

# 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  $g = 9.81 \text{ m/s}^2$  and  $k = 1000 \text{ N/m}$ .

## 5.2 Modeling Objections

Equations 24 should read:

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

## 5.3 Constraints

Last paragraph should read:

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

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

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  $L_{\infty}$  norm is used to enable this to be expressed as bounds constraints.

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