

# Capturability controller for NAO robot

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## 1 制御系

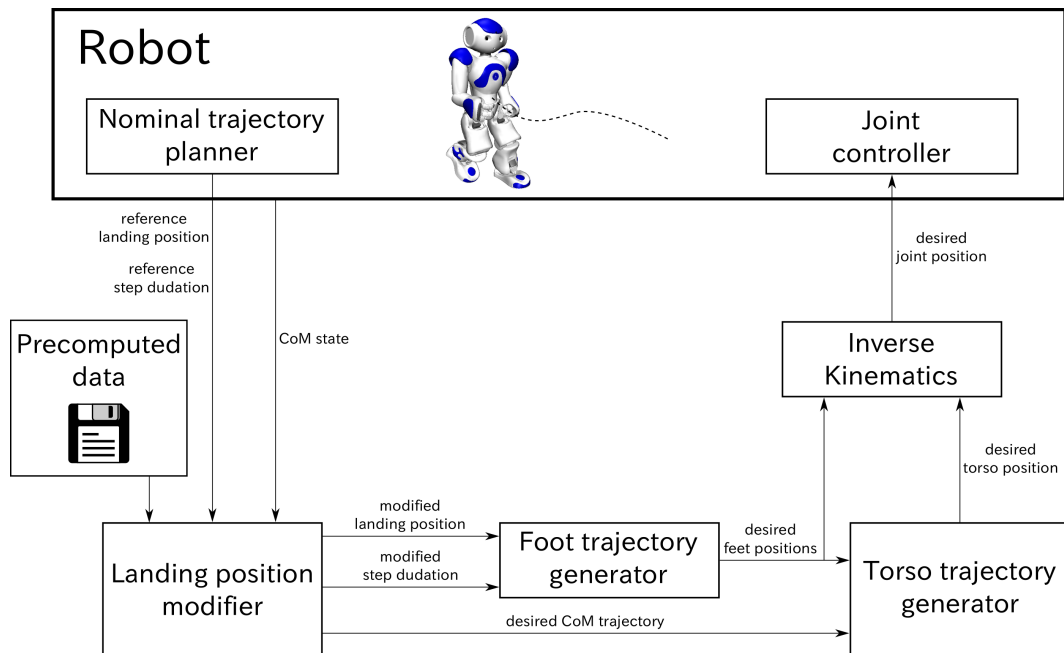


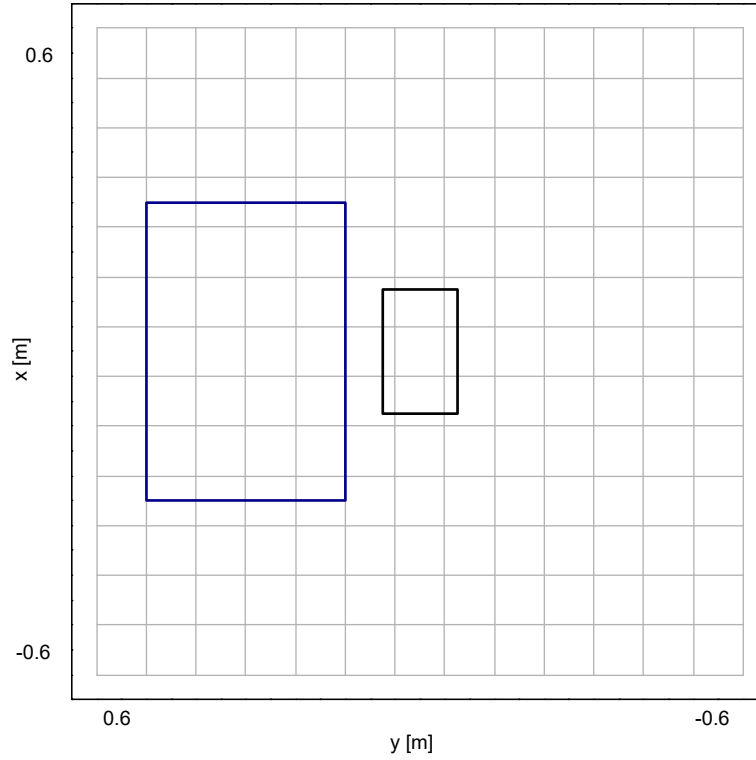
Fig. 1: 制御系

## 2 グリッド

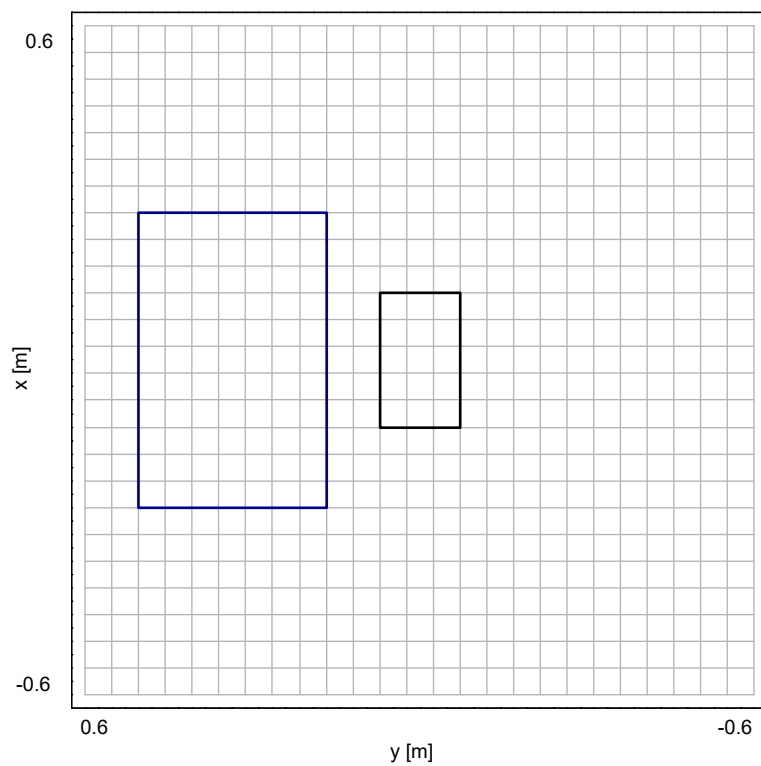
**Table 1:** Parameters

Symbol	Min	Max	Resolution	Unit
$x_{\text{icp}}$	-0.60	0.60	*	[m]
$y_{\text{icp}}$	-0.60	0.60	*	[m]
