



Phase #0

Model: ConnectedArm.bioMod
Phase duration: 0.2 s
Shooting nodes: 100
Dynamics: TORQUE_DRIVEN_WITH_CONTACT
ODE: RK4

Parameters

No parameter set

Lagrange

(MINIMIZE TORQUE)²

Weight: 0.1

Index in list: 0

(SUPERIMPOSE_MARKERS)²

Weight: 10000

first_marker: mg3

second_marker: m0

Index in list: 1

Mayer

No Mayer set

Constraints

CONTACT_FORCE

Min bound: 0

Max bound: 0

contact_force_idx: [0, 1]

Index in list: 0

Shooting nodes index: all

SUPERIMPOSE_MARKERS

Min bound: 0

Max bound: 0

first_marker: md

second_marker: mg1

Index in list: 1

Shooting nodes index: 0

SUPERIMPOSE_MARKERS

Min bound: 0

Max bound: 0

first_marker: md

second_marker: mg2

Index in list: 2

Shooting nodes index: 100