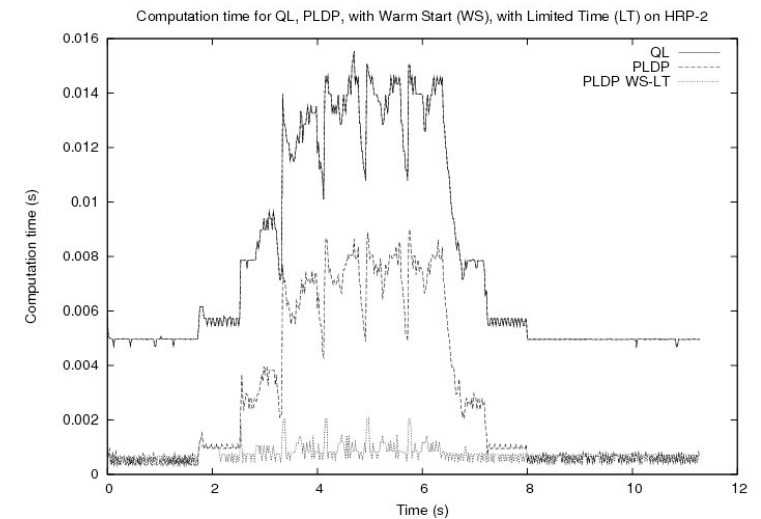


An Optimized Linear Model Predictive Control Solver for Online Walking Motion Generation

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- The article addresses the fast solution of a quadratic program underlying a LMPC scheme that generates walking motions
- A new optimized algorithm is introduced
- Computational complexity is presented and numerical comparison with existing state of the art solver is made
- Quantifiable numerical results of “warm-starting” in the presence of real-time bound is presented



Run-time comparison with
a state of the art solver