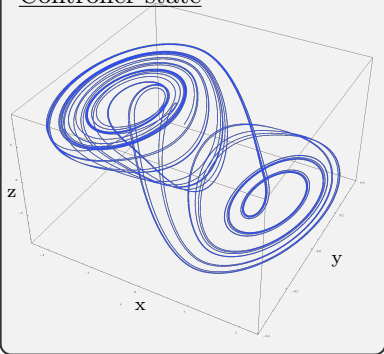
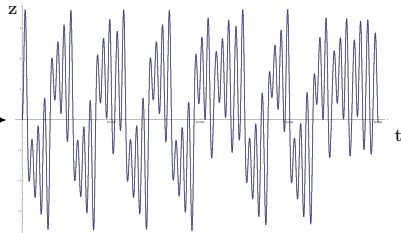


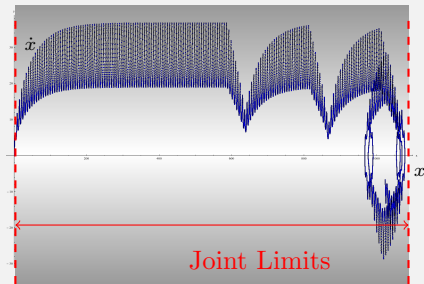
Controller state



Controller output



Joint dynamics



applied as
Torque T

