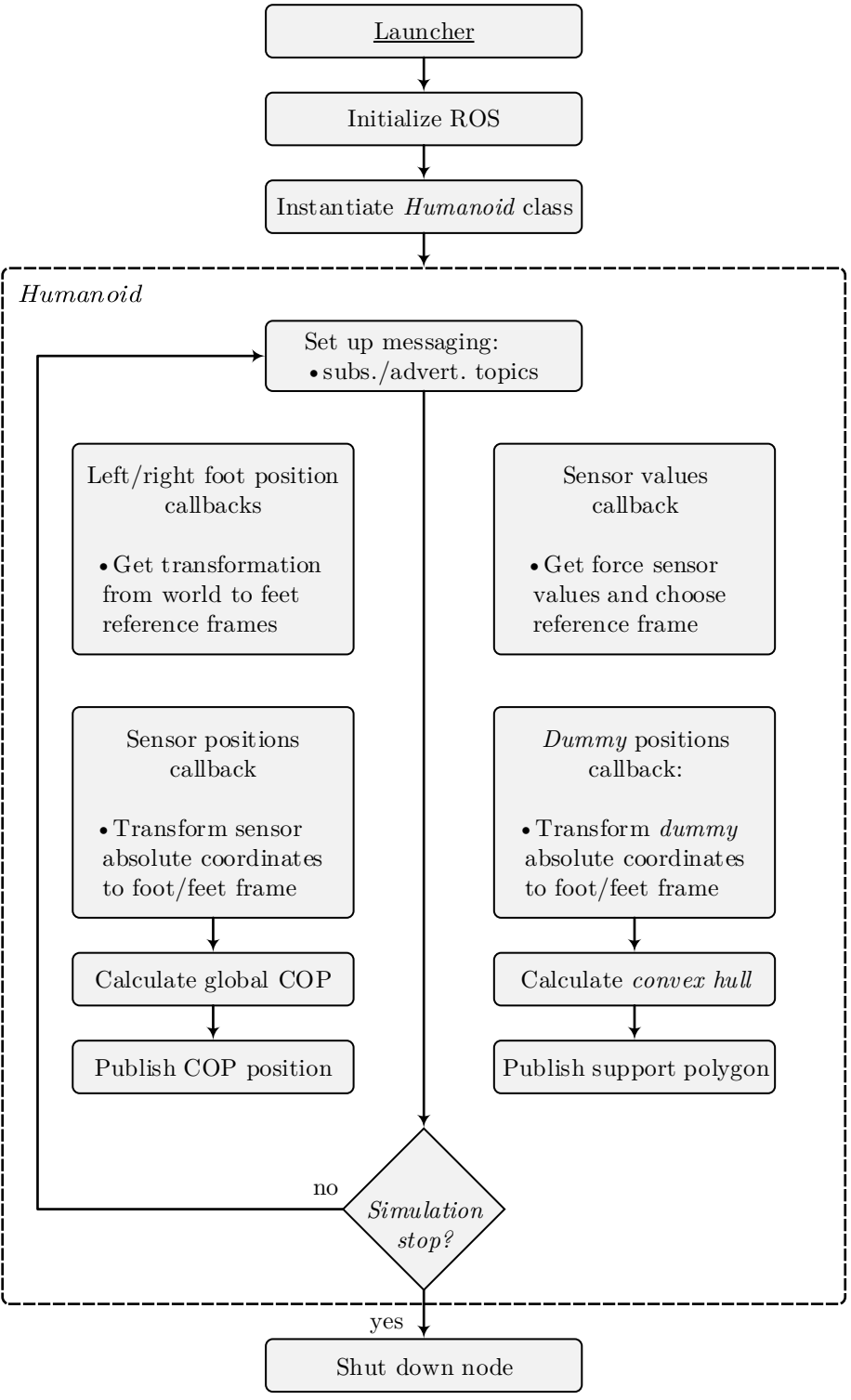
Launcher
Initialize ROS
Instantiate *Humanoid* class
Humanoid
Set up messaging:
• subs./advert. topics
Left/right foot position callbacks
• Get transformation from world to feet reference frames
Sensor values callback
• Get force sensor values and choose reference frame
Sensor positions callback
• Transform sensor absolute coordinates to foot/feet frame
Dummy positions callback:
• Transform *dummy* absolute coordinates to foot/feet frame
Calculate global COP
Calculate *convex hull*
Publish COP position
Publish support polygon
no
Simulation stop?
yes
Shut down node