θ_d   +   Δθ   Controller   Δρ   ∫ 1)   ρ   Equilibrium Model 2)   α_flexor   Sign Flexor   Antagonist Joint
−
c
α_extensor   Sign Extensor
θ   Sign Encoder

1)   ρ = ρ + (Δρ)(sign_equilibrium)

2)   α_flexor   = -ρ(ɣ/4) + c(π/2)   , ɣ = servo_range
       α_extensor = ρ(ɣ/4) + c(π/2)