

Electronic Supplementary Material

Estimation-based disturbance adaptive model predictive control for wheeled biped robots

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Table S1 Elements of the process noise covariance in the Kalman filter

	\mathbf{v}_b	\mathbf{v}_w	x_{cw}	\dot{x}_{cw}	δ_d
\mathbf{Q}_e	1E-8	1E-8	1E-10	1E-6	1E-4

Table S2 Elements of the measurement noise covariance in the Kalman filter

	\mathbf{v}_b^l	\mathbf{v}_b^r	$\dot{\mathbf{r}}_{bw}$	\ddot{x}_c	x_{cw}	\dot{x}_{cw}
\mathbf{R}_e	1E-5	1E-5	1E-5	1E-3	1E-7	1E-5