

MuJoCo: 2D Biped (I)

Using [template_pendulum2.zip](#) to get started

1. From tiny.cc/mujoco download [template_pendulum2.zip](#) and unzip in myproject
2. Rename folder [template_pendulum2](#) to [biped](#)
3. Make these three changes
 1. main.c — line 28, change [template_pendulum2/](#) to [biped/](#)
 2. makefile — change `ROOT = template_writeData` to `ROOT = biped` also UNCOMMENT (del #) appropriate to your OS
 3. run_unix / run_win.bat change `<template_pendulum2>` to `<biped>`
4. In the shell, navigate to [biped](#) and type `./run_unix` (unix)

MuJoCo: 2D Biped (2)

Model (xml)

World

Un-actuated: x, z, q_1

Leg 1

Knee Joint: l_1

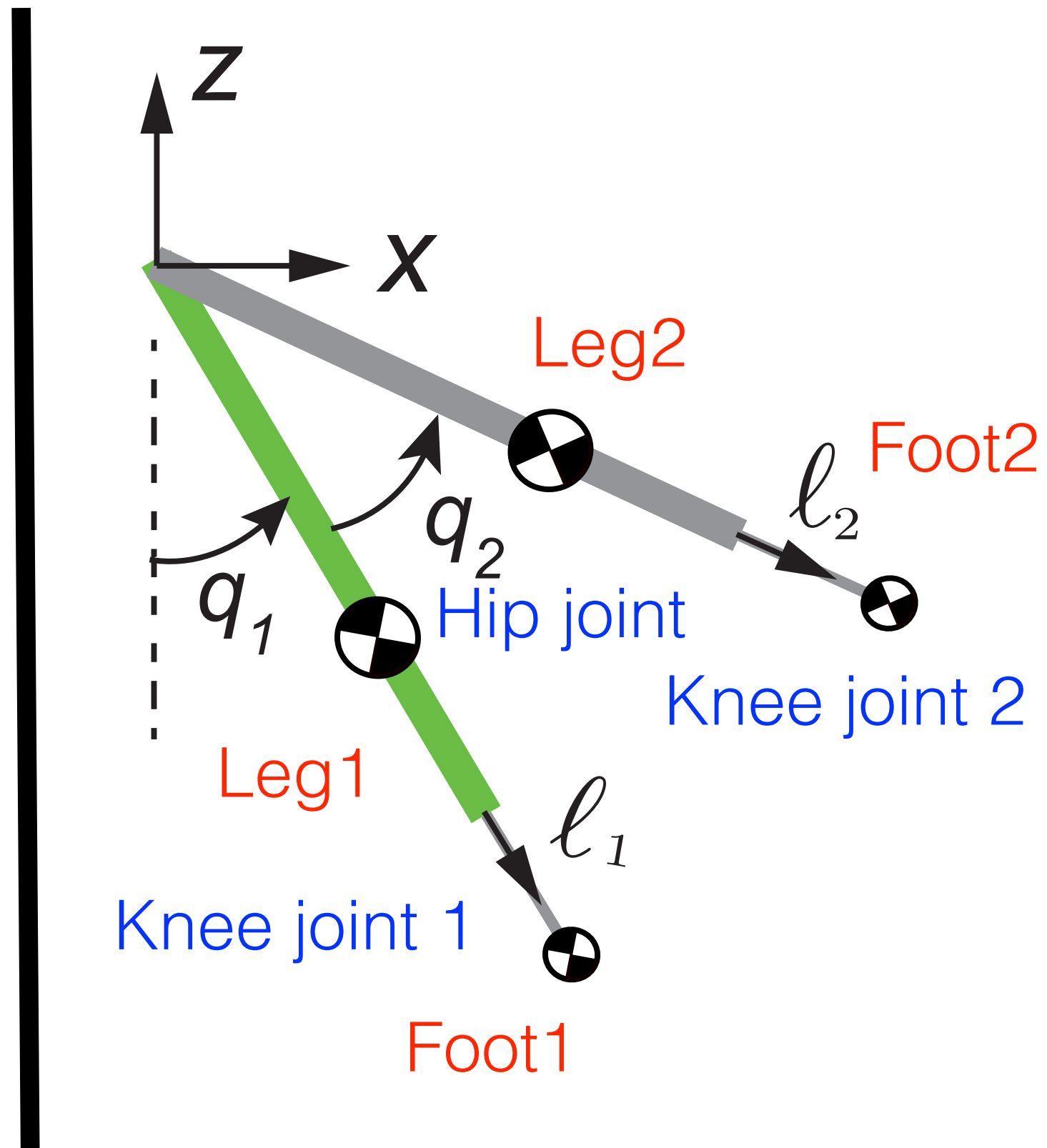
Hip Joint: q_1

Foot 1

Leg 2

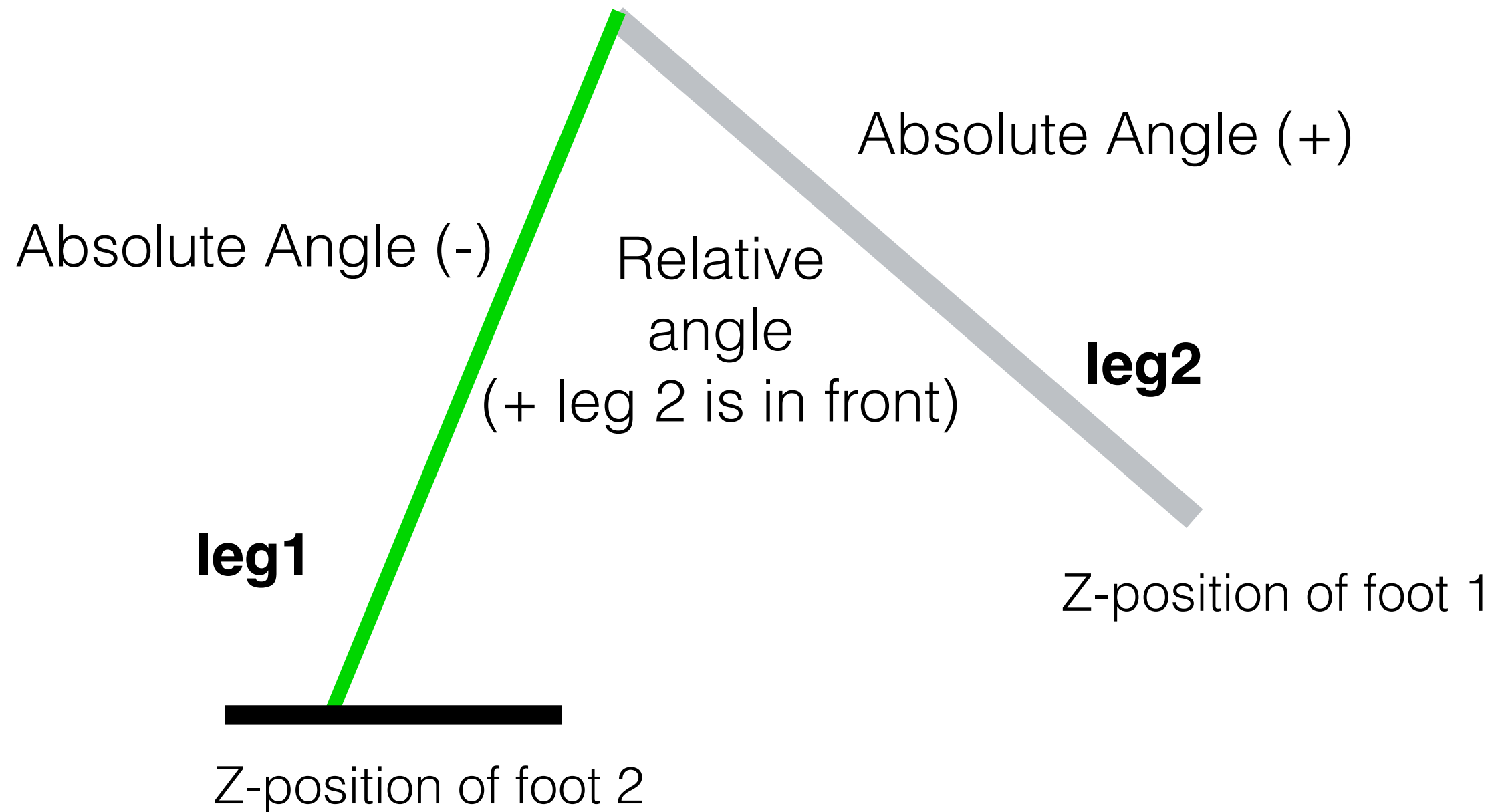
Knee Joint: l_2

Foot 2

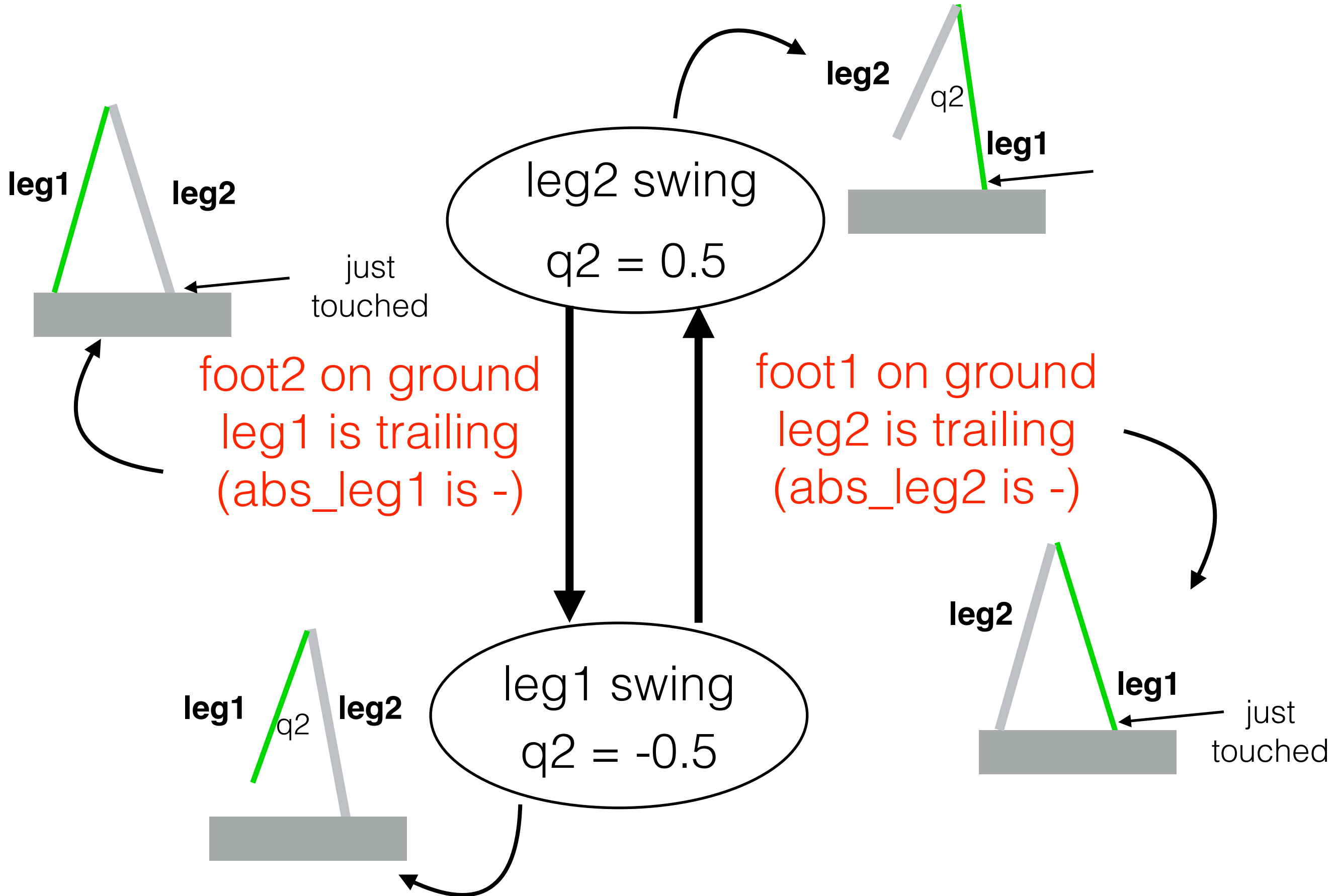


MuJoCo: 2D Biped (3)

