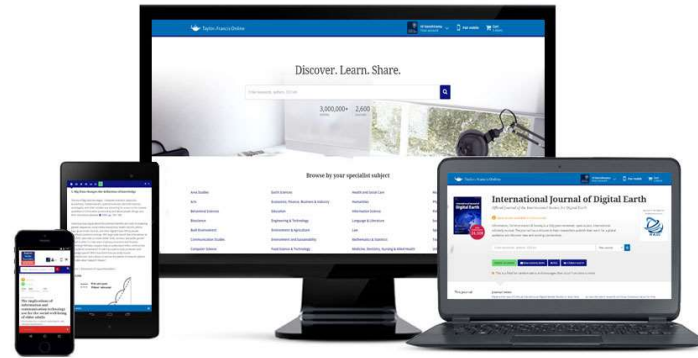




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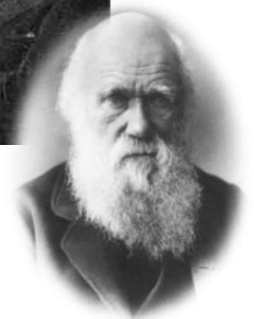
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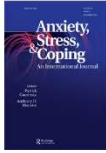

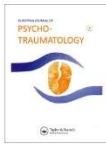


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Itsumoto, Takumi Kawasetsu & Koh Hosoda

2023, Accepted 29 May 2023, Published online: 26 Jun 2023

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Abstract

Quadrupedal animal, such as dogs, typically have soft but heavy abdomens, whose swinging motion significantly contribute to the energy efficiency of their entire locomotion. This study examines the effect of a swinging mass on quadrupedal locomotion by simulating the soft abdomen of its biological counterparts. A quadruped robot is designed with a swinging mass beneath its trunk. Its pitching motion was evaluated by a mechanical model. The experiment results demonstrate that the swinging mass effectively reduces the pitching motion, thereby improving the energy efficiency of the robot. Although the swinging mass does not always guarantee the energy efficiency of locomotion, the spring stiffness that supports the mass can be obtained for energy-efficient locomotion.

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Figure 9 of 10
Figure 9. Pitch angle θ_p (black line; left axis) and angle formed by the trunk and pendulum $\theta_s - \theta_p$ (dash line; right axis). (a) $k_s = 0$ [N m/rad], (b) $k_s = 7.0$ [N m/rad] (c) rotational center fixed. The horizontal dash line indicates 0 [deg] on the θ_p axis and 90.0 [deg] on the $\theta_s - \theta_p$ axis.

(a) $k_s = 0$ [N m/rad]: The pitch angle θ_p (black line) oscillates between approximately -10 and 20 degrees. The trunk-pendulum angle $\theta_s - \theta_p$ (dashed line) oscillates between approximately 60 and 120 degrees.

(b) $k_s = 7.0$ [N m/rad]: The pitch angle θ_p (black line) oscillates between approximately -10 and 20 degrees. The trunk-pendulum angle $\theta_s - \theta_p$ (dashed line) oscillates between approximately 60 and 120 degrees.

(c) rotational center fixed: The pitch angle θ_p (black line) oscillates between approximately -10 and 20 degrees. The trunk-pendulum angle $\theta_s - \theta_p$ (dashed line) oscillates between approximately 60 and 120 degrees.

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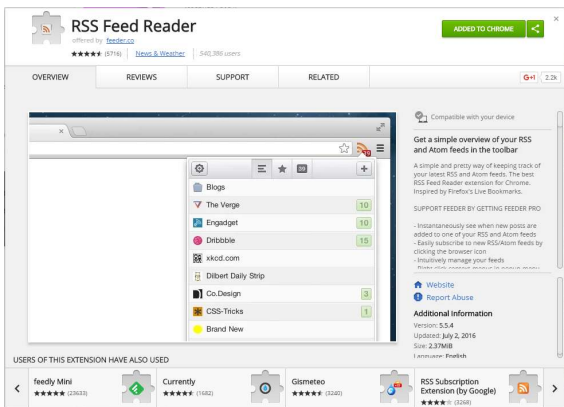
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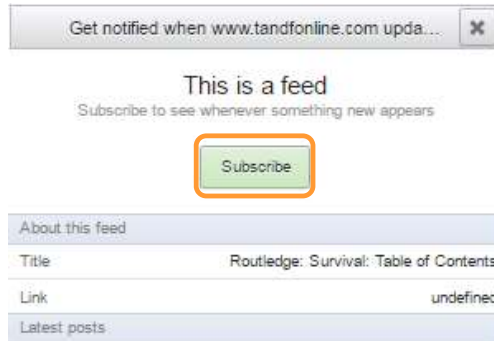
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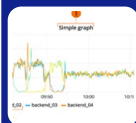
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