**Thesis:**

Intro:

Background:

Theoretic Limits:

Polynomial:

Standing:

Walking:

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
* Add more citations

**Presentation:**

**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:

* Citing
* Single or double “ ‘
* durations
* Difference between
* Work vs plural?

Todo voor weggaan:

* Tas inpakken
* Thesis compleet, code & data beschikbaar voor NL
* Maak 1 branche hfb1 + hfb2