Participants: Francesco Nori, Alessio Rocchi, Alessandro Altobelli

Details:

• Convert the output of the CoM planner group into an iCub controller (either torques or joint velocities).
• Trying to use available packages (e.g. SOT and QP by Nicholas Mansard or Sentis whole-body-control-framework).
• Handle additional constraints such as relative foot positions and limits at the joints.