(19) Europäisches Patentamt
European Patent Office
Office européen des brevets

(11) **EP 2 206 582 A8**

(12) **CORRECTED EUROPEAN PATENT APPLICATION**

(15) Correction information:
Corrected version no 1 (W1 A1)
Corrections, see
Bibliography INID code(s) 30

(48) Corrigendum issued on:
02.03.2011 Bulletin 2011/09

(43) Date of publication:
14.07.2010 Bulletin 2010/28

(21) Application number: **10003336.4**

(22) Date of filing: **28.06.2004**

(51) Int Cl.:
B25J 5/00 *(2006.01)* ***B25J 13/00*** *(2006.01)*
B62D 57/032 *(2006.01)*

(84) Designated Contracting States:
DE FR GB

(30) Priority: **27.06.2003 JP 2003185930**

(62) Document number(s) of the earlier application(s) in accordance with Art. 76 EPC:
04746941.6 / 1 642 687

(71) Applicant: **Honda Motor Co., Ltd.**
Minato-ku
Tokyo 107-8556 (JP)

(72) Inventors:
- **Takenaka, Toru**
  Wako-shi
  Saitama 351-0193 (JP)
- **Matsumoto, Takashi**
  Wako-shi
  Saitama 351-0193 (JP)
- **Yoshiike, Takahide**
  Wako-shi
  Saitama 351-0193 (JP)

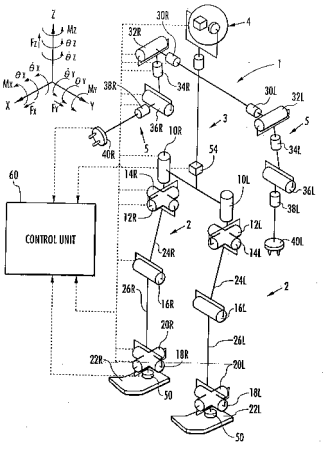
(74) Representative: **Hague, Alison Jane**
Dehns
St Bride's House
10 Salisbury Square
London
EC4Y 8JD (GB)

Remarks:
This application was filed on 29-03-2010 as a divisional application to the application mentioned under INID code 62.

(54) **Control device of legged mobile robot**

(57) On the basis of at least a difference between a desired state amount related to a posture of a robot (1) about a vertical axis or a floor surface normal line axis and an actual state amount of the robot (1) and a permissible range of a restriction object amount, namely, a vertical component of a floor reaction force moment or a component of the floor reaction force moment in a floor surface normal line direction to be applied to the robot (1), instantaneous values of a desired motion and a desired floor reaction force are determined such that a difference between a floor reaction force moment balancing with the desired motion on a dynamic model and a floor reaction force moment of the desired floor reaction force approximates the aforesaid difference to zero, while having the restriction object amount, which is associated with the desired floor reaction force, fall within the permissible range.

FIG.1



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