

HOW TO

- 1 check-out offsets of each qbmmove and set it up in the simulink models (remove offset block);
- 2 build the limit-switches on the qbmmove ankle flanges;
- 3 build the robot with the z-axis of the qbmmove legs actuators pointing on the right (figure 1);
- 4 set filter gains for smoothing reference input command (in main.m).

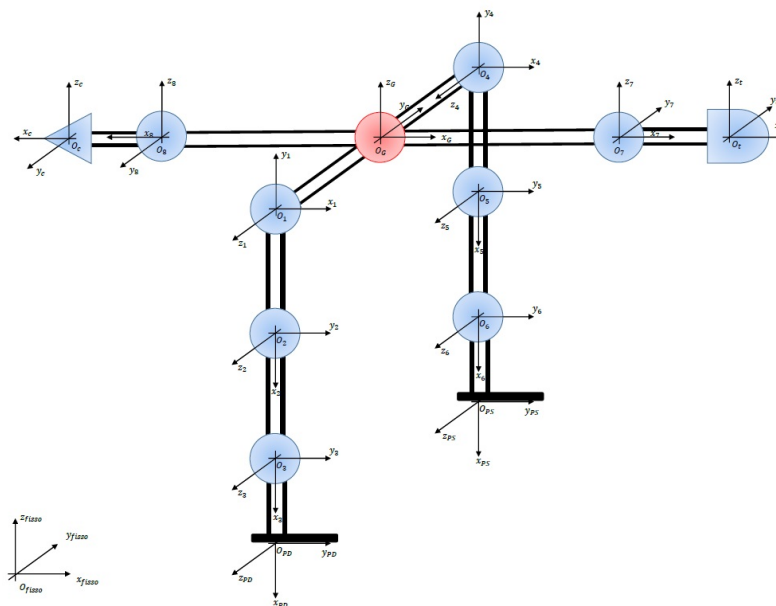


Figure 1: Reference frame