

# Robot\_spawn. launch

Model.world

hyq.tort.xml

robot.xacro

hyq.yaml

DDPG\_tort.yaml

training\_trot.py

hyq.xacro

materials.xacro

hyq.gazebo

DDPG.py

hyq\_env.py

trunk.xacro

leg.xacro

gazebo\_connection.py

controllers\_connection.py

hyq\_state.py

joint\_publisher.py

trunk.dae

hipassembly.dae

lowerleg.dae

upperleg.dae