



Phase #0

OCP

Model: Slider1Leg.bioMod **Phase duration**: 0.2 s **Shooting nodes**: 25 **Dynamics**: TÖRQUE DRIVEN **ODE**: COLLOCATION **Control type**: CONSTANT

> **Time Size**: 2

Scaling: [1.000 1.000] **Initial guess**: [0.200 0.400] **Min bound**: [0.100 0.300] **Max bound**: [0.100 0.300]

Lagrange

(MINIMIZE CONTROL)² Weight: 0.1**key**: tau Index in list: 0

(MINIMIZE CONTROL)² **Weight**: 0.1 **key**: tau **Index in list**: 2

<u>Mayer</u>

MINIMIZE TIME **Weight**: 0.01 **min bound**: 0.1 max bound: 0.2 Ind $\overline{\mathbf{e}}\mathbf{x}$ in list: 1

Shooting nodes index: Node.END

(MINIMIZE COM VELOCITY)² $\overline{\text{Weight}}$: -1 axes: 2

Index in list: 3 **Shooting nodes index**: Node.END

> **Constraints** TRACK CONTACT FORCES

Min bound: 0 Max bound: inf contact index: 0 **Index in list**: 0 **Shooting nodes index**: 0 Phase #1

Model: Slider1Leq.bioMod **Phase duration**: 0.4 s **Shooting nodes**: 25 **Dynamics**: TÖRQUE DRIVEN **ODE**: COLLOCATION **Control type**: CONSTANT

> Time Size: 2

Scaling: [1.000 1.000] **Initial guess**: [0.200 0.400] **Min bound**: [0.100 0.300] **Max bound**: [0.100 0.300]

<u>**Lagrange**</u> (MINIMIZE CONTROL)² Weight: 0.1**key**: tau Index in list: 0

(MINIMIZE CONTROL)² **Weight**: 0.1 **key**: tau **Index in list**: 2

Mayer

MINIMIZE TIME **Weight**: 0.01 **min bound**: 0.3 max bound: 0.5 Index in list: 1

Shooting nodes index: Node.END

(MINIMIZE COM POSITION)² $\overline{\text{Weight}}$: -1 axes: 2 **Index in list**: 3

Shooting nodes index: Node.END

Constraints

No constraint set