

CONFÉRENCES INTERNATIONALES DE LA THÉMATIQUE CONCEPTION BIOMIMÉTIQUE ET COMMANDE 2010 - 2014

Conférences internationales avec comité de lecture et actes 2010 - 2014

2012

M. Souissi, V. Hugel, P. Blazevic, "Design optimization of parallel joint mechanism for humanoid spine", Proc. of the 16th IEEE Mediterranenan Electrotechnical Conference (MELECON), 2012, pp. 997-1000.

M. Souissi, V. Hugel, P. Blazevic, "Modeling and simulation of humanoid robot spine vertebra", Proc of the 9th International Conference on Informatics in Control, Automation and Robotics, Vol. 2, 2012, pp. 415-418.

V. Hugel and N. Jouandeau, "Walking Patterns for Real Time Path Planning Simulation of Humanoids", Proc. of the 21st IEEE International Symposium on Robot and Human Interactive Communication (2012 IEEE RO-MAN), 2012, pp. 424-430.

C. Cibert and V. Hugel, "Bio-Inspired Compliant Spine for Humanoid Robot: A Degrees of Freedom Challenge", Proc. of the 21st IEEE International Symposium on Robot and Human Interactive Communication (2012 IEEE RO-MAN), 2012, pp. 1-5.

2011

V. Khomenko, O. Bruneau, F.B. Ouezdou, P. Hénaff, A. Melnyk, V. Borysenko “Non-Invasive Low Cost Method for Linear and Angular Accelerations Measurement in Biped Locomotion Mechanisms ”,IEEE Proc. of SENSORS 2011, pp. 1756-1759, Limerick, October 28-31, Ireland, 2011

J.-C. Palyart Lamarche, O. Bruneau and J.-G. Fontaine,“Time-Independent, Spatial Human Coordination For Humanoids”, IEEE Proc. of Intelligent Robots and Systems, 2011, IROS 2011, pp. 3951-3956, IEEE/RSJ International Conference, San Fransisco, California,
USA, September 25-30, 2011.

A. Tayebi, A. Roberts and A. Benallegue, “Inertial Measurements Based Dynamic Attitude Estimation and Velocity-Free Attitude Stabilization”, in American Control Conference (ACC’2011), San Francisco, California, USA June 29 - July 1, 2011.

2010

J.-C. Palyart Lamarche, O. Bruneau and J.-G. Fontaine “ Humanoid Walking Coordination Through a Single Spatial Parameter ”, IEEE-RAS International Conference on Humanoid Robots, Humanoids10, pp. 230-236, December 6-8, 2010, Nashville, TN, USA.

P.-F. Doubliez, O. Bruneau and F. Ben Ouezdou, “Dynamic obstacle crossing by a biped robot, based on control of the propulsion energy”, IEEE Proc. of Intelligent Robots and Systems, 2010, IROS 2010, pp. 3144-3149, IEEE/RSJ International Conference, Taipei, Taiwan, October 18-22, 2010.

J.-C. Palyart Lamarche, O. Bruneau and J.-G. Fontaine, “ The Current Humanoids with Seven Degrees of Freedom per Leg are not Sufficient to Accurately Reproduce Human Walking Kinematics ”, International Conf. on Climbing and Walking Robots, CLAWAR

2010, pp. 467-474, Nagoya, Japan, 31 August- 3 September, 2010.

L. Derafa, L. Fridman, A. Benallegue and A. Ouldali “Super Twisting Control Algorithm for the Four Rotors Helicopter Attitude Tracking Problem” in the 11th IEEE International Workshop on Variable Structure Systems (VSS’2010), June 26-28, 2010, Mexico City, Mexico.

N. Gachadoit, A. El Hadri, A. Benallegue, A. Seba and B. Vidalie “Advanced Modeling with a Symbolic Based Approach Application to the Modeling, Control Design and Real-Time Control and HIL Simulation of a Quadrotor Helicopter” in European Congress in Embedded Real Time Software and Systems (ERTS’2010), May 19-21, Toulouse, France.