active inference model using only prediction error in the fwd mdl input sensorimotor temporal tapping style Block diagram style g_t RefArc S_t \hat{e}_t $s_t + \hat{e}_t$ Body e_t World \hat{e}_t $t \leftarrow t + 1$ only need this line e_{t} $s_t + \hat{e}_t$ when sys is kinematic e_t^{-1} S_{t} inf. propagation pred. propagation ----