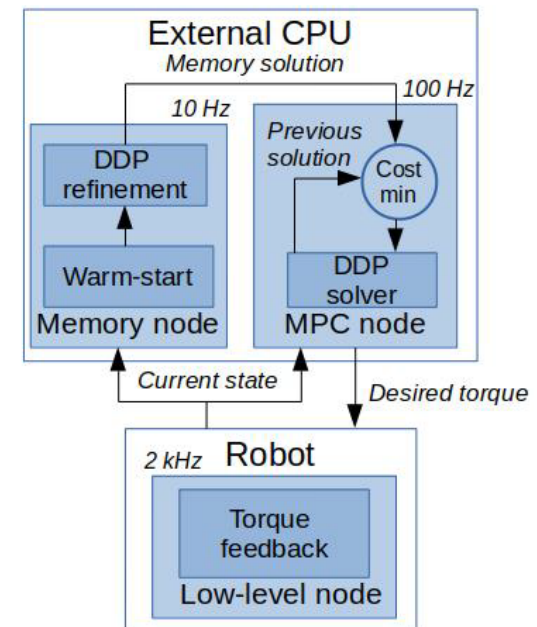


Whole Body Model Predictive Control with a Memory of Motion: Experiments on a Torque-Controlled Talos

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- Successful implementation of a MPC with state-feedback on a torque-controlled humanoid
- Solver is based on a DDP scheme running at 100 Hz, with low-level control at 2 kHz
- Experiments involve end-effector and CoM tracking tasks, as well as obstacle avoidance
- Offline-built memory used to warm-start the OCP



Memory MPC architecture