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

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4.2 Stance Dynamics and Simulation

The last sentence of the **Vertical Motion** paragraph should read:

In all our examples we use $g = 9.81 \ m/s^2$ and $k = 1000 \ N/m$.

5.2 Modeling Objections

Equations 24 should read:

$$g_{accel} = \int ||\ddot{\mathbf{c}}(t)||^2 dt. \tag{24}$$

5.3 Constraints

Last paragraph should read:

Each component of the footstep location is constrained to lie near the COM:

$$||\mathbf{c}_{\parallel} - \mathbf{y}_{swing}||_{\infty} < \frac{1}{2}L_r \tag{28}$$

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

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