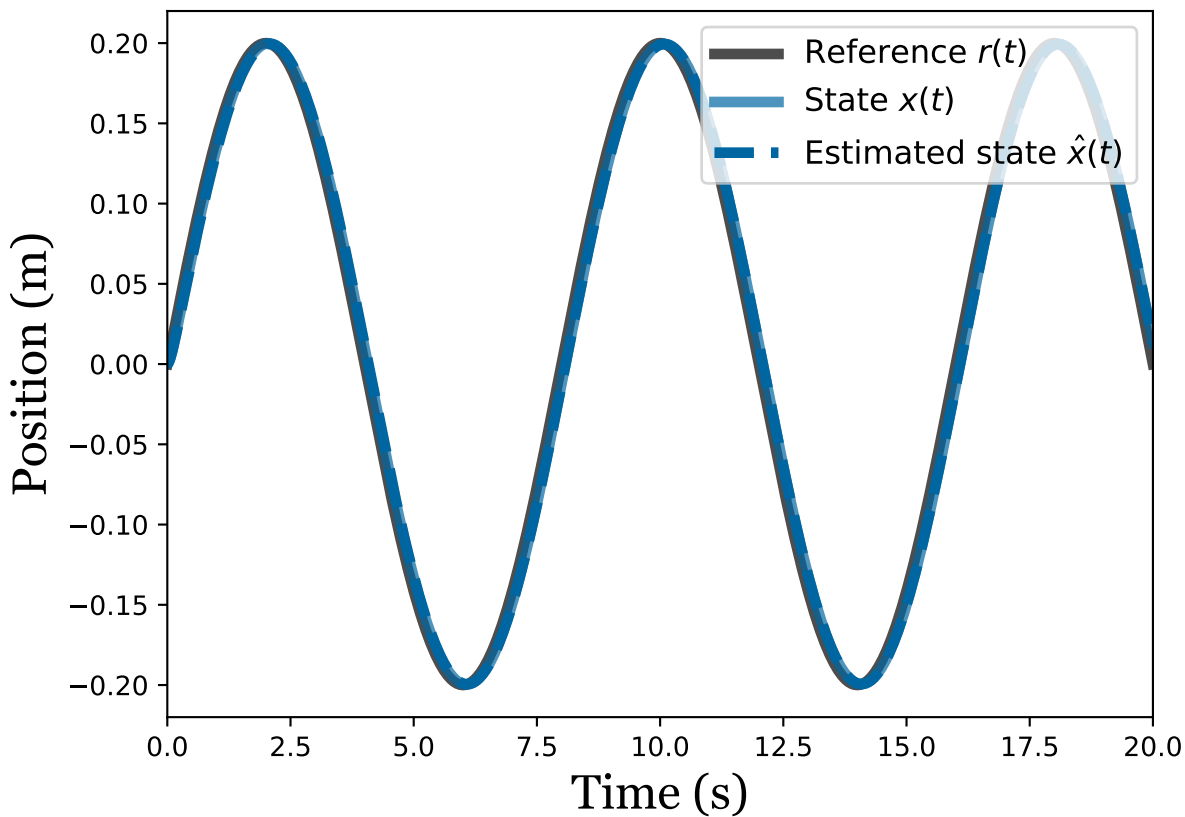
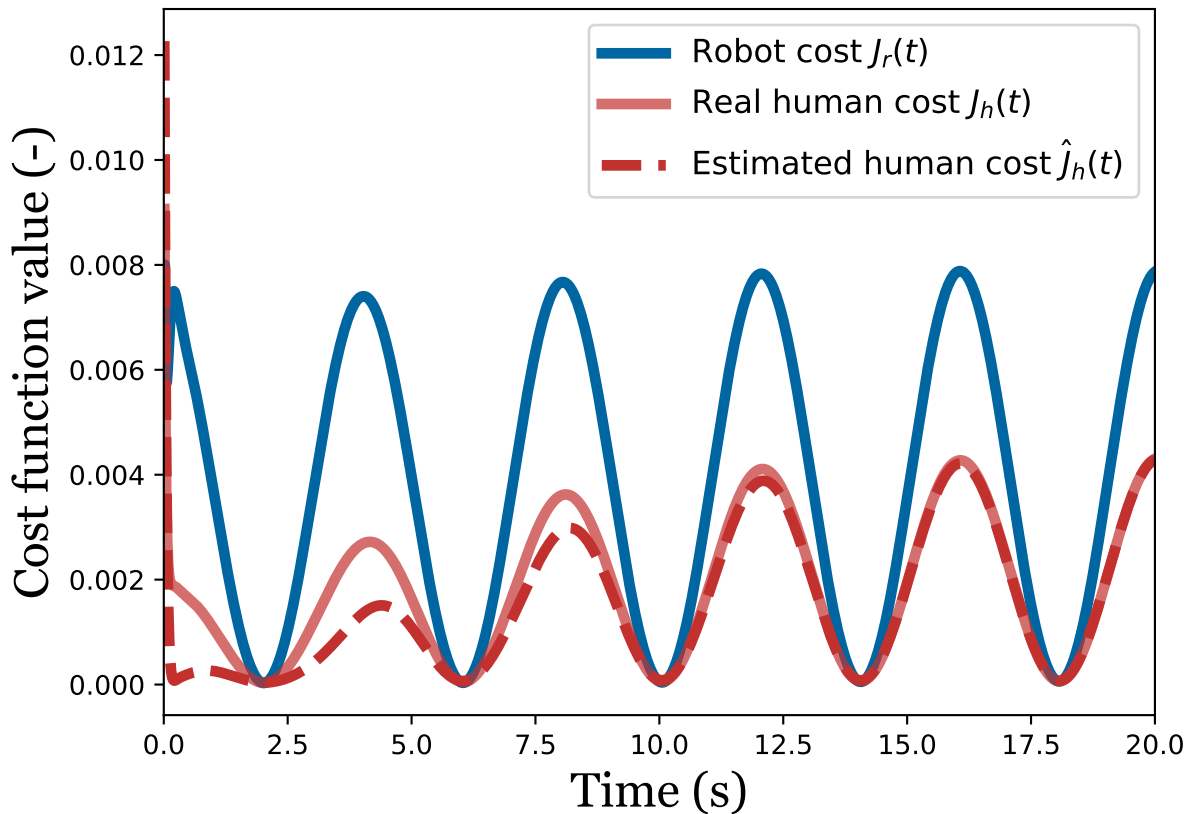


