



Phase #0

Model: Humanoid6Dof.bioMod
Phase duration: 0.3 s
Shooting nodes: 20
Dynamics: TORQUE_DRIVEN
ODE: RK4
Control type: CONSTANT

Parameters
No parameter set

Lagrange
(MINIMIZE CONTROL)²
Weight: 1
key: tau
Index in list: 0

(MINIMIZE QDDOT)²
Weight: 0.01
Index in list: 1

(MINIMIZE QDDOT)²
Weight: 0.01
Index in list: 2

(MINIMIZE STATE)²
Weight: 0.01
key: qdot
Index in list: 3

(MINIMIZE COM VELOCITY)²
Weight: 0.1
Index in list: 6

Mayer
(MINIMIZE COM VELOCITY - 1.500)²
Weight: 1000
Index in list: 4
Shooting nodes index: Node.START

(MINIMIZE COM VELOCITY - 1.500)²
Weight: 1000
Index in list: 5
Shooting nodes index: Node.END

Constraints
TRACK CONTACT FORCES
Min bound: 0
Max bound: inf
contact_index: 1
Index in list: 0
Shooting nodes index: all

TRACK MARKERS
Min bound: 0
Max bound: 0
marker_index: RFoot
Index in list: 1
Shooting nodes index: 0

TRACK MARKERS VELOCITY
Min bound: 0
Max bound: 0
marker_index: RFoot
Index in list: 2
Shooting nodes index: 0

TRACK MARKERS
Min bound: 0
Max bound: 0
Target: [0.000 -0.400 0.000]
marker_index: LFoot
Index in list: 3
Shooting nodes index: 0

TRACK MARKERS
Min bound: 0
Max bound: 0
Target: [0.000 0.400 0.000]
marker_index: LFoot
Index in list: 4
Shooting nodes index: 20

TRACK MARKERS
Min bound: 0.05
Max bound: inf
marker_index: LFoot
Index in list: 5
Shooting nodes index: 0