STARLETH: A COMPLIANT QUADRUPEDAL ROBOT FOR FAST, EFFICIENT, AND VERSATILE LOCOMOTION

MARCO HUTTER, CHRISTIAN GEHRING, MICHAEL BLOESCH, MARK A. HOEPFLINGER, C. DAVID REMY, and ROLAND SIEGWART
Autonomous Systems Lab, Institute of Robotics and Intelligent Systems, Swiss Federal Institute of Technology (ETHZ), Zurich, Switzerland, mahutter@ethz.ch

This paper introduces StarlETH, a compliant quadrupedal robot that is designed to study fast, efficient, and versatile locomotion. The platform is fully actuated with high compliant series elastic actuation, making the system torque controllable and at the same time well suited for highly dynamic maneuvers. We additionally emphasize key elements of a powerful real time control and simulation environment. The work is concluded with a number of experiments that demonstrate the performance of the presented hardware and controllers.

Keywords: compliant quadruped, legged locomotion, torque control, SEA

1. Introduction

Inspired by locomotion in nature, research in legged robotics is currently undergoing substantial changes. In contrast to the early walking machines [1] which were built stiff and controlled kinematically, more and more compliant systems are nowadays finding their way into robotics; thereby offering an entirely new field of research. Due to their mechanical softness in terms of back-drivability and low system inertia, these systems are perfectly suited to continuously interact with their environment. They can cope with (unexpected) ground contact collisions and are at the same time inherently safe for hand-in-hand collaboration with human operators. Similar to nature, where compliant elements in muscles and tendons largely contribute to the energetic efficiency [2,3], springs can be exploited in robotics to support non-linear oscillations.

*This research was supported by the Swiss National Science Foundation through the National Centre of Competence in Research Robotics, as well as by the Hans Eggenberger Foundation.
2. Hardware Description

StarlETH is based on four identical legs that are arranged in an X configuration. With linear dimensions of about 0.6 m and a total weight of 23 kg, it has the size of a medium-sized dog. Every leg has a total of 3 degrees of
Table 1. Key data of StarlETH

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>total leg length</td>
<td>488.5 mm</td>
</tr>
<tr>
<td>leg segment length</td>
<td>200 mm</td>
</tr>
<tr>
<td>total mass</td>
<td>23 kg</td>
</tr>
<tr>
<td>payload</td>
<td>25 kg</td>
</tr>
<tr>
<td>max. hip AA,FE torque</td>
<td>24 Nm</td>
</tr>
<tr>
<td>max. knee torque</td>
<td>40 Nm</td>
</tr>
<tr>
<td>max. hip AA,FE speed</td>
<td>600 °/s</td>
</tr>
<tr>
<td>max. knee speed</td>
<td>350 °/s</td>
</tr>
<tr>
<td>motor power</td>
<td>200 W</td>
</tr>
</tbody>
</table>

Note: 1. abduction/adduction, 2. flexion/extension

freedom, one each for hip abduction/adduction, hip flexion/extension, as well as knee flexion/extension. The robot’s design is based on earlier studies that we conducted to optimize a planar running leg [7,8]. This leg was extended with an abduction degree of freedom. The key data of the mechanics as well as the actuation are summarized in Table 1. We put emphasis on keeping the inertia of the moving segments minimal by concentrating all actuators at the main body through the use of chain and cable pulley systems. This is beneficial to ensure fast swing leg motion and to reduce impact losses at the intermittent ground contact. The lightweight main body is fabricated as a carbon fiber sandwich monocoque with aluminum front- and back connectors. It contains well protected all electronic parts that are cooled through active air circulation. The key elements of StarlETH are the high compliant series elastic actuators that are implemented in all joints using linear compression springs in a pre-compressed setup (antagonistically at the hip joints). Springs decouple the motor (Maxon EC-4pole 200 W) and gearbox (Harmonic Drive CSG-14, 1:100 reduction) from the joint. This setup ensures robustness against impacts, allows for energy storage to improve the efficiency [7], and provides full torque controllability. All joint angles, motor angles, and spring deflections are precisely measured in every joint [8]. The lightweight ball feet (70 g, Figure 3(b)) are based on air filled racquet balls that provide ample cushioning with minimal weight while having a high contact friction coefficient. To detect changes in the contact force, we tightly integrated force sensing resistors (FSR). The proprioceptive sensor equipment is completed with a X-sense MTi IMU that includes an accelerometer and gyroscopes.