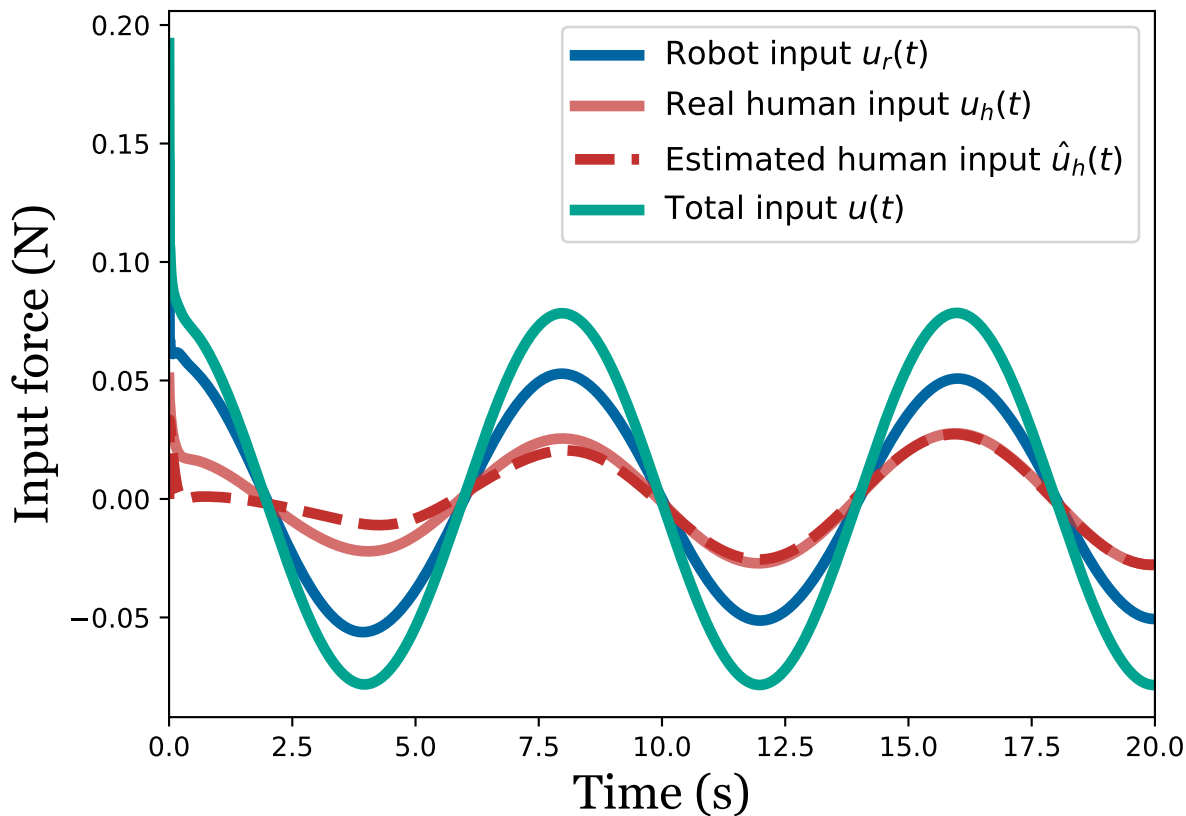
Position



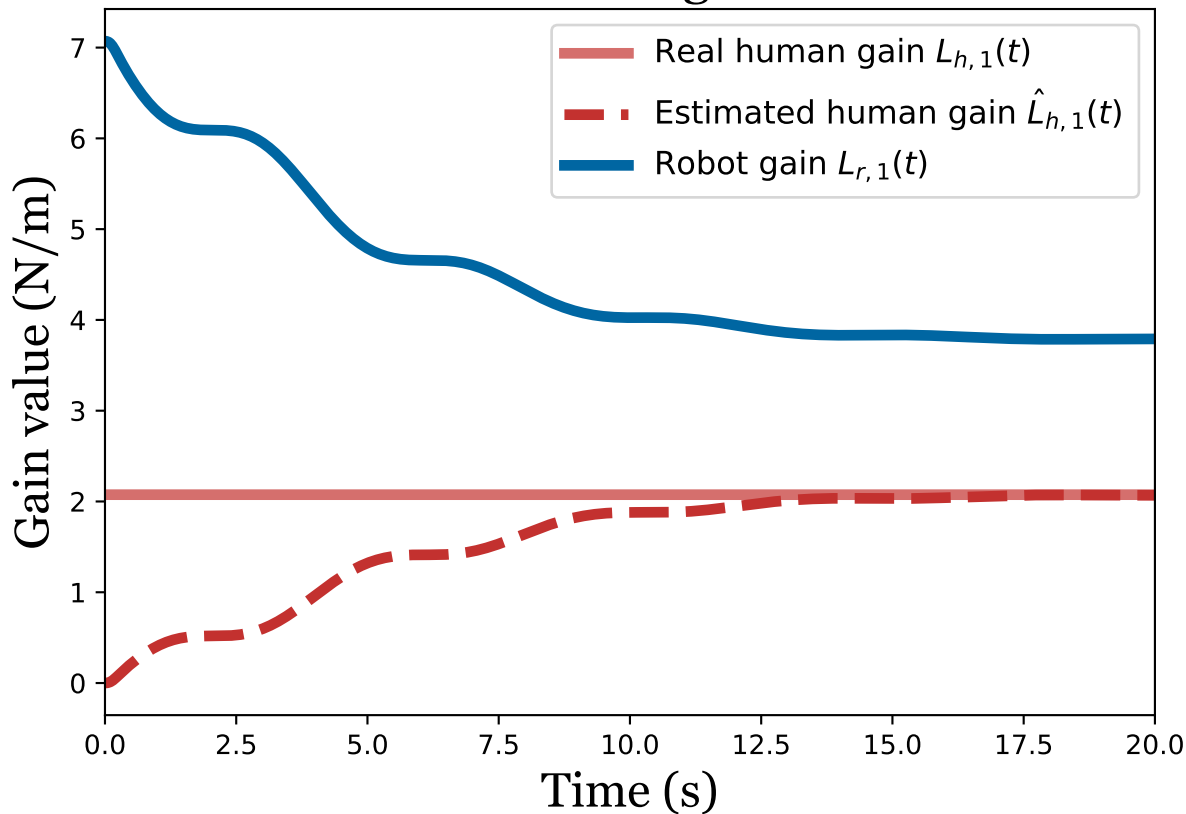
