動される劣駆動脚移動ロボットの運動生成、および非線形力学特性に関する基礎的考察を行ったものである。

論文の前半では、まず最も単純なものとして立脚前期に加速、立脚後期に減速をする矩形波として記述される信号を導入し、これを股関節トルクとして印加したコンパス型 2 脚モデルが空間的に非対称な軌道を生成すること、その結果としてエネルギー回復が達成され安定歩容生成が可能となることを示した。次に正弦波として記述される信号を導入し、その振幅と固有振動数を適切に設定することで引き込み現象が起り 1 周期の安定歩容生成が可能となること、また入力と歩行運動の振動数が 1:1 である場合に歩行性能が最大となること、更には移動効率を悪化させることなく歩行の高速化が達成されることを示した。また 2 脚ロボットの実機を開発し、正弦波信号による歩容生成可能性を実験的にも確認した。更には、上記の歩行特性が遊脚自由度をもたないリムレスホイール型モデルでは得られないこと、半円足の力学効果を期待できない場合でも 2 脚モデルであれば実現し得ることなどの力学的性質を明らかにすることで、遊脚自由度の存在意義と必要性を説いた。

論文の後半では、長期の時間積分値がゼロに近い準時間的対称性をもつ信号としてレスラー方程式系から生成されるカオスの信号を導入し、これを股関節トルクとして生成されるリミットサイクル歩容のロバスト性について考察を行った。正弦波信号により生成される歩容との比較を通して、カオスの信号が安定歩容生成可能な初期状態の範囲を拡大することを示した。これまでにリミットサイクル歩行系における分岐現象やカオスの挙動の現象論的研究は多数の報告がなされてきたが、工学的応用に関する成功例は存在していなかった。その中で本研究結果は、カオスの歩容の優位性を示唆する新規かつ重要な知見を与えるものと評価することができる。

以上、本論文は、劣駆動脚移動ロボットの高効率かつ頑健な歩容生成法の提案、運動の時空対称性に関する考察、および非線形現象の解析とカオスの歩容の優位性に関する検討を行ったものであり、学術的に貢献するところが大きい。よって博士（情報科学）の学位論文として十分価値あるものと認めた。