**Thesis:**

Intro:

* First part

Background:

* Related works

Theoretic Limits:

* Discussion

Polynomial:

Standing:

* Discussion

Walking:

* *Add test with longer step length.*
* Discussion

Conclusion/Discussion

* Unmodelled dynamics, actuator limits, sensor errors, discrete time/numerical problems, actuator stiction/PD-controlled torque.
* ‘0-step’ focus
* Discuss numerical issues

Bibliography

* Entries + citing check
* Add more citations

**Presentation:**

* Edit presentation based on feedback
* make and answer possible questions – extra slides

**DATA:**

* IHMC repos: Make controller compact, neat and tested. Try fix prepare phase. Clean code+matlab
* Hfb repos
* Drive met atlas data

Questions:

* CoP in QP how computed?
* *Orbital energy in appendix?*