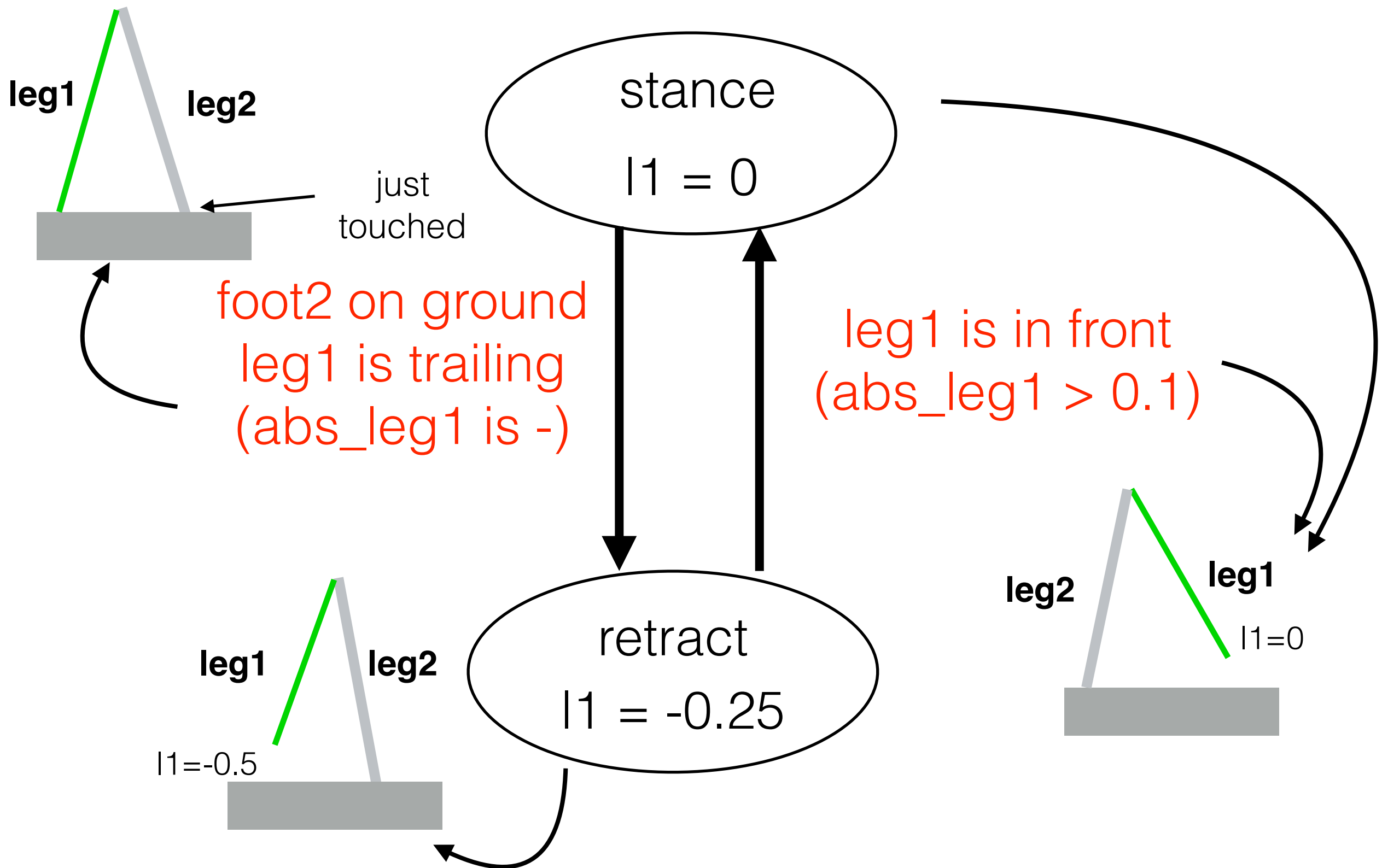
State Estimation



MuJoCo: Finite State Machine, Hip (4)



MuJoCo: Finite State Machine, Knee I (5)



MuJoCo: Finite State Machine, Knee 2 (6)