Cost function



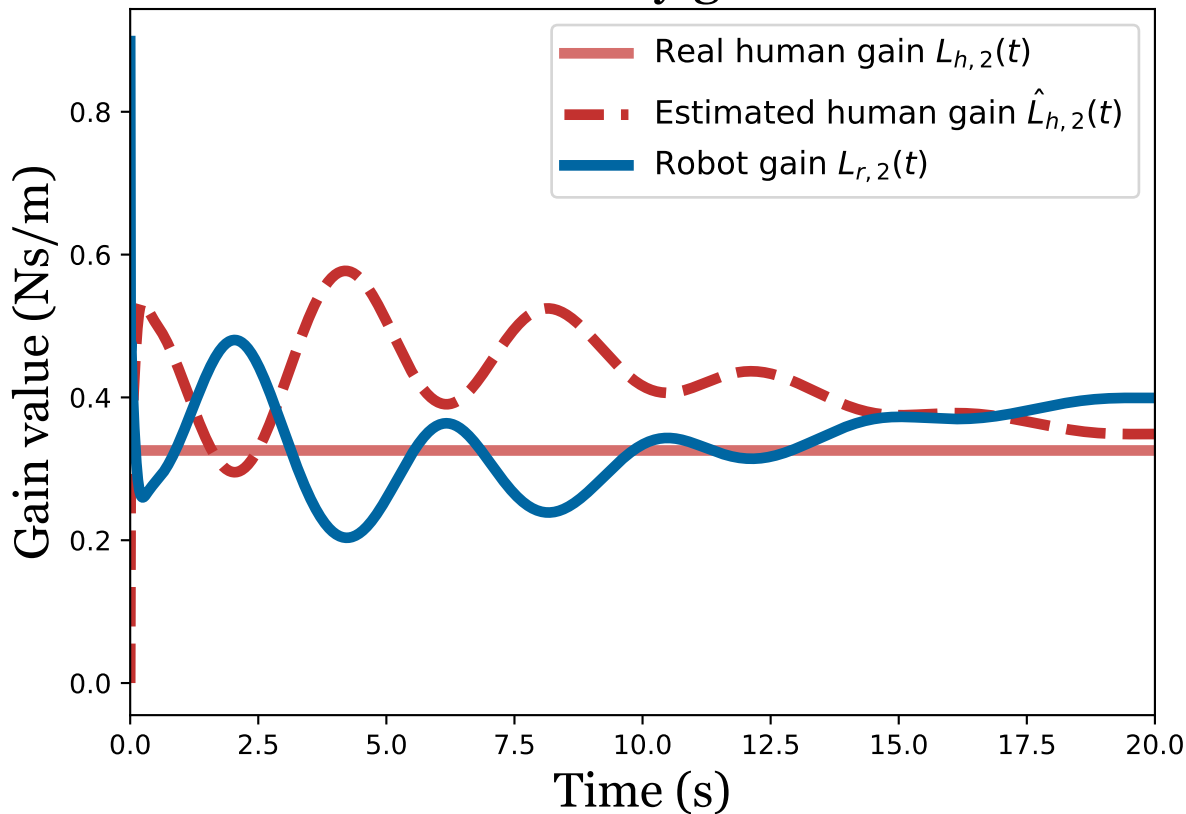
Control action