3. Simulation and Control Framework

Controlling highly complex and inherently unstable systems like StarlETH with 12 actuated joints and 6 unactuated (floating base) degrees of freedom in an often unknown environment requires a very powerful and reliable
control setup. After several iterations through different configurations, we realized a framework as depicted in Figure 2. The setup is based on a single centralized host-PC that is responsible for the entire high-level control part. The software contains the real-time simulation and control environment SL [9], which is used as a multi-body dynamics engine, for visualization of the robot and its environment, as well as for handling the internal messaging between the different servos through shared memory. It additionally provides tools for data logging and post-processing.

As a core element, the motor servo is responsible for timing and coordination of the individual actuators. It contains all low level regulators (position, velocity, torque, ...) and signal filters. Using either shared memory to access the simulation, or a CAN gateway to communicate with the actual robot, the user has the possibility to run simulations and experiments (even in parallel) with exactly the same controller implementation. This is highly advantageous for controller development, since it avoids code reimplementation, simplifies debugging and testing, and ensures certain safety if the controllers show good robustness in the simulation.

Fig. 2. The real-time simulation and control environment is based on SL [9] and analytical global kinematics and dynamics. The framework allows an immediate exchange of simulation and actual robot, as well as a direct integration into ROS.
The ROS servo provides an interface to the robotic operation system that can not meet the hard real-time constraints of SL itself. This connection opens the door to a huge set of existing interfaces to different sensors and existing software packages. In our current setup, this includes the IMU, the Microsoft Kinect sensor, as well as several external devices such as a 3D joystick for control or a vicon motion capture system to track the main body position/orientation.

Finally, the task servo decouples the controller entirely from the multi-body simulation and provides the global kinematics and dynamics (robot model) of the system in analytical form. Therefore, we developed proNEu [10], a MATLAB framework that uses the Symbolic Math toolbox\textsuperscript{a} to translate a relative kinematic tree into global kinematics using Euler rotations, and to derive the system dynamics using projected Newton-Euler equations. In addition to speed and simplicity of the implementation, this separation between the model used in the controller and the simulation has several benefits. First of all, the control engineer has user friendly access to any kind of updated kinematic or dynamic parameters. Second, sensor noise, imperfect state estimation, or (intentionally) introduced differences between simulation and controller allows to test the robustness of the controller against modeling errors and limits the problematic of instable plant inversion. The state estimator which is implemented on top of the robot model fuses kinematic information with the IMU sensor signals. It is based on an Extended Kalman filter [11] and estimates not only the base coordinates but is also able to generate a sparse ground elevation map using the contact feet.

In practice, the rate-limiting factor in our framework is the data connection of the CAN bus system between the host PC and the motor controllers. Although we managed to parallelize 4 channels (1 per leg), the bit rate of 1 MBits/s limits the overall loop cycle time to about 400 Hz.

4. Experimental Results

In the first part of the experimental validation, we are focusing on hardware performance. First of all, walking and running machines need to provide sufficient torque that enables them to conduct various maneuvers. A representative scenario is standing up from a completely crouched position with maximal payload (Figure 3(a)). Due to the high power per weight ratio, we are able to stand up with a payload of 25 kg. This is more than the total weight of the actual robot and considerably better than for systems

\textsuperscript{a}www.mathworks.com/products/symbolic
such as Little Dog [12] or ALoF [13]. In theory, the peak torque at the
knee of 40 Nm with a lever arm of 0.2 m results in a maximal total lift force
of 800 N or a maximal stand-up payload of \( \approx 50 \) kg. However, these peak
loads should only occur in highly dynamic maneuvers and were hence not
experimentally validated for safety reasons.

