Intro:

* Tell about LIP/ICP first

Background:

* Fuse flywheel model and pendulums? Change name ‘leg’ of pendulums
* Write related works

Theoretic Limits:

* Make unilateral and height constrained concise and write proof separate.
* Add force constrained limits
* Extend capturability comparison -> fix comparison plot

Polynomial:

* Rewrite a bit and write discussion why not.

Standing:

* Run 360 push
* Try some angular momentum tests.
* Hardware: pd gains foot angular
* **Ask feedback paper**
* **Atlas hardware / ball**
* Gray angular vs height plot

Walking:

* Make controller compact, neat and tested. Try fix prepare phase. Clean code+matlab
* Run 360 push incremental 0.0 0.1 … 0.7 swing phase
* Add test with longer step length.

Conclusion