

matlab → .../coddyco-superbuild/main/WBIToolboxControllers/controllers/BalancingTorque

- TorqueBalancingR2015b86.mdl ← Simulation
- README ← documentation - outdated
- initTorqueBalancing.m ← contains a few more lines of doc.
 - check robot name
 - option to turn on/off scopes
- app/robots/iCubNanogy01/gains.m ← controller gains, torque saturation value...
- " /initStateMachine.m ← gains for yogo state machine
→ overwrites some variables from gains.m +
- /initRefGen.m ← more parameters

+ changed hardware joint limits in PID file.

changes in robot configurations motor control (PID gains from yarpmdtorgui)

	Kp	Kbemf	ktau	
torso →	yaw : 450	0.0008	200	
	roll : 400	0.0015	200	
	pitch : 400	0.0015	200	
l_arm →	shoulder + elbow joints			Kbemf = 0
r_arm →	"			"
l_leg →	knee : switch sign	Kp, K _z	and K _z = -100	
r_leg →	r ankle pitch : Kp = -300	(was -200)		
	r ankle roll : Kp = 0	(was -200) ⇒ PUT BACK TO -200*		

↓
new change

BUG sm.com.threshold TWICE in initStateMachine.m