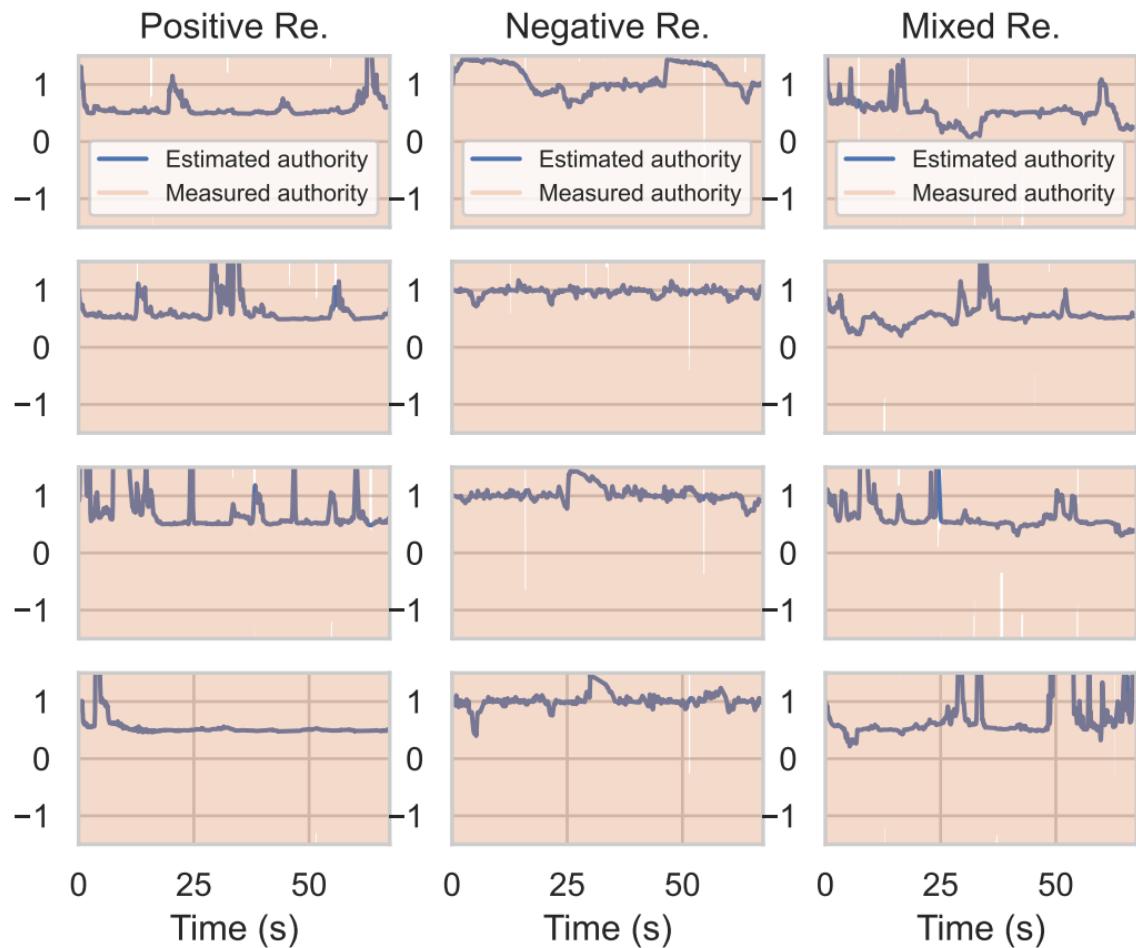
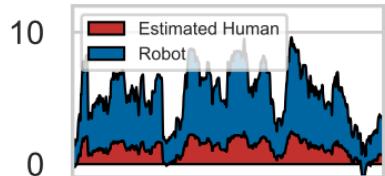


