

References:

- [1] M. H. Raibert, *Legged Robots That Balance*. Cambridge, MA: MIT Press, 1986.
- [2] Miomir Vukobratovic and Branislav, "Zero-Moment Point-Thirty five years of its life." *International Journal of Humanoid Robotics*, vol.1, No. 1, pp.157-173, 2004.
- [3] J. Yamaguchi, Y. Takanishi and I. Kato, "Development of a biped walking robot compensating for three axis movement by trunk motion," *IEE/RSJ International workshop on intelligent robotics and systems*, vol. 2, pp. 561-566, 1999.
- [4] A. Agrawal and S.K. Agrawal, "An approach to identify joint motions for dynamically stable walking." *ASME Trans. Mechanical Design*, vol.128, pp.649-653.P, 2006.
- [5] Goswami, A., "Foot rotation indicator (FRI) point: A new gait planning tool to evaluate postural stability of biped robots", *Robotics and Automation, 1999.Proceedings, 1999 IEEE Int. Conference on*, Volume: 1, 1999, pp. 47-52 vol.1.
- [6] Honda Corporation. Say hello to asimo. <http://asimo.honda.com>, Accessed December 27, 2009.
- [7] L. Geppert. Qrio, the robot that could. *IEEE Spectrum*, 41(5):34-37, May 2004.
- [8] Massachusetts Institute of Technology (MIT) Leg laboratory ,<http://www.ai.mit.edu/projects/leglab/robots/robots>, Accessed September 21, 2009.
- [9] K. Kaneko, F. Kanehiro, S. Kajita, H. Hirukawa, T. Kawasaki, M. Hirata, K. Akachi, and T. Isozumi. Humanoid robot HRP-2. In *Proc IEEE Int Conf Robotics and Automation (ICRA'04)*, pages 1083-1090, April 2004.
- [10] K. Nishiwaki, T. Sugihara, S. Kagami, F. Kanehiro, M. Inaba, and H. Inoue. Design and development of research platform for perception-action integration in humanoid robot : H6. In *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS'00)*, volume 3, pages 1559-1564, 2000.
- [11] Fujitsu Automation. Humanoid robot.<http://www.techjapan.com/Article1037.html>, Accessed August 25, 2009.
- [12] M. Gienger K. Lffler and F. Pfeiffer. Sensors and control concept of walking "Johnnie". *Int J Robot Res*, 22(3):229-239, March 2003.
- [13] J.-H. Kim; J.-H. Oh. Realization of dynamic walking for the humanoid robot platform khr-1. *Adv Robotics*, 18(7):749-768, August 2004.

- [14] R.R. Murphy. Trial by fire [rescue robots]. IEEE Robotics and Automation Magazine, 11(3):50-61, 2004.
- [15] N. Robertson. Meet packbot: The newest recruit. <http://archives.cnn.com/2002/TECH/science/08/01/packbot/>. August 1, 2002. Accessed June 25, 2005.
- [16] J. Bares and D. Wettergreen. Dante II: Technical description, results and lessons learned. IntJ Robot Res, 18(7):621-649, 1999.
- [17] California Institute of Technology NASA Jet Propulsion Laboratory. Mars exploration rover mission. <http://marsrovers.jpl.nasa.gov/home/>, Accessed August 15, 2009.
- [18] R.K.Mittal, and I.J.Nagrath .Robotics and Control, Tata McGraw-Hill, 2003.
- [19] John J. Craig, Introduction to Robotics:Mechanics and Control, Prentice Hall, 2004.
- [20] RoboWorks –A tool for realtime interactive 3D modeling and animation with distributed simulation, <http://www.newtonium.com>, Accessed December 28, 2009.
- [21] F.Plestan, W.G.Jessy, R.Westervelt, A.Gabrial, "Stable walking of a 7-DoF biped robot." IEEE Trans.Robot.Autom.,vol.19, pp. 653-668 , 2003.
- [22] M.G.A.P Abeyratne, "Modelling of bipedal robot negotiating slopes" Master Thesis, University of Moratuwa, January 2010.

