

Humanoid hip workout

Author: @stephane-caron

Consider a humanoid robot in the following configuration:

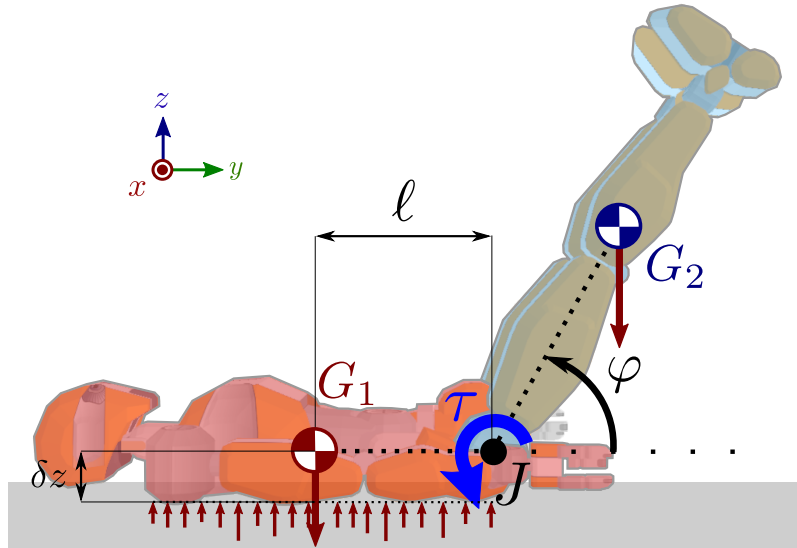


Figure 1: JVRC humanoid model lying on a horizontal floor.

We consider the problem in the sagittal plane. The robot is lying on a horizontal floor, holding a static posture where its hips are making an angle φ with the horizontal.

Let us denote by m_1 and G_1 the total mass and center of gravity of the robot's upper body (all links above the hips, red in Figure 1), and similarly m_2, G_2 for the legs (blue in Figure 1).

- **Question 1:** What angle φ maximizes the hip torque τ ?

We assume that all forces between the floor and the back of the robot are exerted over a horizontal surface located at an altitude δz below the center of gravity G_1 .

- **Question 2:** What is the critical angle φ_{tilt} beyond which the robot cannot keep its back flat on the floor?