For given unstable configuration $\mathbf{q}_{given}$ we can find the closest stable $\mathbf{q}$ using the following optimization problem.

$$\begin{aligned} \underset{\mathbf{q}}{\text{minimize}} \quad & ||\mathbf{q} - \mathbf{q}_{given}||^2 \\ \text{subject to} \quad & CoM_{xy}(\mathbf{q}) \in \Omega \;\; (\Omega \;\; is \;\; the \;\; Support \;\; Polygon) \\ & r(\mathbf{q}) = r_0 \\ & \mathbf{q}_{min} \leq \mathbf{q} \leq \mathbf{q}_{max} \end{aligned}$$

Where $CoM_{xy}(\mathbf{q})$ is the projection of center of mass for the robot into XY-plane, Ω is support polygon in world frame. $r(\mathbf{q})$ the position of the foot in contact with the ground that must be the same r_0 for the robot to maintains contact. $\mathbf{q}_{min}$ and $\mathbf{q}_{max}$ are the limit for the configuration $\mathbf{q}$.