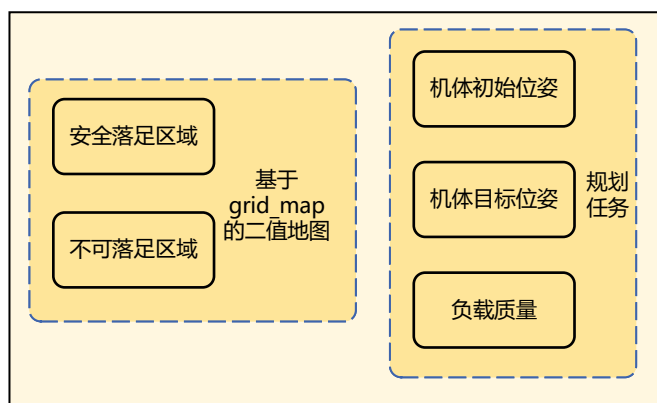
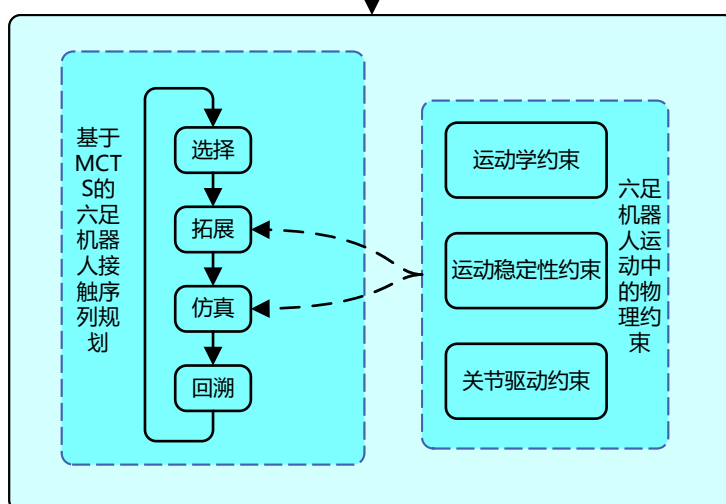