# Estimated Control Authority

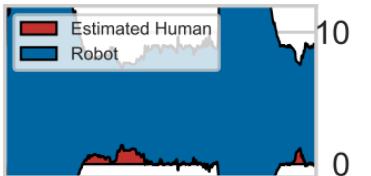


# Gains

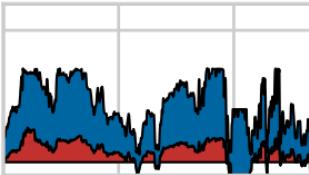
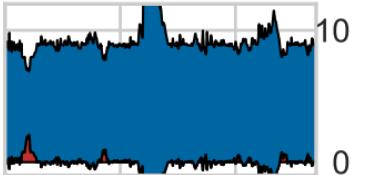
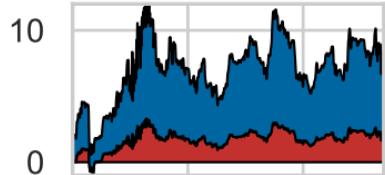
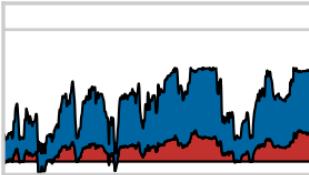
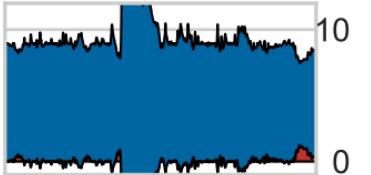
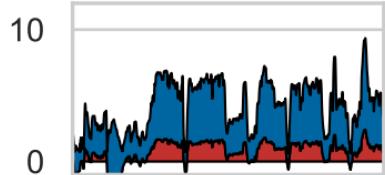
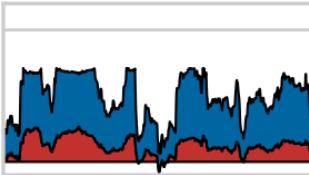
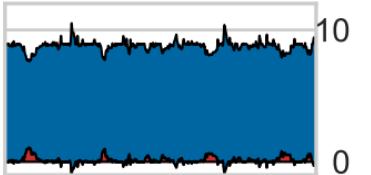
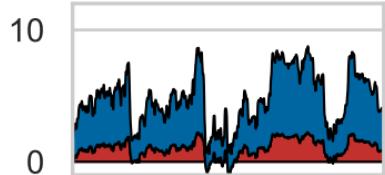
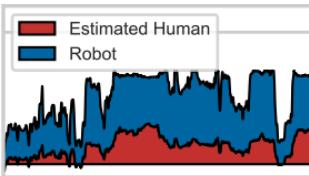
Positive Re.



Negative Re.



Mixed Re.

