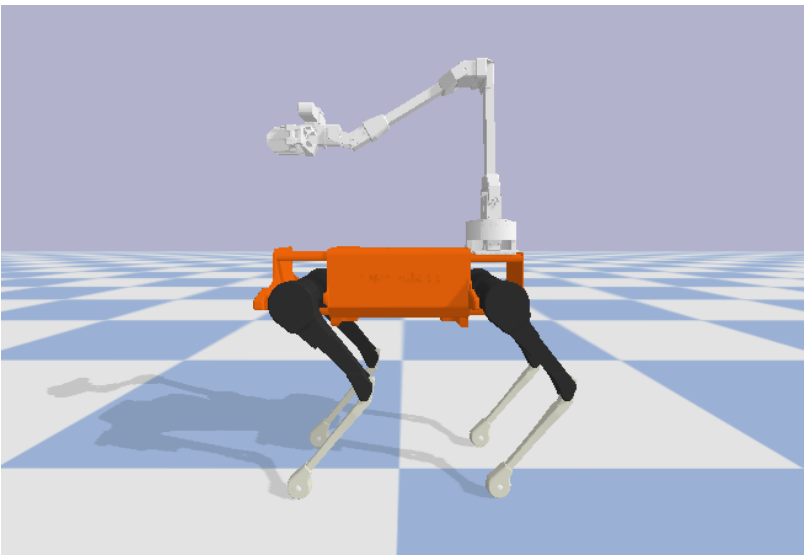


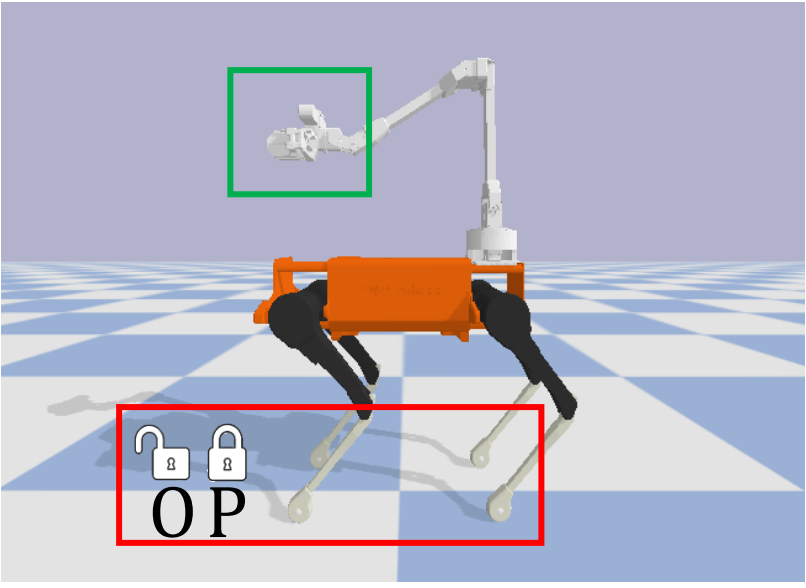


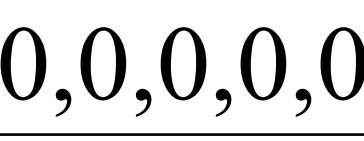
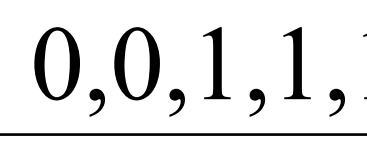
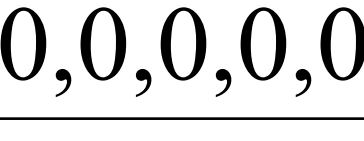
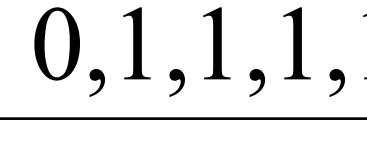
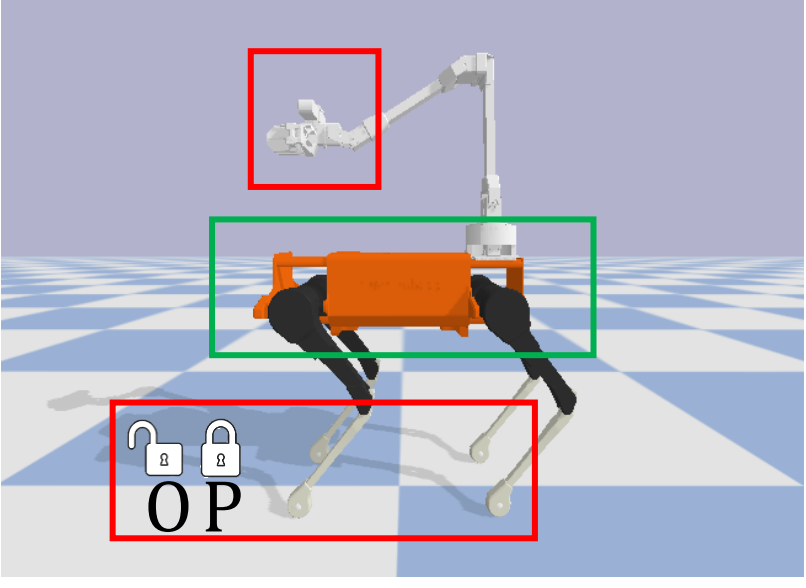
