

ZMP walking pipeline

via Hubo-Ach channel

Kinematic, model-based simulation

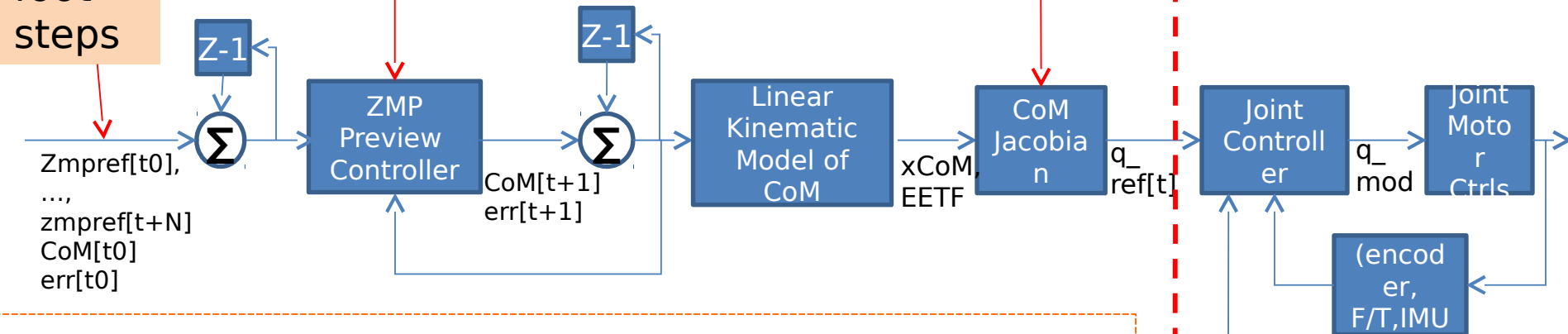
Real Hubo

Task #1:
foot steps

Task #2: ZMP
preview control

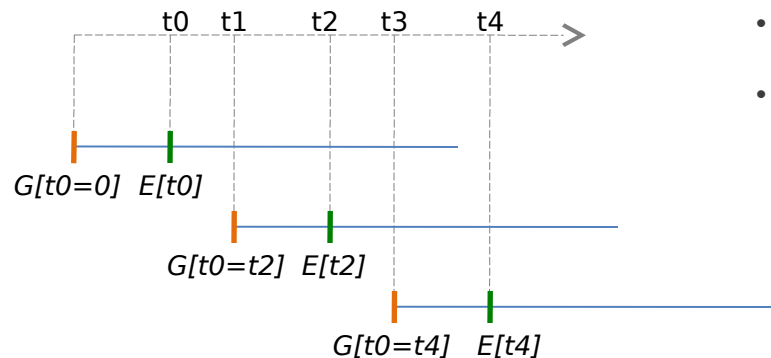
Task #3:
CoM IK

Task #4:
Run Hubo



G: Generate trajectory (Steps 1-3)

E: Execute trajectory (Step 4)



Parameters to Change

- Initial ZMPReferenceContext
 - Obtained from previous traj
- Starting foot
 - Left or right step first
- Startup time
 - Zero in middle of walking

Reference Values
(ex. Moment at ankle = 0)