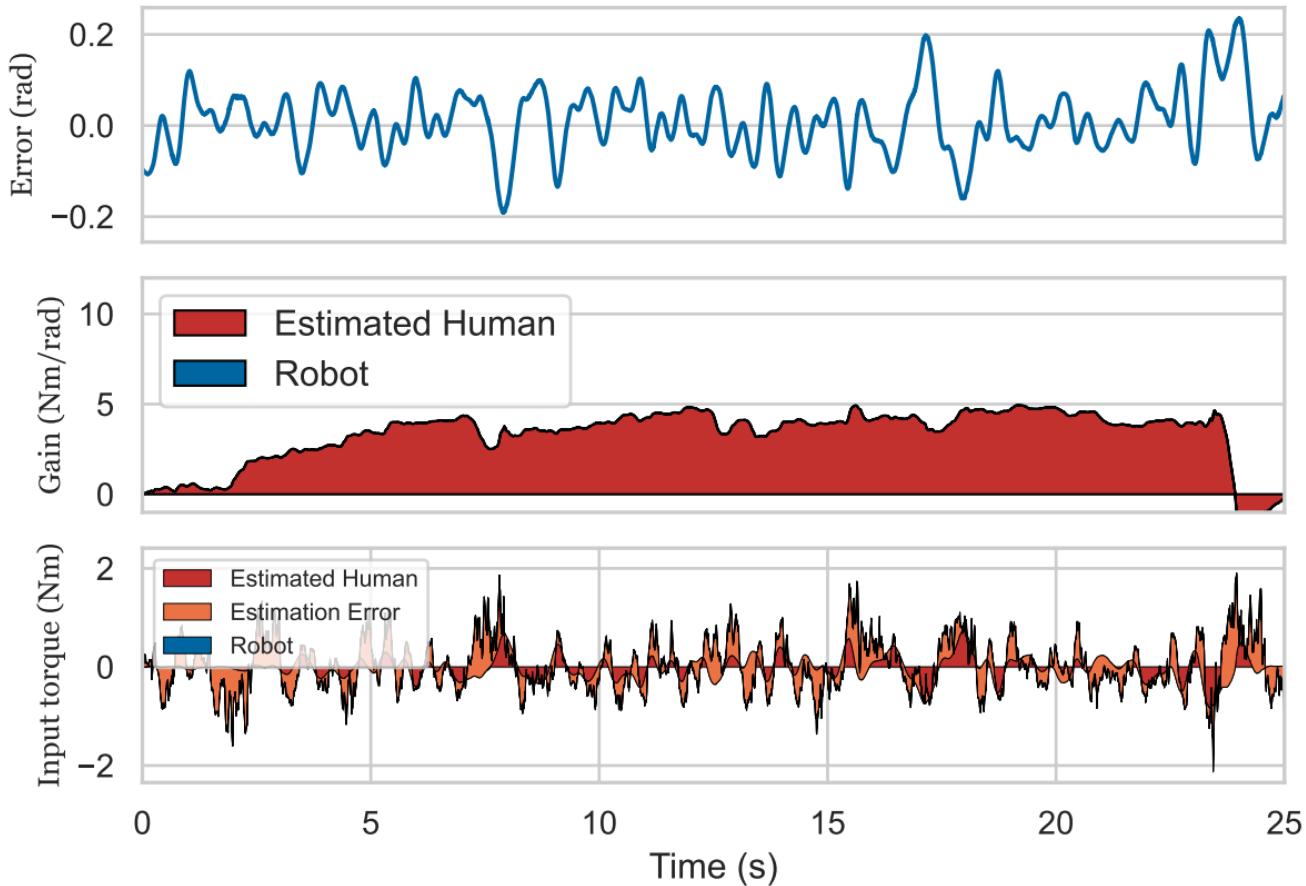


Time (s)

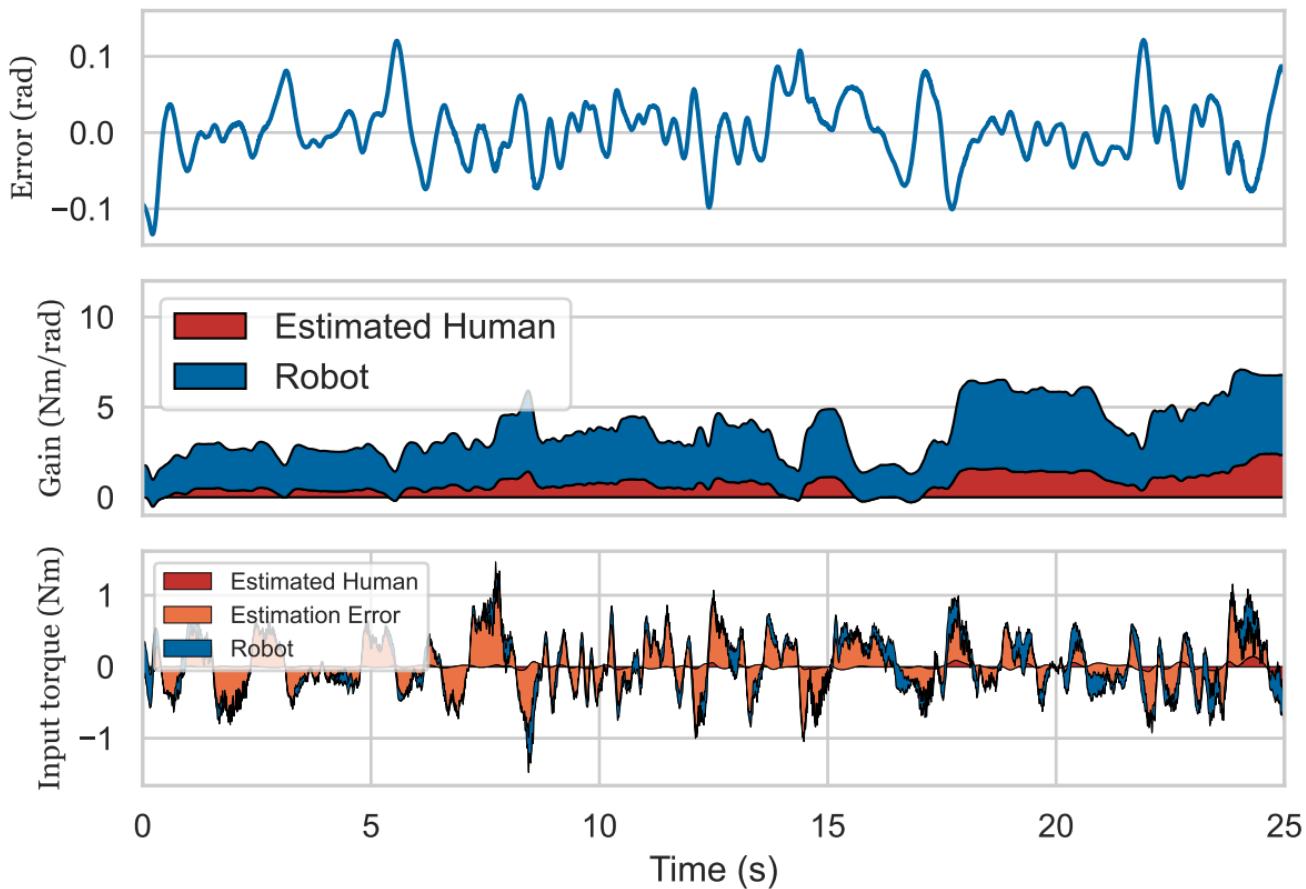
Time (s)

