# Errata: Robust Physics-Based Locomotion Using Low-Dimensional Planning 

Martin de Lasa

February 12, 2011

### 4.2 Stance Dynamics and Simulation

The last sentence of the Vertical Motion paragraph should read:
In all our examples we use $g=9.81 \mathrm{~m} / \mathrm{s}^{2}$ and $k=1000 \mathrm{~N} / \mathrm{m}$.

### 5.2 Modeling Objections

Equations 24 should read:

$$
\begin{equation*}
g_{\text {accel }}=\int\|\ddot{\mathbf{c}}(t)\|^{2} d t \tag{24}
\end{equation*}
$$

### 5.3 Constraints

Last paragraph should read:
Each component of the footstep location is constrained to lie near the COM:

$$
\begin{equation*}
\left\|\mathbf{c}_{\|}-\mathbf{y}_{\text {swing }}\right\|_{\infty}<\frac{1}{2} L_{r} \tag{28}
\end{equation*}
$$

where $\mathbf{c}_{\|}$are the COM coordinates projected on the ground plane and $L_{r}$ is the character's leg length when standing. The $L_{\infty}$ norm is used to enable this to be expressed as bounds constraints.

We thank Mazen Al-Borno for bringing this error to our attention.

