First, define $q = [q_p^T, q_a^T]^T$, where q_p are the passive (floating base) joints, and q_a are the actuated joints. If I assume that the ground contacts on the feet will stay stationary, then I have

$$\begin{aligned} \dot{x}_{gc} = [J^p_{gc}, J^a_{gc}] \begin{bmatrix} \dot{q}_p \\ \dot{q}_a \end{bmatrix} = 0, \\ \Rightarrow \quad J^p_{gc}\dot{q}_p = -J^a_{gc}\dot{q}_a, \\ \Rightarrow \quad \dot{q}_p = -J^{p+}_{gc} J^a_{gc}\dot{q}_a, \\ \Rightarrow \quad \dot{q} = \begin{bmatrix} -J^{p+}_{gc} J^a_{gc}, \\ I \end{bmatrix} \dot{q}_a = A\dot{q}_a, \end{aligned}$$

where J_{gc} is the kinematic Jacobian of the ground contacts, the superscripts a and p denote the subsets of this matrix related to q_a and q_p, and the superscript $+$ indicates a pseudo-inverse. In the planar case, J^p_{gc} will likely have full column rank if there are two contact points (even on a single foot); in the 3D case you'd like to have three contact points (presumably on at least two different bodies).

For control, I want to regulate the x and y positions of the center of mass (first priority), then regulate hand position (second priority), then stay near a comfortable posture (last priority). For a good summary of kinematic Jacobian control, see [1]. We will use

$$\begin{gathered} \dot{x}_{com,xy} = \begin{bmatrix} I & 0 \end{bmatrix} J_{com} A\dot{q}_a = J_1\dot{q}_a, \quad x^d_{com,xy} = x_{csp}, \text{ and} \\ \dot{x}_{rhand} = J_{rhand} A\dot{q}_a = J_2\dot{q}_a, \end{gathered}$$

where COM stands for "center of mass" and CSP stands for "center of support polygon". Set

$$\begin{aligned} \dot{x}_1 &= \eta_1(x^d_{com,xy} - x_{com,xy}) \\ \dot{x}_2 &= \eta_2(x^d_{rhand} - x_{hand}) \\ \dot{q}_0 &= \eta_3(q^d_0 - q_0) \end{aligned}$$

Finally, the control law is given by ([1] eq 15):

$$q_d = q + J_1^+\dot{x}_1 + (I - J_1^+ J_1)J_2^+(\dot{x}_2 - J_2 J^1 + \dot{x}) + (I - J_1^+ J_1)(I - J_2^+ J_2)\dot{q}_0.$$

References

[1] Bruno Siciliano. Kinematic control of redundant robot manipulators: A tutorial. *Journal of Intelligent and Robotic Systems*, 3:201–212, 1990.