Time (s)

# Manual Control



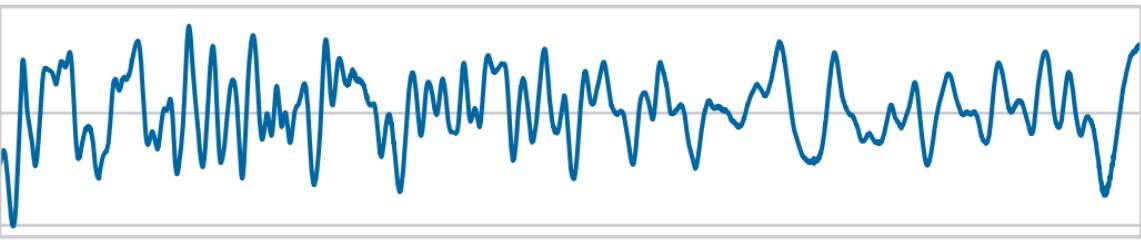
# Mixed Reinforcement



# Negative Reinforcement

Error (rad)

0.0  
-0.1



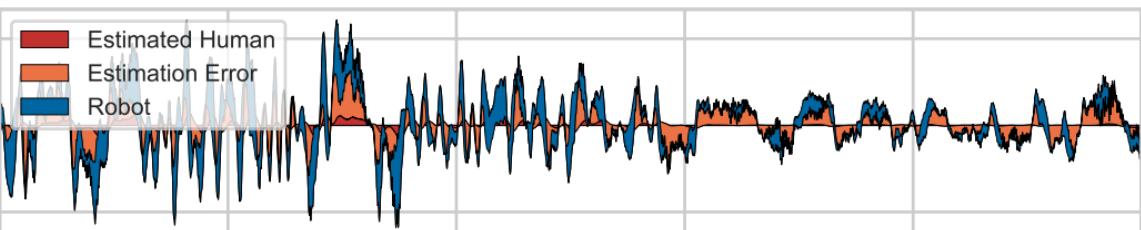
Gain (Nm/rad)

10  
5  
0



Input torque (Nm)