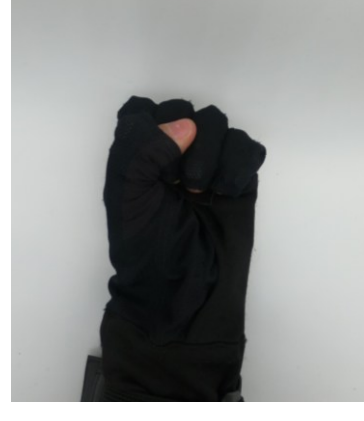
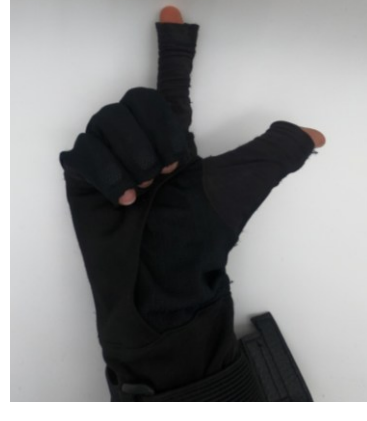
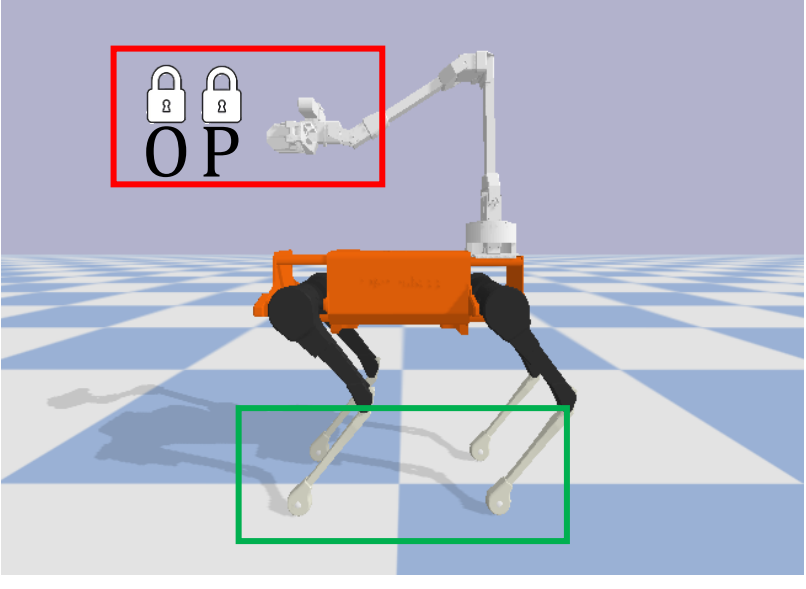


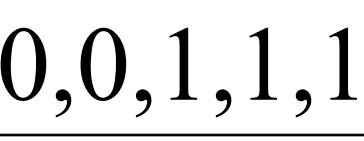
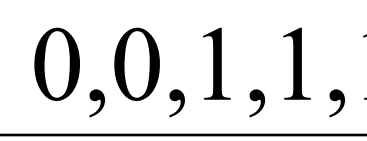
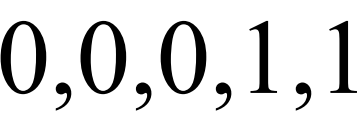
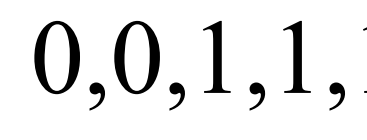
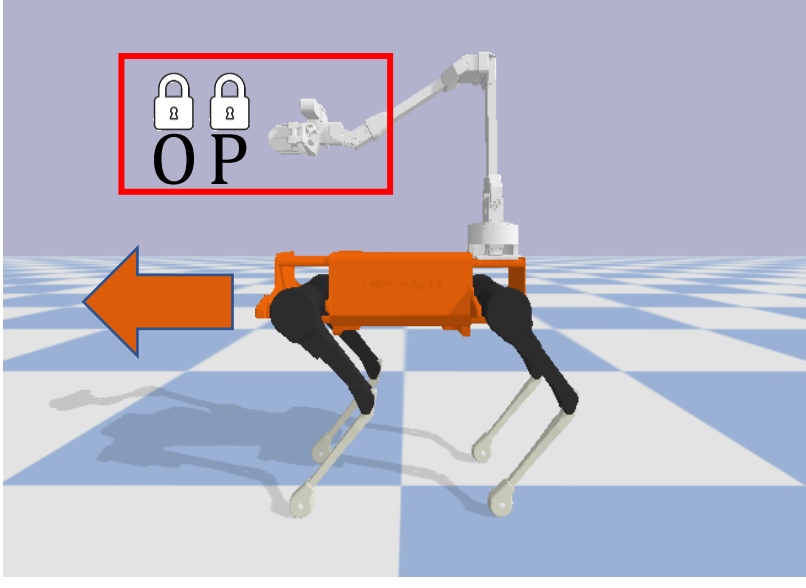