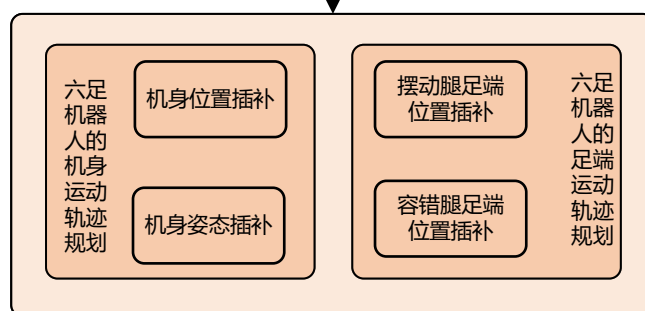
数据输入层



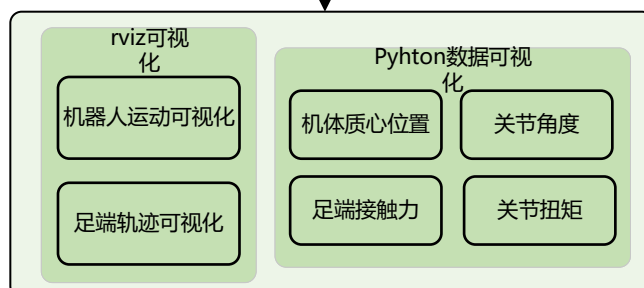
六足机器人接触序列规划层



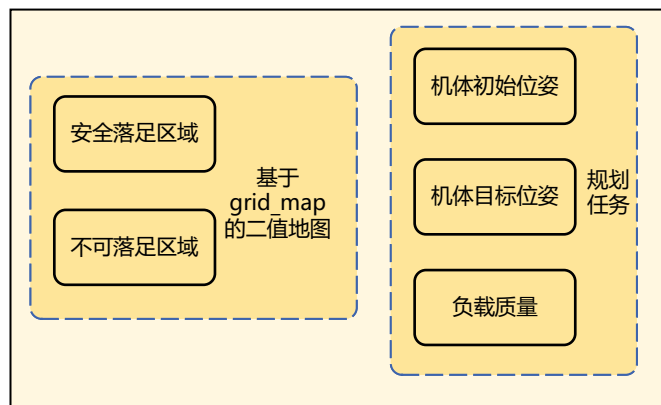
六足机器人轨迹规划层



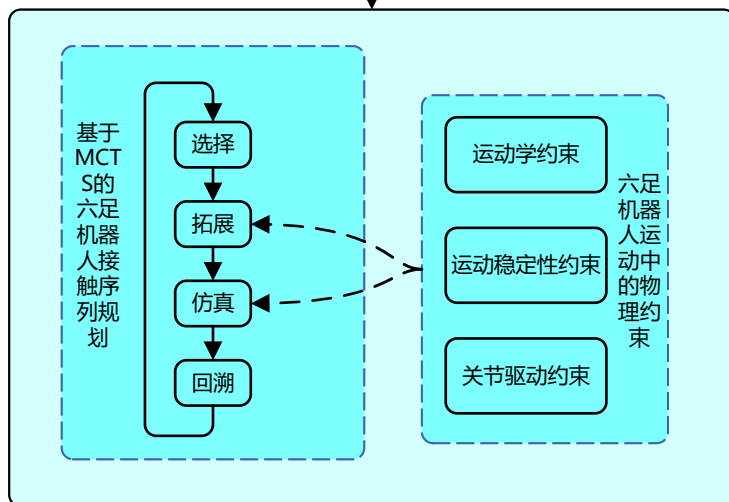
可视化层



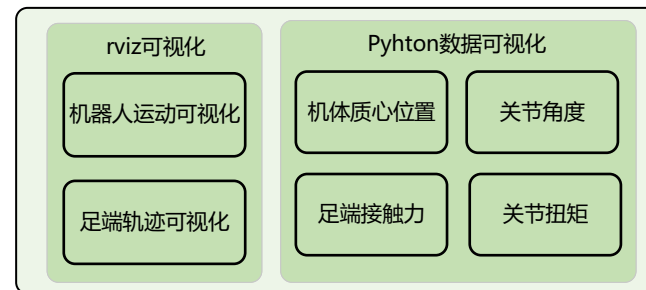