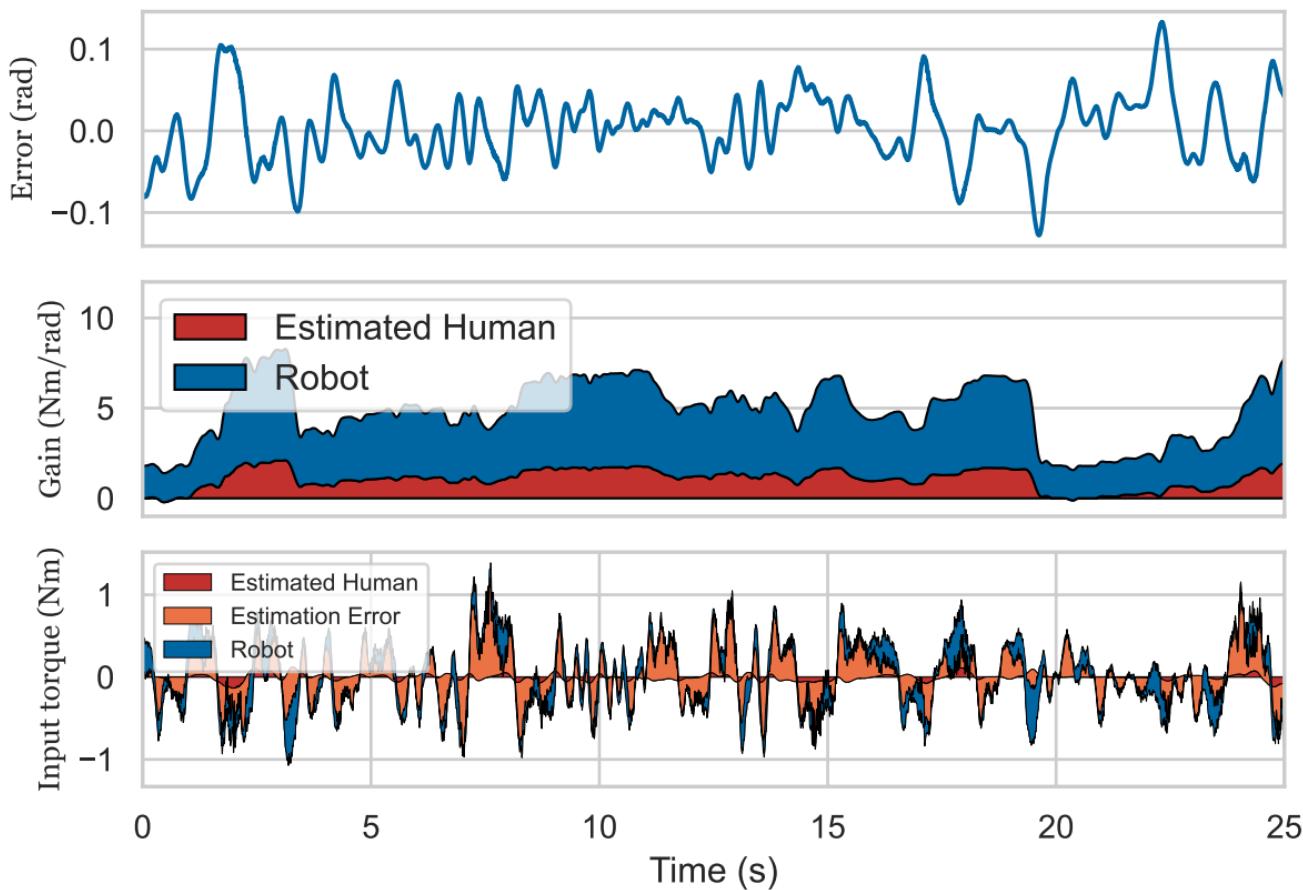
2  
0  
-2



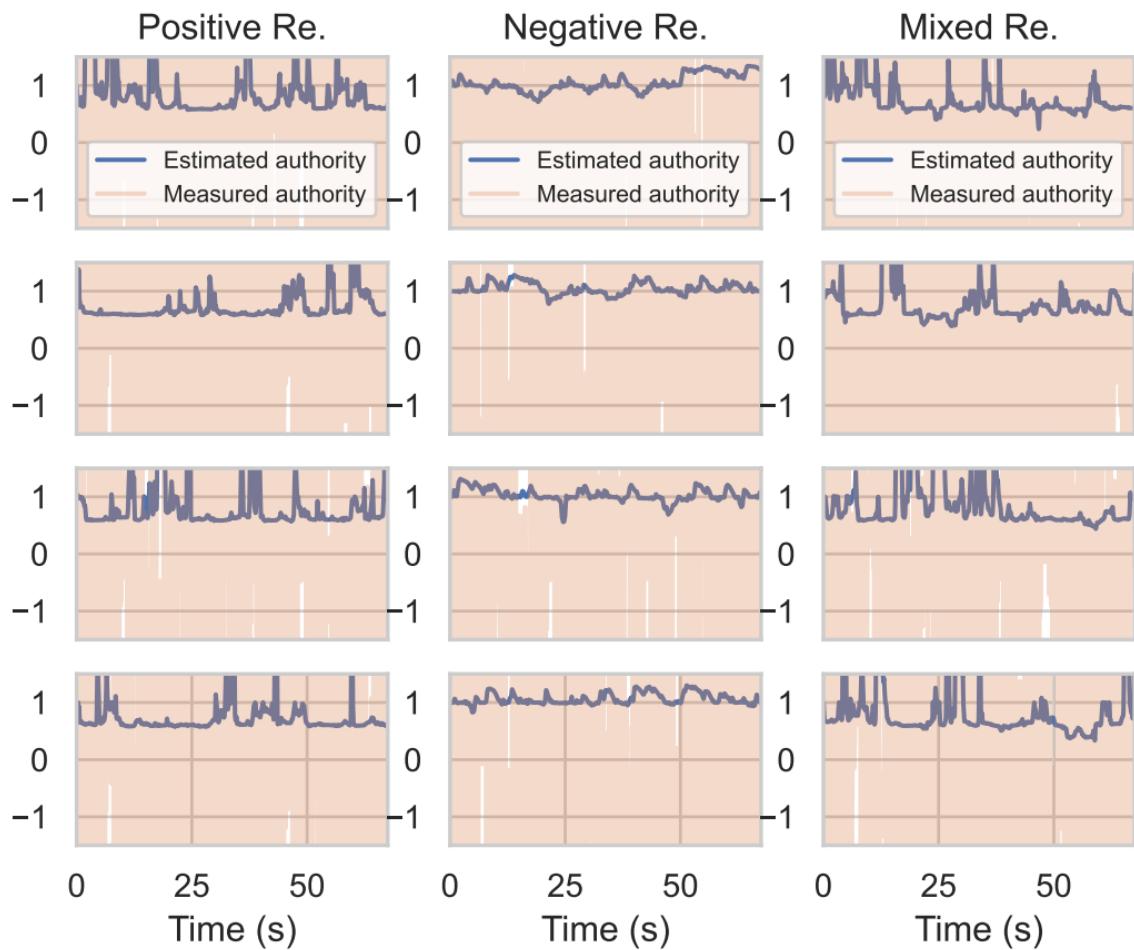
0 5 10 15 20 25

Time (s)

# Positive Reinforcement

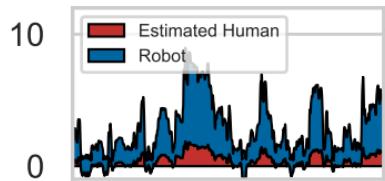


# Estimated Control Authority

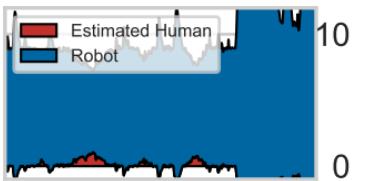


# Gains

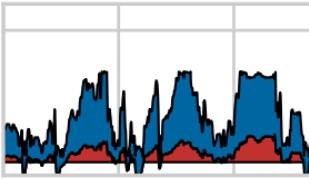
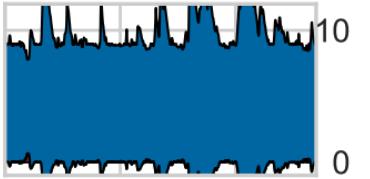
