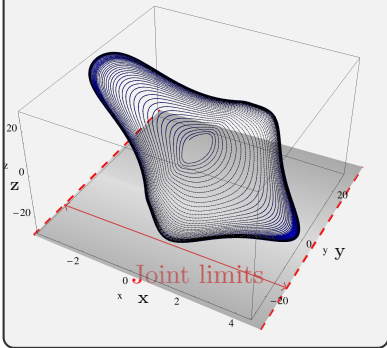
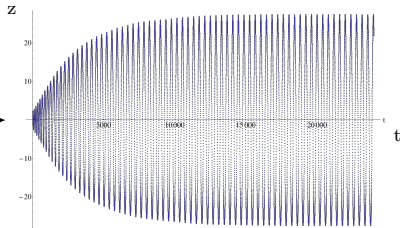


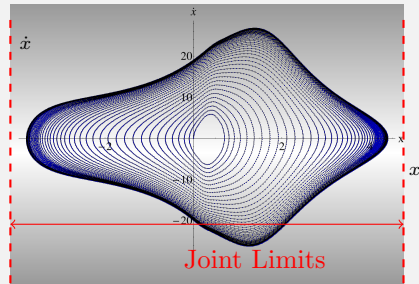
Controller state



Controller output

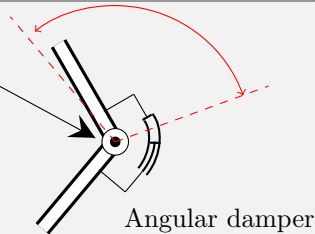


Joint dynamics



applied as

Torque T



Sensory feedback

Joint position x as controller state value x

Joint velocity \dot{x} as controller state value y