



OCP

Phase #0

Model: Model JeCh 15DoFs.bioMod Phase duration: 1.35 s Shooting nodes: 125 Dynamics: CUSTOM

> **ODE**: RK4 **Control type**: CONSTANT

<u>Time</u> Size: 2

Scaling: [1.000 1.000] Initial guess: [1.352 0.193] Min bound: [1.202 0.043] Max bound: [1.202 0.043]

<u>Lagrange</u>

(MINIMIZE_STATE)²
Weight: 1
key: adot

key: qdot **Index in list**: 0

(MINIMIZE MARKERS)²

Weight: 10 reference_jcs: 1 marker_index: 6 Index in list: 1

(MINIMIZE_MARKERS)²

Weight: 10 reference_jcs: 1 marker_index: 11 Index in list: 2

(MINIMIZE_MARKERS)²
Weight: 100000

reference_jcs: 0 marker_index: 16 Index in list: 3

(MINIMIZE_STATE)²

Weight: 10 key: q Index in list: 4

Mayer

custom angular momentum **Weight**: 100000

Index in list: 5
Shooting nodes index: Node.START

MINIMIZE TIME

Weight: Te-06 min_bound: 1.201875 max bound: 1.501874999999998

Index in list: 6

Shooting nodes index: Node.END

<u>Constraints</u> No constraint set **Phase #1**

Model: Model JeCh 15DoFs.bioMod Phase duration: 0.19 s Shooting nodes: 25

Shooting nodes: 25 Dynamics: CUSTOM ODE: RK4

Control type: CONSTANT

<u>Time</u> Size: 2

Scaling: [1.000 1.000] Initial guess: [1.352 0.193] Min bound: [1.202 0.043] Max bound: [1.202 0.043]

Lagrange

(MINIMIZE STATE)²

Weight: 1 key: qdot Index in list: 0

(MINIMIZE MARKERS)²

Weight: 10 reference_jcs: 1 marker_index: 6 Index in list: 1

(MINIMIZE_MARKERS)²

Weight: 10 reference_jcs: 1 marker_index: 11 Index in list: 2

(MINIMIZE MARKERS)²

Weight: 100000 reference jcs: 0 marker_index: 16 Index in list: 3

(MINIMIZE_STATE)²

Weight: 10 key: q Index in list: 4

<u>Mayer</u>

MINIMIZE TIME

Weight: 1e-06 min_bound: 0.043125 max_bound: 0.343125 Index in list: 5

Shooting nodes index: Node.END

Constraints

No constraint set