OBJECTIVE $x_d(t) = [0, 0.7, 0.7, 0, 0]$ low-skill Q = [0, 150, 100, 0, 0] R = [0.1, 0.1]user $x_d(t) = [0, v(t), 1.7, 0, 0]$ Q = [0.150, 100, 0, 0] R = [0.1, 0.1]skilled user

TABLE II: SLIP Simulation Setup.

$v(t) = \begin{cases} 0.2m/s & 0s < t \le 8s \\ 0.2 + 0.05(t - 8)m/s & 8s < t \le 16s \\ 0.6m/s & 16s < t \le 24s \end{cases}$

MIG filter

& controller

 $x_d(t) = [0, 0, 1.4, 0, 0]$

Q = [0, 0, 5, 0, 0] R = [0.1, 0.1]