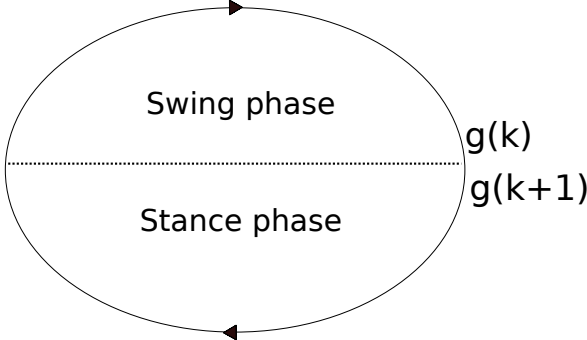


$l(k)$



Swing phase

$g(k)$

$g(k+1)$

Stance phase