**Thesis:**

* **Make new version first**
* **Check all figures -> all on top?**
* **Check all units**
* **Check all calculations.**
* **Check citing style-> remove all names.**
* **Check bib on entries -> also order**
* **Check analytic/closed-form**
* **Check word writing consistent**
* **Check itemizing ; or .**
* **Discussion after chapters & recommendations vs conclusion**
* **Replace all \paragraph{} commands with subsubsections.**

Intro:

Background:

Theoretic Limits:

Polynomial:

Standing:

Walking:

* *Add test with longer step length.*

Conclusion/Discussion/Recommendations

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

Bibliography

* Entries
* Check manner of citing
* Add more citations

**Presentation:**

* Edit presentation based on feedback
* make and answer possible questions – extra slides
* Stand plots: phase + Video: ldotz, comz and ankle torque
* Walk plots: …
* All figures from thesis after last slide

**DATA:**

* Clean code+matlab
* Hfb repos
* Alle belangrijke niet-repos data in drive
  + Belangrijke resultaten val+atlas
  + Presenatie

Questions to answer:

* CoP plots for Valkyrie?
* Wat was the filtering used?
* Suspensory strategy?
* Increasing height decreases ankle control?

Final thesis delivery check:

* Cursive
* Citing
* Single or double “ ‘
* Real-time
* Closed-form
* Point-mass
* Time-response?
* Feedforward, feedback
* Whole-body
* Momentum-based, everything with –based
* Footstep, foot hold foothold
* Touchdown
* Mass-spring
* Work ipv works
* Boston dynamics’ or dynamics’s
* Knot-point
* End-effector
* Upper body upper-body
* Rough terrain rough-terrain
* Re-plan
* Multi-step
* Left-hand right-hand side
* High-level

Todo voor weggaan:

* Tas inpakken
* Borrel dingen rond: beamer en geluid
* Thesis compleet, code & data beschikbaar voor NL
* Maak 1 branche hfb1 + hfb2