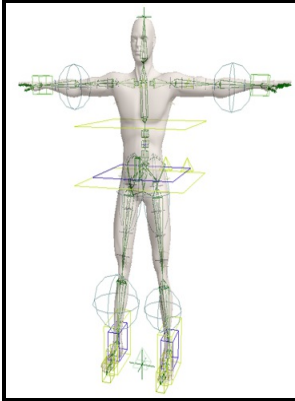


# Controlling bipedal locomotion for computer animation

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Description: -

-Controlling bipedal locomotion for computer animation

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Canadian theses = -- Thèses canadiennesControlling bipedal locomotion for computer animation

Notes: Thesis (M.Sc.) -- University of Toronto, 1996.

This edition was published in 1996



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## CiteSeerX — Controlling Bipedal Locomotion For Computer Animation

It has a number of layout errors but was pretty impressive at the time.

### Joe Laszlo's M.A.Sc. Thesis

The representation also permits the animator to define procedures with general instructions that can be automatically executed by the controller during the dynamics simulation. However, despite the grace and agility with which many living creatures effortlessly perform skilled motions, modeling motor control has proven to be a difficult problem

### Evolutionary generation of human

The control requires no character-specific or motion-specific tuning, is robust to disturbances, and is simple to compute. An optimized control policy is then computed using reinforcement learning.

### Joe Laszlo's M.A.Sc. Thesis

This thesis proposes an approach to generating balanced 3D walking motions for physically-based computer animations by viewing the motions as a sequence of discrete cycles in state space. The control requires no character-specific or motion-specific tuning, is robust to disturbances, and is simple to compute.

## CiteSeerX — Controlling Bipedal Locomotion For Computer Animation

Building on recent advances, this thesis presents several approaches to creating control policies that allow physically-simulated characters to demonstrate skill and purpose as they interact with their virtual environments.

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