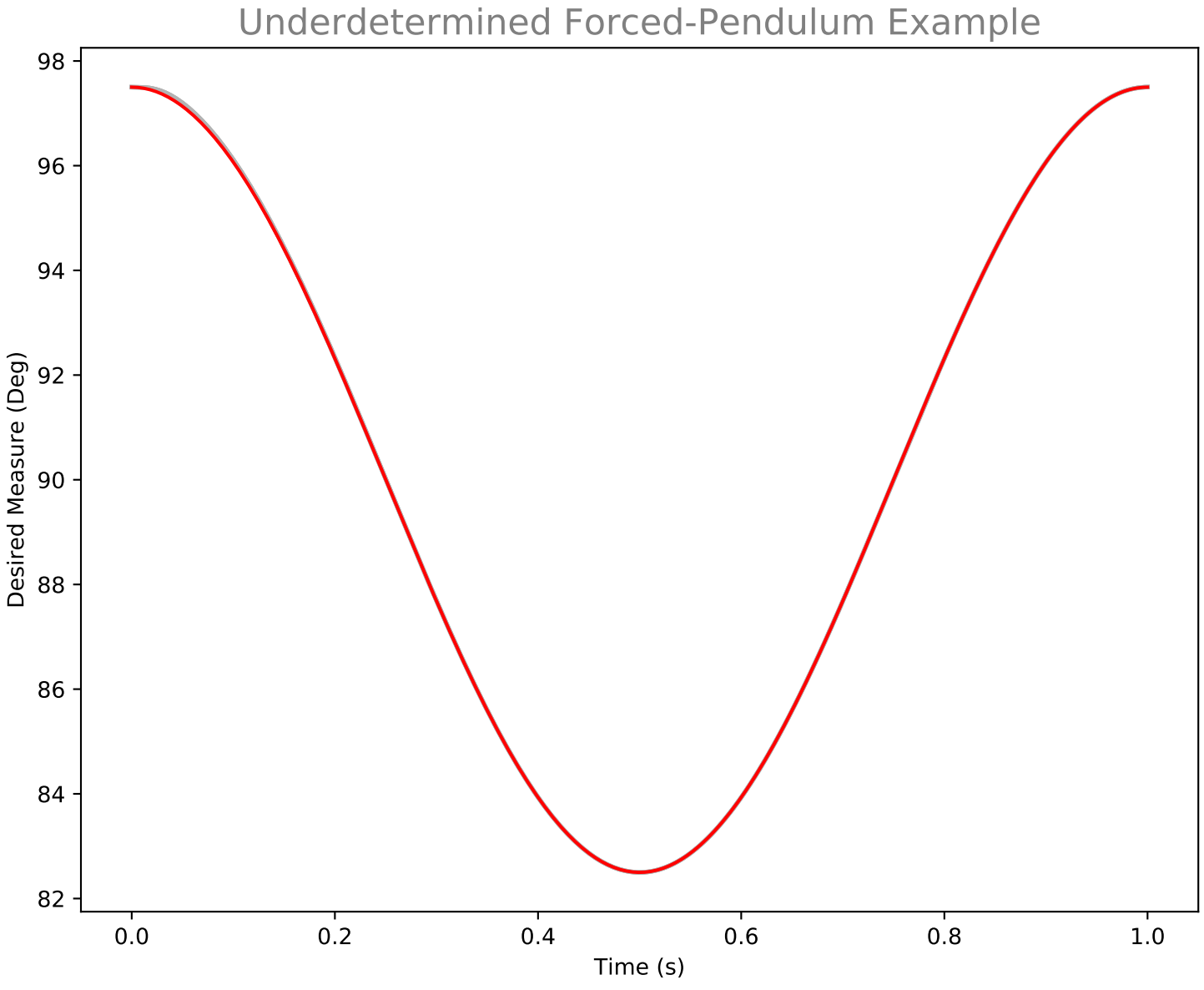
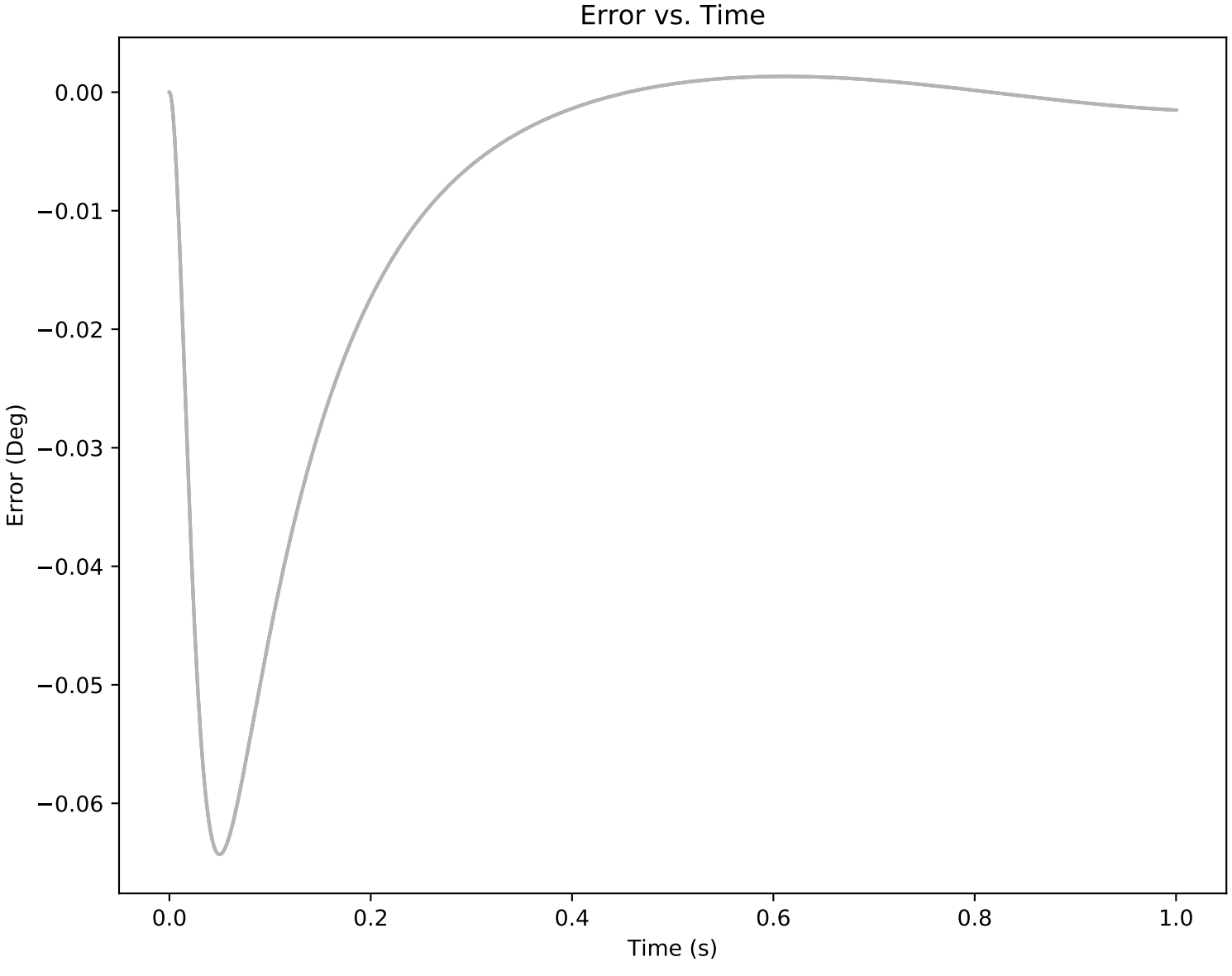
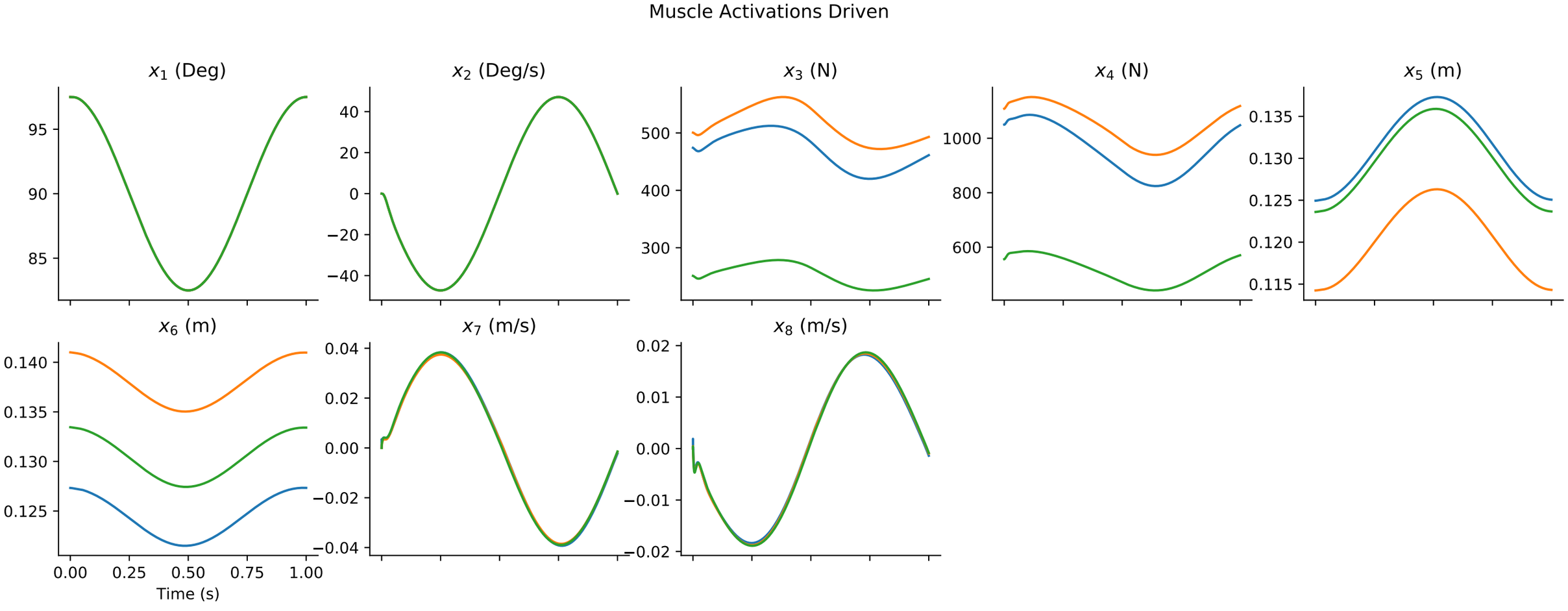
This iteration ran 3 separate trials that resulted in three distinct activation trajectories that created smooth state trajectories (i.e., without an noisy transitions that occur around 0.5 sec.). Ran with v1.0.

