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Learning a Contact-Adaptive Controller for Robust, Efficient Legged Locomotion

Robust controllers enable efficient qudruped locomotion which requires execution various complex gaits. The work proposes a hierarchical framework for robust control of a quadruped. The hierarchical system consists of a high level controller which makes use of Reinforcement Learning (RL) to select primitives. The low level controller learns contact adaptive behavior based on these primitives using Quadrtic Programming (QP). The end-result of hierarchical framework is a robust and energy-efficient physical robot controller which generalizes to tasks not seen during training.