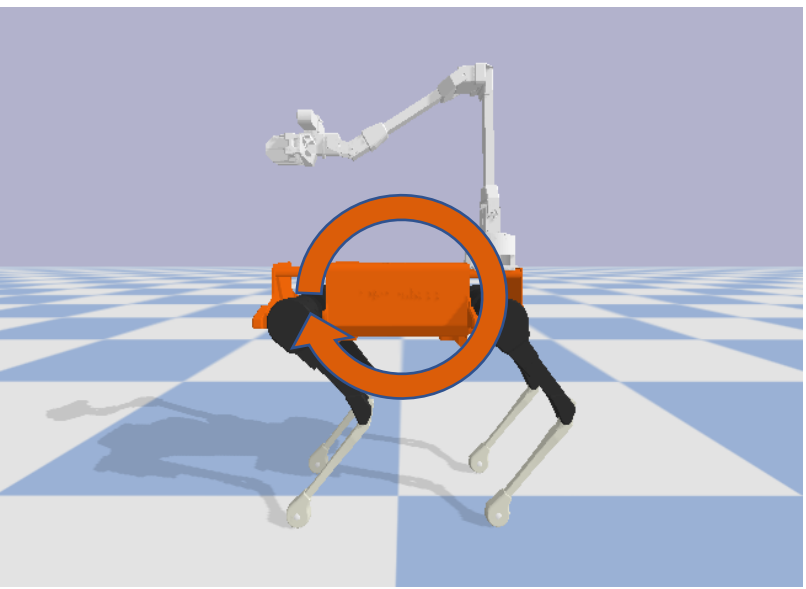
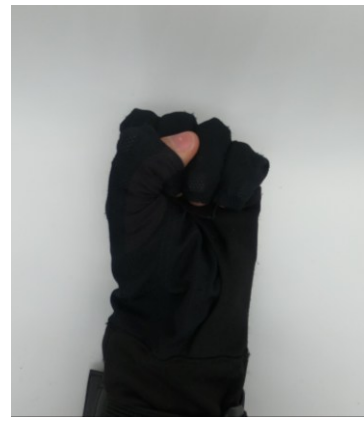


Name	Reference Diagram	Frame Controlled		Features	Left Hand	Right Hand
TS0		n/a		No reference sent to the robot.	0,0,0,0,0 	0,0,0,0,0 
TS1		TS1a	End-effector control	<ul style="list-style-type: none"><li>Feet locked in position and orientation.</li><li>End-effector can be opened and closed.</li></ul>	0,0,0,0,0 	1,1,1,1,1 
		TS1b	End-effector orientation		0,0,0,0,0 	0,0,1,1,1 
		TS1c	End-effector position			
			0,0,0,0,0 		0,1,1,1,1 	
TS2		TS2a	Base	<ul style="list-style-type: none"><li>End-effector locked in position.</li></ul>	1,1,1,1,1	0,1,1,1,1
		TS2b		<ul style="list-style-type: none"><li>End-effector locked in position and orientation.</li><li>Automatic stepping.</li></ul>		
TS3		TS3a	FR foot	<ul style="list-style-type: none"><li>End-effector is locked in position and orientation.</li><li>Automatic CoM adjustments and foot lifting.</li></ul>	0,1,1,1,1 	0,0,1,1,1 
		TS3b	FL foot		0,0,1,1,1 	0,0,1,1,1 
		TS3c	RR foot			
		TS3d	RL foot		0,0,0,1,1 	0,0,1,1,1 
TS4		n/a		<ul style="list-style-type: none"><li>Robot completes static gait.</li><li>End-effector is locked locally in position.</li></ul>	1,1,1,1,1 	1,0,1,1,0 
TS5		n/a		<ul style="list-style-type: none"><li>Resets all frames to a home position.</li></ul>	1,1,1,1,1 	1,1,1,1,1 