

A Motion Planning Method Based on HRL for Autonomous Exoskeleton

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- Propose a Motion Planning algorithm(HPPO) to solve the path planning and gait policies of autonomous exoskeleton(Auto-LEE) .
- HPPO contains two levels: High-level path planning controller (HL); Low-level gait generation controller(LL).
- HL is responsible for planning a reasonable path in various complex terrains; LL generates a movement gait and executes actions to complete the interaction with the environment

