**Thesis:**

Intro:

Background:

* Incorporate that CMP is not restricted to lie inside the polygon

Theoretic Limits:

* Write about search + write about WHY solution is not closed-form possible: sergey

Polynomial:

Standing:

* Try some angular momentum tests 360 push
* Gray angular vs height plot
* Discuss without commanding height, doesn’t dot better

Walking:

* Make controller compact, neat and tested. Try fix prepare phase. Clean code+matlab
* Add delfta\_f in thesis
* Run 360 push incremental 0.0 0.1 … 0.7 swing phase -> fix after 0.5
* Add test with longer step length.

Conclusion/Discussion

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

Bibliography

* Entries?
* Citing and citing of names in thesis?

**Presentation:**

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

**DATA:**

* IHMC repos
* Hfb repos
* Drive met atlas data

Questions:

* Achieved wrench -> achieved angular momentum rate
* CoP in QP how computed?
* How is the binary search called?