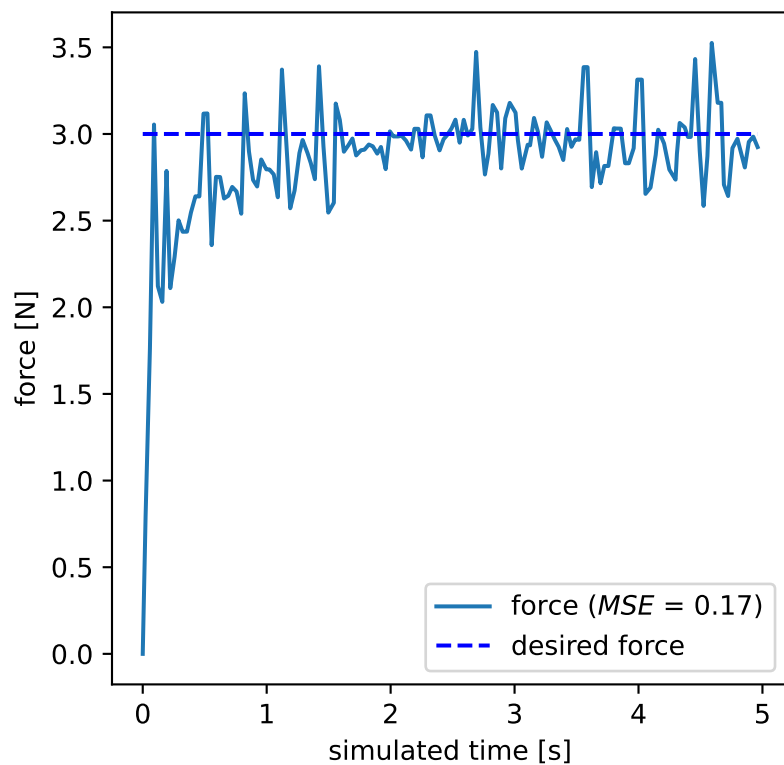
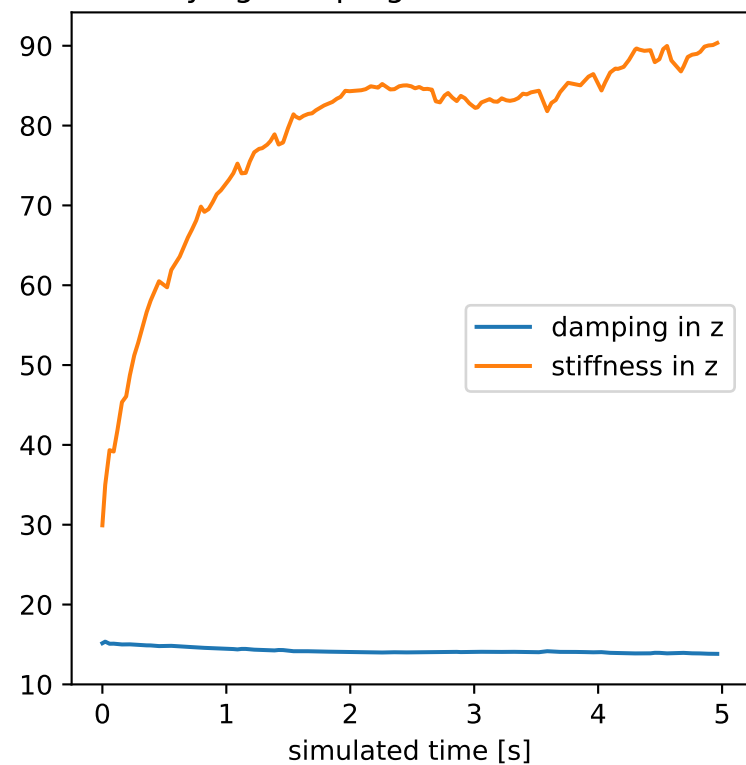


Performance of Force-based VIC (sim)

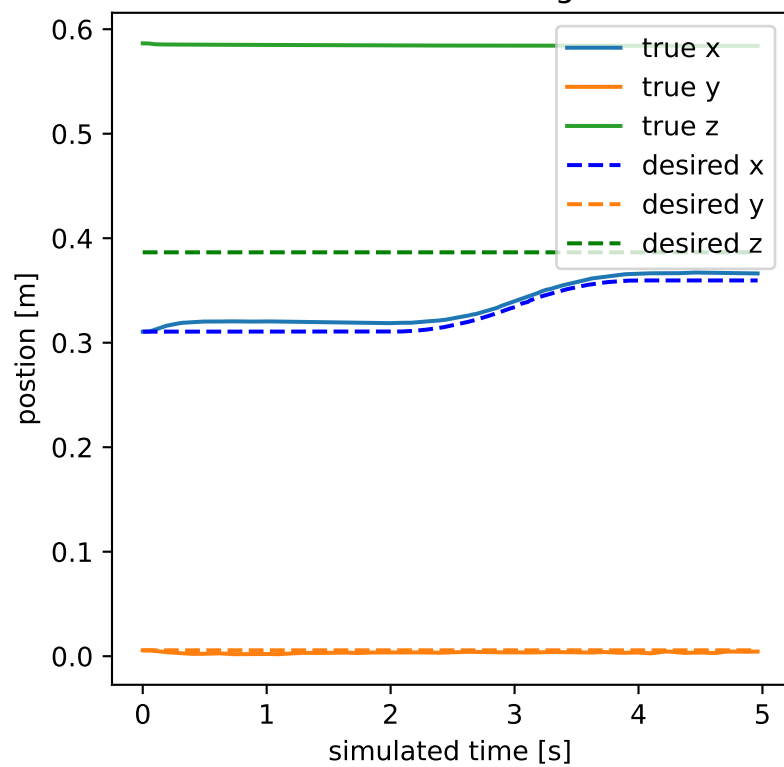
Contact force



Varying damping and stiffness in z



Motion tracking



Deviation from desired orientation