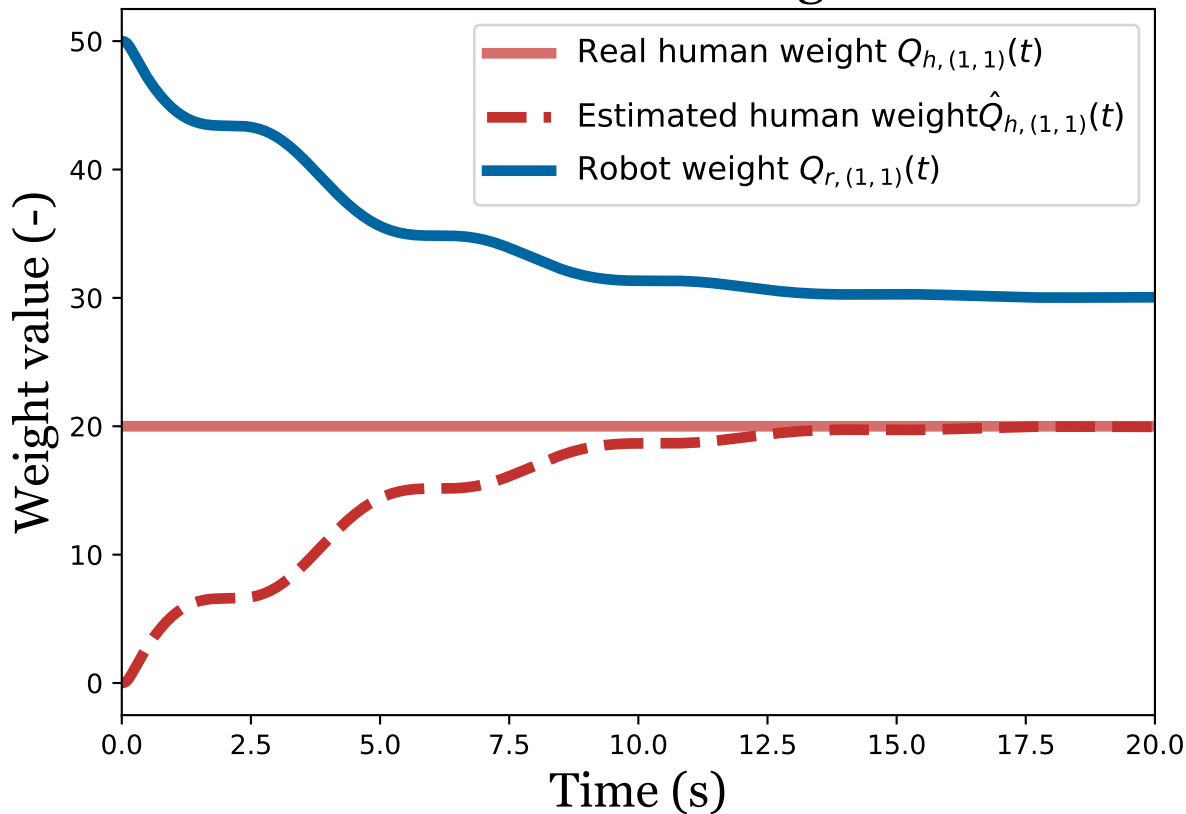
Position gain



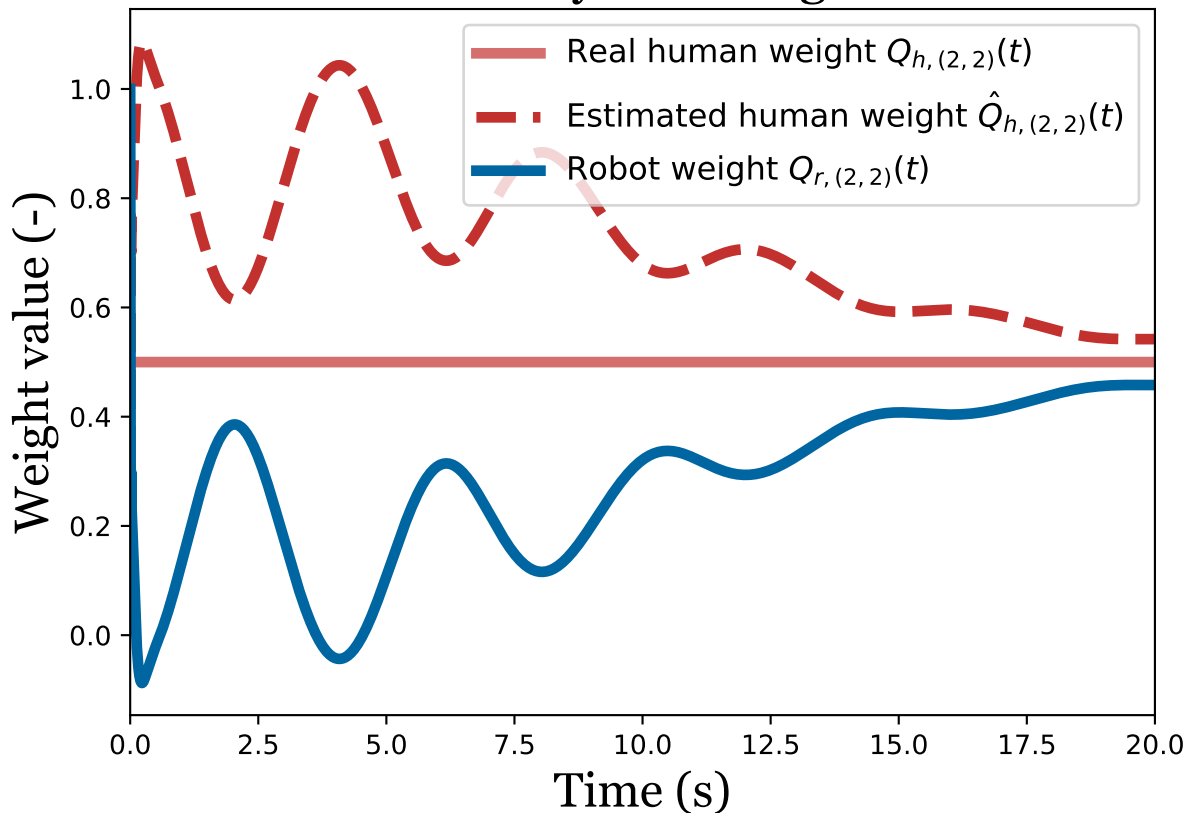
Velocity gain



Position cost weight



Velocity cost weight



Velocity