$x_{\text{swf}}$	-0.25	0.25	*	[m]
$y_{\text{swf}}$	0.20	0.50	*	[m]
$x_{\text{cop}}$	-0.125	0.125	*	[m]
$y_{\text{cop}}$	-0.075	0.075	*	[m]

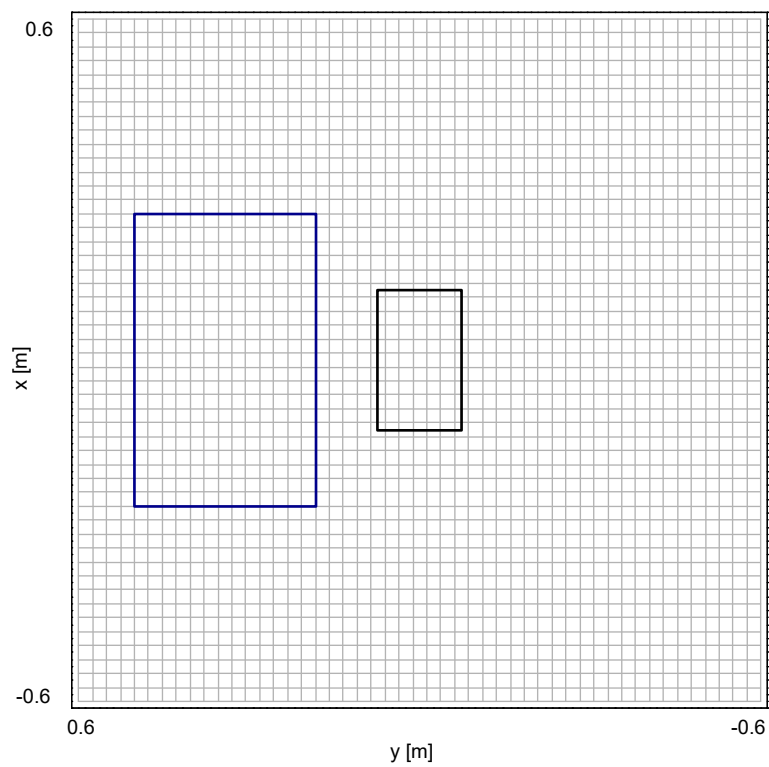
足の頂点  
+0.125, +0.075  
+0.125, -0.075  
-0.125, -0.075  
-0.125, +0.075



**Fig. 2:** Resolution: 0.1 m



**Fig. 3:** Resolution: 0.05 m



**Fig. 4:** Resolution: 0.025 m