```
void GeneralControlLoop::init()
{


        localParameters.outputNegMax=-4000;  //-4000 is -100%
        localParameters.outputPosMax=4000;   // 4000 is +100%
        localParameters.polyPar[0]=0; //adjust those 4 values to your spring
        localParameters.polyPar[1]=1; //should map displacement into a force in [N]
        localParameters.polyPar[2]=0; // here a linear mapping with a gain of 1
        localParameters.polyPar[3]=0;

        localParameters.radPerEncoderCount=2*M_PI/(2000.0*53.0); //gear box ratio of 53 and
                        //2000 counts per rotation with encoder (4 x 500 pulse, edge count)

        localParameters.spNegMax=-10; //limit position reference value
        localParameters.spPosMax=10;
        localParameters.tag=0; //don't care, leave to 0
        localParameters.timePeriod=1010; //us
        localParameters.torqueConstant=1; // motor constant, set to useful value when torque control required

        localParameters.params.pidParameters.IntegralNegMax=-4000;  //limit the integrator
        localParameters.params.pidParameters.IntegralPosMax=4000;
        localParameters.params.pidParameters.deadBand=0;            //choose dead-band
        localParameters.params.pidParameters.forwardGain=0;         //set controller gains
        localParameters.params.pidParameters.pgain=0.12;
        localParameters.params.pidParameters.igain=0;
        localParameters.params.pidParameters.dgain=0;
        localParameters.params.pidParameters.integral=0; //initialise the integrator
        localParameters.params.pidParameters.lastError=0; //initialise last error

        //configure a few position controllers
        //other modes: Raw=0,   Torque=1,   Velocity=2, Position=3, Force=4,

        p_robot->getGanglion(0)->getMuscles()[0]->setControllerParams(Position,localParameters);
        p_robot->getGanglion(0)->getMuscles()[1]->setControllerParams(Position,localParameters
        p_robot->getGanglion(3)->getMuscles()[2]->setControllerParams(Position,localParameters);
        p_robot->getGanglion(4)->getMuscles()[3]->setControllerParams(Position,localParameters);
}
```