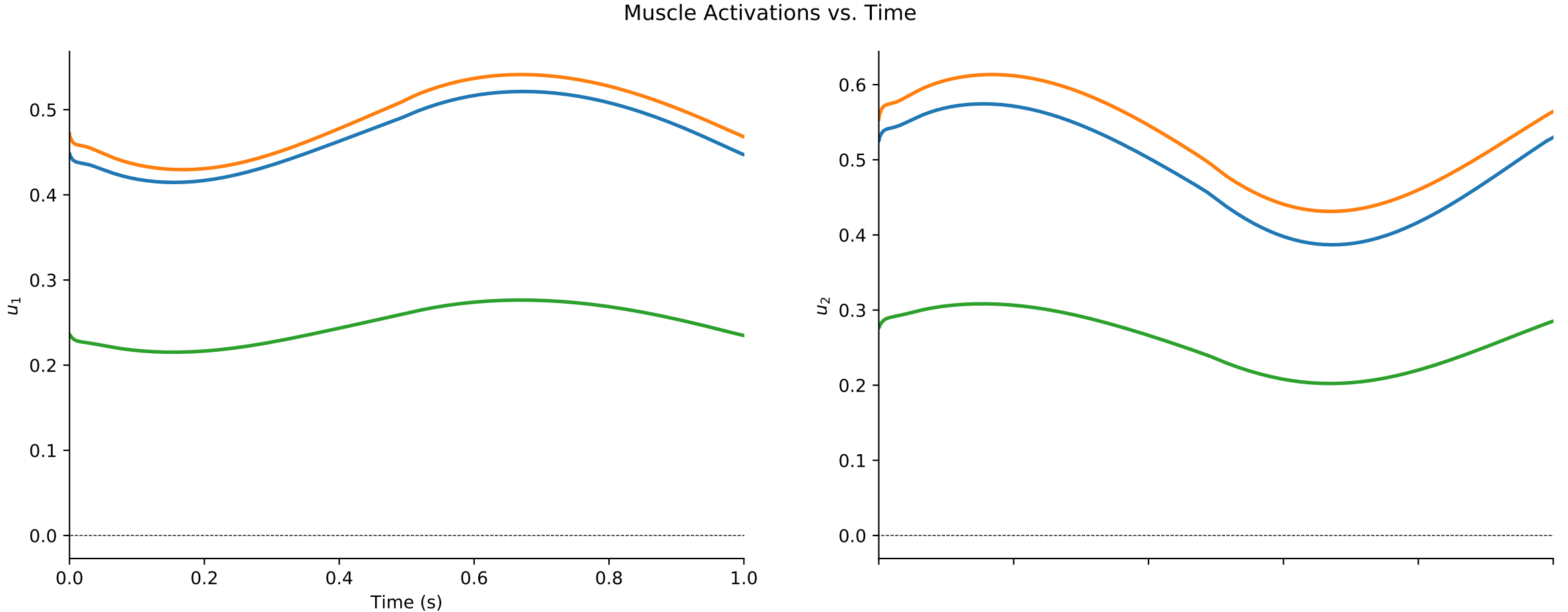
ICs:

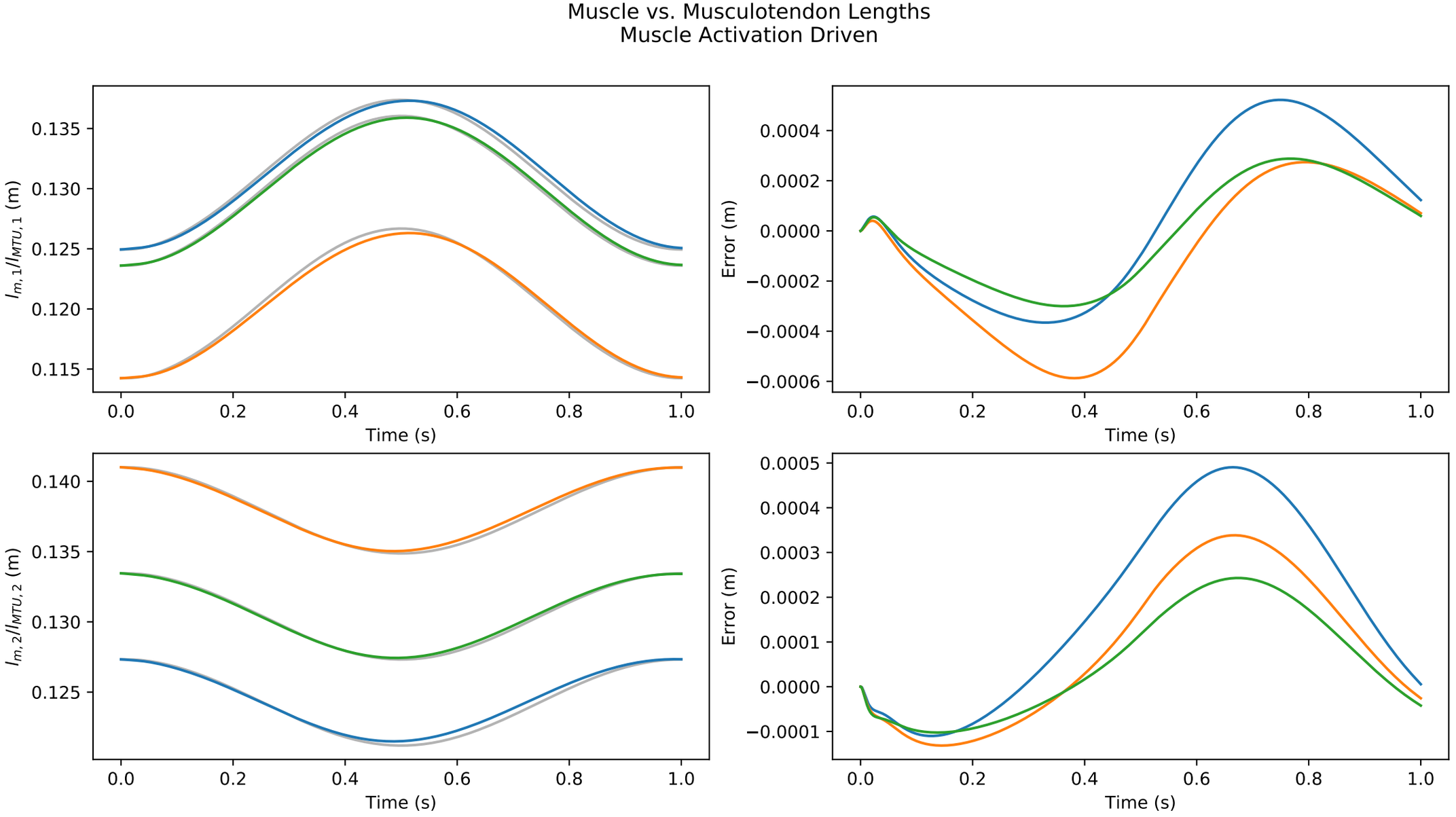
```
X_o = array([[ 1.70169602e+00, -0.00000000e+00,  4.74158764e+02,
         1.05014103e+03,  1.24943328e-01,  1.27327649e-01,
         0.00000000e+00,  0.00000000e+00],
       [ 1.70169602e+00, -0.00000000e+00,  5.00561214e+02,
         1.10861574e+03,  1.14243126e-01,  1.41001565e-01,
         0.00000000e+00,  0.00000000e+00],
       [ 1.70169602e+00, -0.00000000e+00,  2.51026303e+02,
         5.55959398e+02,  1.23603707e-01,  1.33453260e-01,
         0.00000000e+00,  0.00000000e+00]])

U_o = array([[0.44812033, 0.52583681],
       [0.47185962, 0.55379608],
       [0.23588348, 0.27700442]])
```


Underdetermined Forced-Pendulum Example
