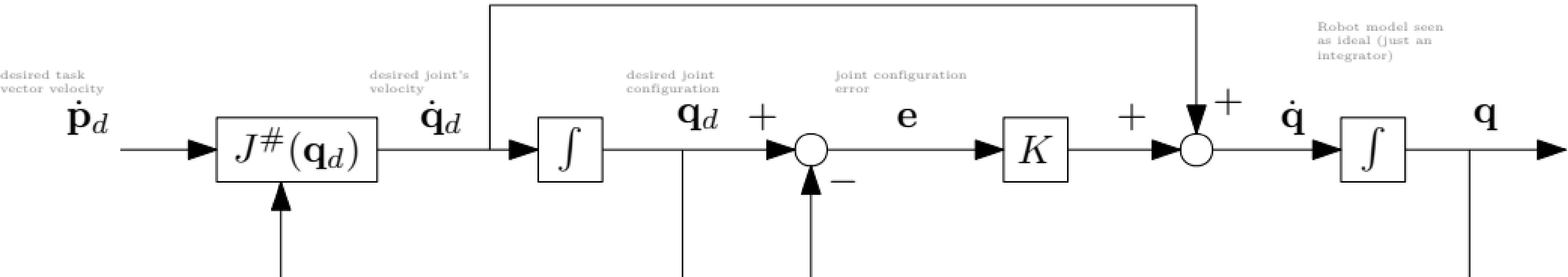


feedforward action



desired configuration
used for the
inverse differential
kinematics

feedback loop