

## REFERENCES

- [1] A. Sprowitz, A. Tuleu, M. Vespignani, M. Ajallooeian, E. Badri, and A.J. Ijspeert, "Towards Dynamic Trot Gait Locomotion: Design, Control, and Experiments with Cheetah-cub, a Compliant Quadruped Robot," in *International Journal of Robotics Research*, vol. 32, no. 8, pp. 933-951, July 2013.
- [2] M. Buehler, R. Battaglia, A. Cocosco, G. Hawker, J. Sarkis, and K. Yamazaki, "Scout: A simple quadruped that walks, climbs and runs," IEEE Int. Conf. Robotics and Automation, p. 2348-2353, May 1999.
- [3] S. Talebi, I. Poulakakis, E. Papadopoulos, and M. Buehler, "Quadruped Robot Running With a Bounding Gait," in *Proc. 7<sup>th</sup> Int. Symp. Experimental Robotics, 2000*, [Online], Available: <http://citeseerx.ist.psu.edu/viewdoc/download?doi=10.1.1.7.2587&rep=rep1&type=pdf>
- [4] J. J. Collins and S. A. Richmond, "Hard-wired central pattern generators for quadrupedal locomotion," in *Biological Cybernetics*, vol. 71, pp. 375-385, 1994.
- [5] J. Halbertsma, "The stride cycle of the cat: the modeling of locomotion by computerized analysis of automatic recordings," in *Acta Physiologica Scandinavica, Supplement 521*, pp. 1-75, 1983.
- [6] M. H. Raibert, *Legged Robots That Balance*, MIT Press, 1986.
- [7] J.L. Meriam and L.G. Kraige, *Engineering Mechanics volume 2: Dynamics*, 6<sup>th</sup> ed., John Wiley & Sons, Inc., 2010.
- [8] W. Bolton, *Mechatronics: Electronic control systems in mechanical and electrical engineering*, 4<sup>th</sup> ed., Pearson Prentice Hall, 2008
- [9] P. E. Sandin, *Robot Mechanism and Mechanical Devices Illustrated*, McGraw-Hill, 2003.