To be capable to perform dynamic maneuvers, it is crucial that the
system can cope with impacts. In contrast to a stiff system (again c.f. Little
Dog [12] or AloF [13]), pre-impact kinetic energy should not be entirely
dissipated in an collision that harms the mechanical structure. Instead, the
system is able to either damp out a certain amount of energy or to store it as
potential energy in the actuator springs. To demonstrate both, we dropped
Star\textit{ETH} from a height of \( \approx 0.5 \) m. The passive mechanical compliance
in the actuators, as well as the high damping feet elements protect the
system from the impact at landing. This ensures that, even if all motors
are blocked, none of the gearboxes gets damaged through high peak forces.
The high compliant springs lead to large oscillations (red-dotted line in
Figure 4) including a number of short rebounces (grey background) after
landing. This can be avoided through active damping (black-solid line in
Figure 4) using a virtual model controller that exerts the force \( \mathbf{F}_{mb} \) and
torque \( \mathbf{M}_{mb} \) at the main body

\[
\mathbf{F}_{mb} = k_p (\mathbf{r}_{des} - \mathbf{r}_{act}) + k_d (\dot{\mathbf{r}}_{des} - \dot{\mathbf{r}}_{act}) \\
\mathbf{M}_{mb} = k_p (\varphi_{des} - \varphi_{act}) + k_d (\dot{\varphi}_{des} - \dot{\varphi}_{act})
\]
Fig. 4. The vertical main body position of the system dropped from \( \approx 0.5 \text{m} \) was estimated using IMU values during flight and kinematic information during contact phase: the red-dotted curve shows the high oscillations due to the passive compliance with intermittent flight phases (grey area), while active damping (blue-solid) using virtual model control ensures nearly critical damping of the system.

with \( \mathbf{r}, \varphi \) representing the main body position and orientation and the spring and damping constant \( k_p, k_d \). In combination with additional gravity compensation \( \mathbf{F}^g_j = -m_j \mathbf{g} \) for the \( N_p = 4 \cdot 3 + 1 \) bodies, the force is distributed onto the different contact forces \( \mathbf{F}^c_i (N \leq 4) \):

\[
\begin{pmatrix}
\mathbf{F}^c_1 \\
\vdots \\
\mathbf{F}^c_N
\end{pmatrix} = 
\begin{bmatrix}
\mathbf{I} & \cdots & \mathbf{I}
\end{bmatrix}^+ 
\begin{pmatrix}
\mathbf{F}_{mb} - \sum_{j=1}^{N_b} \mathbf{F}^g_j \\
\mathbf{M}_{mb} - \sum_{j=1}^{N_b} \mathbf{r}^g_j \times \mathbf{F}^g_j
\end{pmatrix}
\] (3)

These contact forces are subsequently translated into joint torques \( \mathbf{\tau} \) using Jacobian-transposed mapping with the relative Jacobians at contact points \( \mathbf{J}_i = \frac{\partial \mathbf{r}^c_i}{\partial \mathbf{q}} = \frac{\partial \mathbf{r}^{\text{foot}}_i - \mathbf{r}^{\text{base}}_i}{\partial \mathbf{q}} \) and center of gravity \( \mathbf{J}_j = \frac{\partial \mathbf{r}^g_j}{\partial \mathbf{q}} = \frac{\partial \mathbf{r}^{\text{CoG}}_j - \mathbf{r}^{\text{base}}_i}{\partial \mathbf{q}} \):

\[
\mathbf{\tau} = \sum_{i=1}^{N} \mathbf{J}^T_i \mathbf{F}^c_i + \sum_{j=1}^{N_b} \mathbf{J}^T_j \mathbf{F}^g_j
\] (4)

5. Conclusion

The paper introduced StarlETH, a compliant quadruped robot that was developed to study fast, efficient, and versatile locomotion. This lightweight system is driven by high compliant series elastic actuation that makes it fully torque controllable, robust against impacts, and hence perfectly suited
for sophisticated dynamic maneuvers. A framework based on SL [9] in combination with an analytical global kinematics and dynamics implementation serves as a powerful real-time simulation and control environment. It gives the control engineer a compact and user friendly tool to develop and test control algorithms. StarlETH was successfully tested in various experiments that demonstrated a high torque capability, its compliant protection against impact collisions, and full torque controllability. Hence, the presented platform in combination with the control and simulation environment is perfectly suited for dynamic maneuvers and sophisticated model based torque control strategies. As a first step, successful walking experiments were conducted using the presented virtual model controller (1)-(4) in combination with kinematic swing leg control [14]. This holds as a basis for future work towards more dynamic maneuvers.

References

5. R. Philippien, L. Sentis and O. Khatib, An open source extensible software package to create whole-body compliant skills in personal mobile manipulators, in *IROS*, 2011.