

Low-Profile Crawling for Humanoid Motion in Tight Spaces

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- Low-profile crawling gait for humanoid robots to enable operation in tight vertically constrained spaces, thus expanding the range of environments and tasks that can be handled
- Laterally symmetric periodic gait with cooperative motion of both arms and feet to generate forward crawling motion; Gait design based on a projected profile model
- Experimental implementation on NAO humanoid robot

