|  |  |  |
| --- | --- | --- |
| **pdf** | **Página web** | **Apartado memoria** |
| Yarp 03 - CAPITULO 3 - LIBRERIAS SOFTWARE | http://bibing.us.es/proyectos/abreproy/12095/fichero/VOLUMEN+1%252F03+-+CAPITULO+3+-+LIBRERIAS+SOFTWARE.pdf | Programa de adquisición de datos |
| yarp | https://www.researchgate.net/publication/221709988\_YARP\_Yet\_another\_robot\_platform | Programa de adquisición de datos |
| 0referencia\_inercial\_mti\_ahrs(en carpeta apendices) | http://www.sensores-de-medida.es/uploads/0referencia\_inercial\_mti\_ahrs.pdf | Xsens |
| p50-metta | http://delivery.acm.org/10.1145/1780000/1774683/p50-metta.pdf?ip=163.117.82.138&id=1774683&acc=ACTIVE%20SERVICE&key=DD1EC5BCF38B3699%2EAFCE2F3122C4D47C%2E4D4702B0C3E38B35%2E4D4702B0C3E38B35&\_\_acm\_\_=1532028775\_c3d27af62ce735cd28b4858d6077ef1a | Xsens icub |
| 3d linear pendulum(descripción resumida) | https://pdfs.semanticscholar.org/6a31/6e0d44e35a55c41a442b3f0d0eb1f9d4d0ca.pdf | Modelo Péndulo invertido |
| A Linear Inverted Pendulum Walk Implemented on TUlip | https://www.techunited.nl/media/files/humanoid/SwanVanDalen\_GRAD2012\_A\_Linear\_Inverted\_Pendulum\_Walk\_Implemented\_on\_TUlip.pdf | Modelo péndulo invertido |
| Humanoid walking robot: modeling, inverse dynamics, and gain scheduling control | https://www.hindawi.com/journals/jr/2010/278597/ | Apartado 4 |
| Biped Walking Pattern Generation by using Preview Control of Zero-Moment Point | https://www.swarthmore.edu/NatSci/mzucker1/e91/readings/kajita2003preview.pdf | Apartado 4 |
| BIPED LOCOMOTION: STABILITY, ANALYSIS AND CONTROL | https://www.researchgate.net/publication/229004559\_BIPED\_LOCOMOTION\_STABILITY\_ANALYSIS\_AND\_CONTROL | Apartado 4 |
| ankle\_and\_hip\_strategies\_for\_balance\_recovery\_of\_a\_biped\_subjected\_to\_an\_impact | https://www.cambridge.org/core/journals/robotica/article/ankle-and-hip-strategies-for-balance-recovery-of-a-biped-subjected-to-an-impact/2CBD26EE1DE85176D81F49BD40E3DB29 | Apartado 4 |
| Experimental validation of ankle and hip strategies for balance recovery with a biped subjected to an impact | https://www.researchgate.net/publication/4296918\_Experimental\_validation\_of\_ankle\_and\_hip\_strategies\_for\_balance\_recovery\_with\_a\_biped\_subjected\_to\_an\_impact | Apartado 4.4 |
| Strategies for Recovery and Maintain of A Biped Walking Robot Balance | https://www.sciencepubco.com/index.php/ijet/article/view/12893 | Apartado 4.4 |
| Push Recovery of a Position-Controlled Humanoid Robot Based on Capture Point Feedback Control | https://arxiv.org/pdf/1710.10598.pdf | Apartado 4.4 |
| Experimental Robot Model Adjustments Based on Force–Torque Sensor Information | http://www.mdpi.com/1424-8220/18/3/836 | Apartado 5 |
| control\_ZMP₁ | http://revistas.elpoli.edu.co/index.php/pol/article/viewFile/138/114 | Apartado 5.1.4 |
| Ground Reference Points in Legged Locomotion: Definitions, Biological Trajectories and Control Implications | https://www.researchgate.net/publication/221710011/download | Apartado 3 definición CMP |
| Ingenieria de control moderna ogata 5ed | https://hellsingge.files.wordpress.com/2014/10/ingenieria-de-control-moderna-ogata-5ed.pdf | Apartado 5.1.3 error transitorio |