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| Sommario/riassunto | Robustly maintaining balance on two legs is an important challenge for humanoid robots. The work presented in this book represents a contribution to this area. It investigates efficient methods for the decision-making from internal sensors about whether and where to step, several improvements to efficient whole-body postural balancing methods, and proposes and evaluates a novel method for efficient recovery step generation, leveraging human examples and simulation-based reinforcement learning. |