# Practical 4 questions :

To control our leg we use joint space, task space and force profile. This enables us to have as much control over the different parameters.

When simply optimizing for height, we get (after 250 iterations) a huge, very unrealistic jump. That is caused by the optimizing not taking into account the torque limitations of the motors.

When optimizing for less steps (15-20) we get a much more realistic jumping motion. (see linked video).

In order to get a backwards motion, we can multiply the force on x by -1.

To get a static jumping motion, we use a x force that is slightly negative.

It is hard to get backward and static jumping using the optimization process, only takes one optimization function as input.