数据输入层



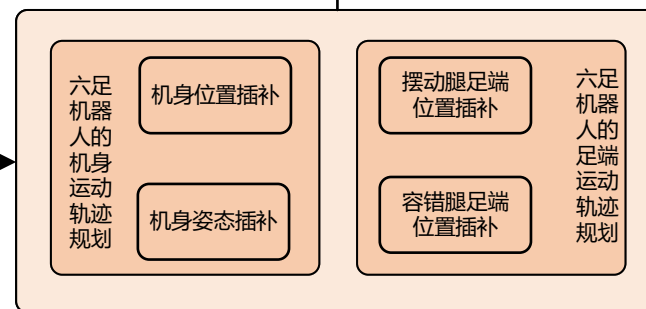
六足机器人的接触序列规划层



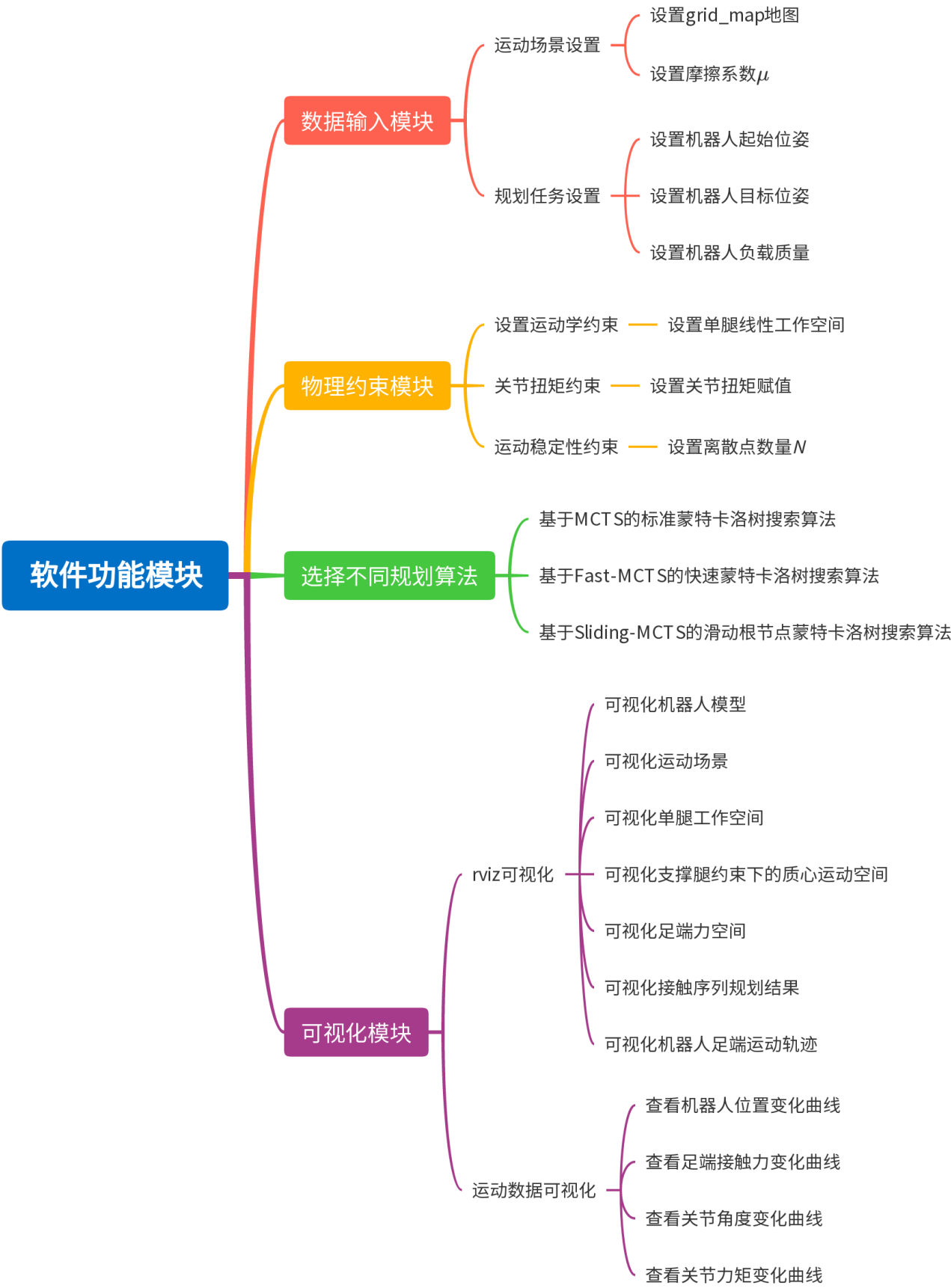
可视化层



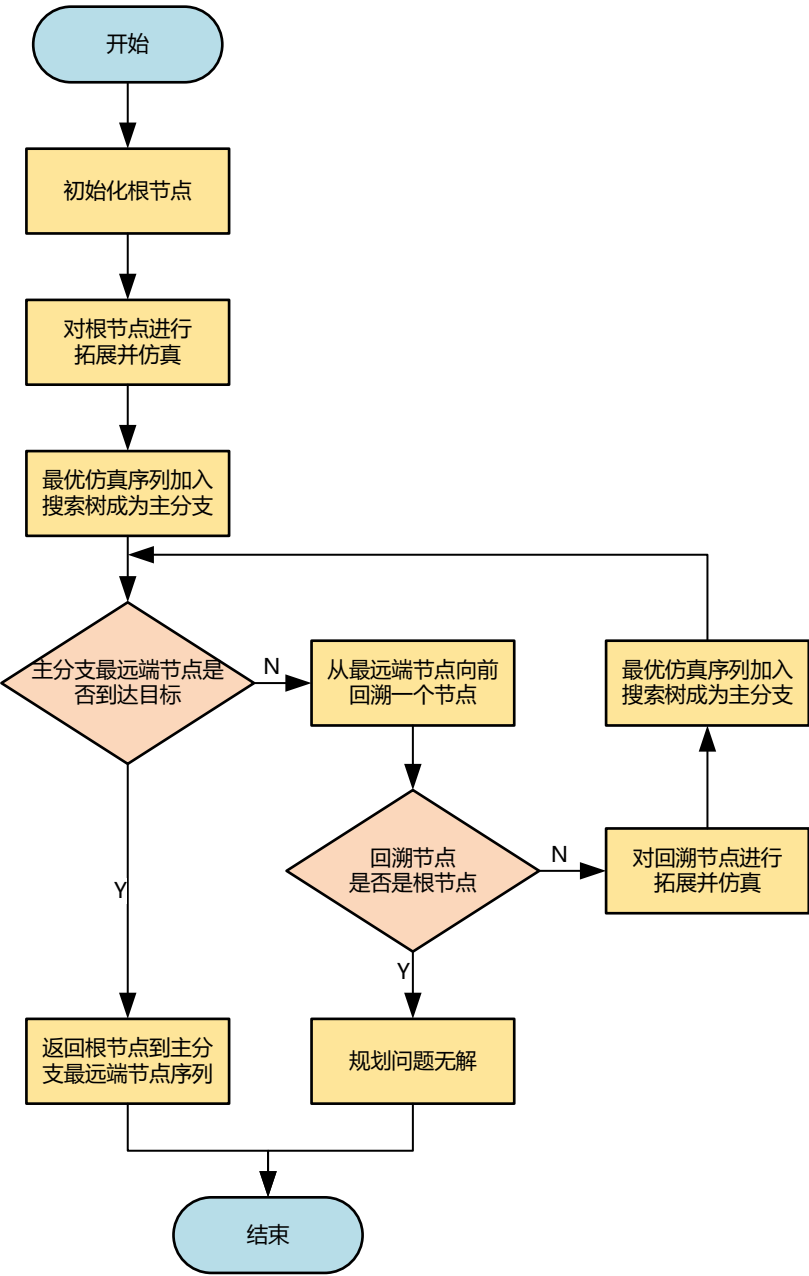
六足机器人的轨迹规划层



软件功能模块图



快速蒙特卡洛树搜索算法



Bretl的迭代投影算法

