Gait Mask		Run	Walk	Stand	
- — — — — Task	r Lin Vel Track	r ^{Vel Tracking}	r ^{Vel Tracking}	r ^{Vel Tracking}	r ^{Vel Tracking}
Reward	r Ang Vel Track	r Ang Vel Track	r ^{Ang Vel Track}	r ^{Ang Vel Track}	r Ang Vel Track
Gait-related Reward	r ^{Contact_walk}	rContact_walk	r ^{Contact_walk}	rContact_walk	rContact_walk
	r ^{Straight Knee}	r Straight Knee	r ^{Straight} Knee	_r Straight Knee	γ Straight Kne
	rContact_stand	$r^{{\cal C}ontact_stand}$	rContact_stand	r ^{Contact_stand}	r ^C ontact_stand
	r Stability	γ Stability	_r Stability	r ^{Stability}	_T Stability
	r Deceleration	r Deceleration	_T Deceleration	r Deceleration	r Deceleration
			•••	•••	
	r ^{Contact_Run}	r ^{Contact_Run}	rContact_Run	rContact_Run	rContact_Run
	rShort Contact	rShort Contact			•••
	r Push of f	r Push off	r Push off	r Push off	r Push of f
	r Ang Momentum	r ^{Ang Momentum}	r ^{Ang Momentum}	r Momentum	r Momentum
	r Arm energy	r ^{Arm energy}	r Arm energy	r Arm energy	r Arm energy
Regulation Reward	r ^{Torque}	r ^{Torque}	r ^{Torque}	r ^{Torque}	r ^{Torque}
	r Base Height	r Base Height	r Base Height	r ^{Base} Height	r Base Height
				•••	•••