Desired Measure (Deg)
98
96
94
92
90
88
86
84
82
0.0
0.2
0.4
0.6
0.8
1.0
Time (s)


Error vs. Time
0.00
−0.01
−0.02
−0.03
−0.04
−0.05
−0.06
Error (Deg)
0.0
0.2
0.4
0.6
0.8
1.0
Time (s)


Muscle Activations Driven
x_1 (Deg)
x_2 (Deg/s)
x_3 (N)
x_4 (N)
x_5 (m)
x_6 (m)
x_7 (m/s)
x_8 (m/s)
Time (s)


Muscle Activations vs. Time
u_1
u_2
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0.0
0.2
0.4
0.6
0.8
1.0
Time (s)


Muscle vs. Musculotendon Lengths
Muscle Activation Driven
$l_{m,1}/l_{MTU,1}$ (m)
0.135
0.130
0.125
0.120
0.115
0.0
0.2
0.4
0.6
0.8
1.0
Time (s)
Error (m)
0.0004
0.0002
0.0000
−0.0002
−0.0004
−0.0006
Time (s)
$l_{m,2}/l_{MTU,2}$ (m)
0.140
0.135
0.130
0.125
Time (s)
Error (m)
0.0005
0.0004
0.0003
0.0002
0.0001
0.0000
−0.0001
Time (s)