Contents

Acknowledgements v

Abstract vii

List of Figures xi

List of Tables xxi

1 Introduction 1

Introduction 1

2 Investigation of Human-Human Interactive Locomotion 13
2.1 Introduction . . . 13
2.2 Human-human interactive locomotion: experiments . . . 14
2.2.1 Methods . . . 14
2.2.2 Main results . . . 18
2.3 Discussion . . . 23

3 Modelling of Interactive Locomotion 25
3.1 Introduction . . . 26
3.2 The model of human-human interactive locomotion . . . 27
3.2.1 SLIP model . . . 27
3.2.2 Paired SLIPs model . . . 28
3.3 Periodic solutions of the model . . . 31
3.3.1 Systematic search . . . 31
3.3.2 An example of a synchronized gait . . . 32
3.4 Data comparison . . . 34
3.4.1 Simulation of the paired behaviour by fitting the experimental paired trial data . . . 35
3.4.2 Simulation of the paired behaviour by fitting the experimental solo trial data . . . 35
3.4.3 Methods and results . . . 36
3.5 The simplified model of human-human interactive locomotion . . . 39
3.5.1 AMP Model . . . 40

3.5.2 Paired AMPs Model . . . 41
3.5.3 Systematic Search . . . 43
3.5.4 Simulation Results . . . 45
3.6 Discussion . . . 47

4 Human Intentions Detection as a Multiclass Classification Problem 51
4.1 Introduction . . . 52
4.2 Human-Human Experiments . . . 54
4.2.1 Data Preprocessing and Labeling . . . 55
4.3 Human Intention Detection As a Classification Problem . . . 57
4.3.1 Features Extraction . . . 58
4.3.2 Classification model . . . 60
4.3.3 Feature Optimization . . . 60
4.4 Supervised Learning Results . . . 61
4.4.1 Single Variable Classification (SVC) . . . 61
4.4.2 Multiple Variables Classification (MVC) . . . 62
4.5 Robot's Modular Control Scheme . . . 63
4.6 Robotics Experiments . . . 65
4.6.1 Start-Stop Test Results . . . 66
4.6.2 Acceleration-Deceleration Test Results . . . 67
4.7 Conclusion . . . 67

5 A Modular Control Architecture for two Humanoids Carrying an Object Together 71
5.1 Introduction . . . 71
5.2 The Decentralized Modular Control Architecture . . . 75
5.2.1 Overview . . . 75
5.2.2 Our Approach . . . 76
5.2.3 Walking Controller . . . 76
5.2.4 Posture Controller . . . 77
5.2.5 Hybrid Force-Position Controller . . . 81
5.2.6 End-Effector Orientation Controller . . . 81
5.3 Experiments . . . 82
5.3.1 Experimental Validation of each Control Module . . . 82
5.3.2 Collaborative Carrying of Objects . . . 84
5.3.3 Simulation . . . 90
5.3.4 Discussion . . . 94
5.4 Conclusion . . . 96

6 Conclusion 97

A Appendix 103
A.1 Real Conditions Score (Chapter 3) . . . 103
A.2 Arnold Tongue for two coupled phase oscillators (Chapter 5) . . . 104