

Goal  $\mathbf{q}_{target}$

Global feedback policy  
 $\boldsymbol{\tau}, R = f(\dot{\mathbf{q}}, \mathbf{q})$

$\dot{q}_1, q_1$

$\tau_1, R_{11}$

$\dots$

$\dot{q}_n, q_n$

$\tau_n, R_{nn}$

Local actuator controller

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