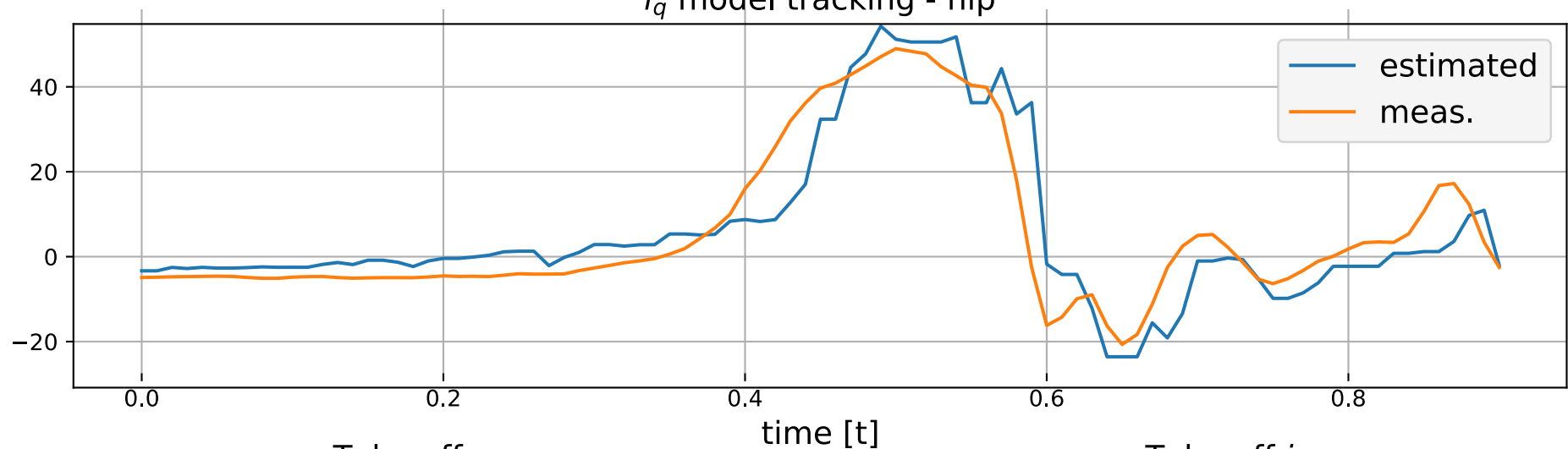
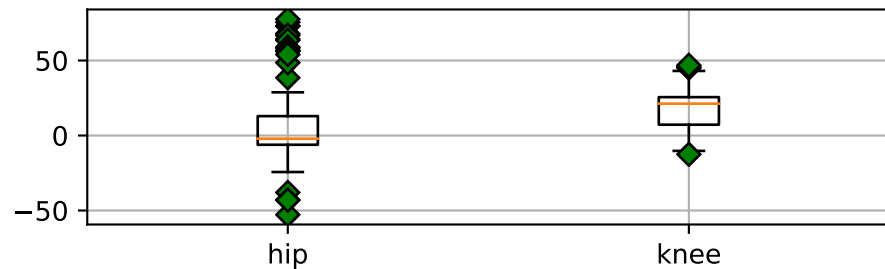


$i_q$  model tracking - hip $i_q$  [A]Take-off  $\tau$  $\tau$  [Nm]Take-off  $i_q$  $i_q$  [A]