

NEXT LEVEL INNOVATION IN ROBOTICS AND AUTONOMY

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Title: A learning based approach to extract gaits for a quadruped.

We will describe our approach to use deep reinforcement learning to learn the motion gaits of our custom-made quadruped. A model of the quadruped is used to learn the actions to generate walking motion, via DRL based training in PyBullet. The learnt gaits are then transformed to extract motion primitives and ported to a resource constrained platform to generate the actual actuator commands.