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

Trajectory Generation

$\ddot{\boldsymbol{q}}_d(:), \dot{\boldsymbol{q}}_d(:), \boldsymbol{q}_d(:)$

Trajectory following controller
$\boldsymbol{\tau}, R = f(\dot{\boldsymbol{q}}, \boldsymbol{q}, \text{t})$

$\dot{q}_1, q_1$ τ_1, R_{11} $\cdots$ $\dot{q}_n, q_n$ τ_n, R_{nn}

Local actuator controller   Local actuator controller