Controlling bipedal locomotion for computer animation

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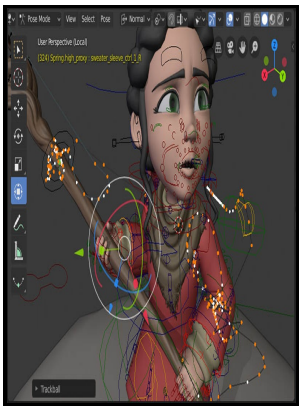

Description: -
-Controlling bipedal locomotion for computer animation
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Notes: Thesis (M.Sc.) -- University of Toronto, 1996.
This edition was published in 1996

Tags: #CiteSeerX #— #Controlling #Bipedal #Locomotion #For #Computer #Animation

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This allows our characters to complete higher-level locomotion tasks, such as walking in a user specified direction, while interacting with the environment in significant ways. In this paper, we applied genetic programming to induce the model of the nervous system automatically and showed its effectiveness by simulating a human bipedal gait with the obtained model. The sensors can be optimized, facilitating their definition and use.

Joe Laszlo's M.A.Sc. Thesis

Abstract Understanding and reproducing the processes that give rise to purposeful human and animal motions has long been of interest in the fields of character animation, robotics and biomechanics.

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Lastly, we describe a control strategy for walking that generalizes well across gait parameters, motion styles, character proportions, and a variety of skills. A constrained state exploration phase is first used to define a dynamics model as well as a finite volume of character states over which the control policy will be defined.

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In addition to other interesting variations, the speed, stride rate and direction of a walk can each be controlled.

Real

The representation also permits the animator to define procedures with general instructions that can be automatically executed by the controller during the dynamics simulation. Third, the dynamics model is exploited by a planner to solve new instances of the task in real-time. The control requires no character-specific or motion-specific tuning, is robust to disturbances, and is simple to compute.

Joe Laszlo's M.A.Sc. Thesis

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