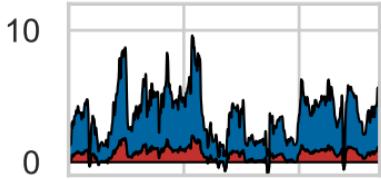
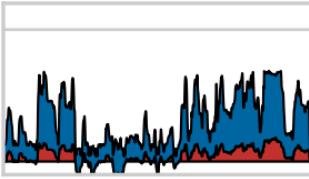
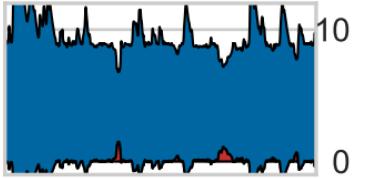
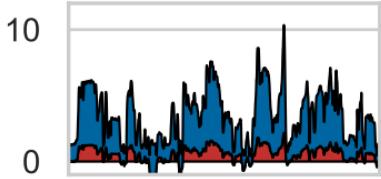
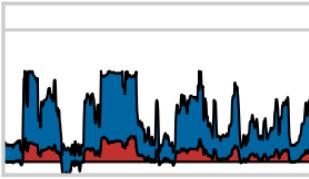
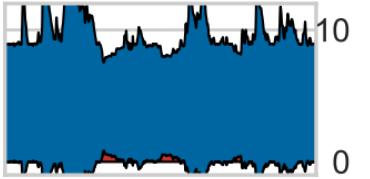
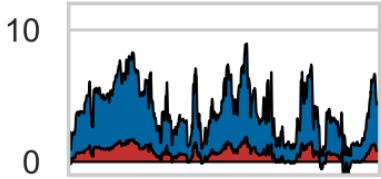
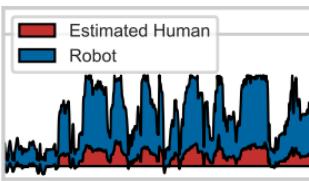
Positive Re.



Negative Re.

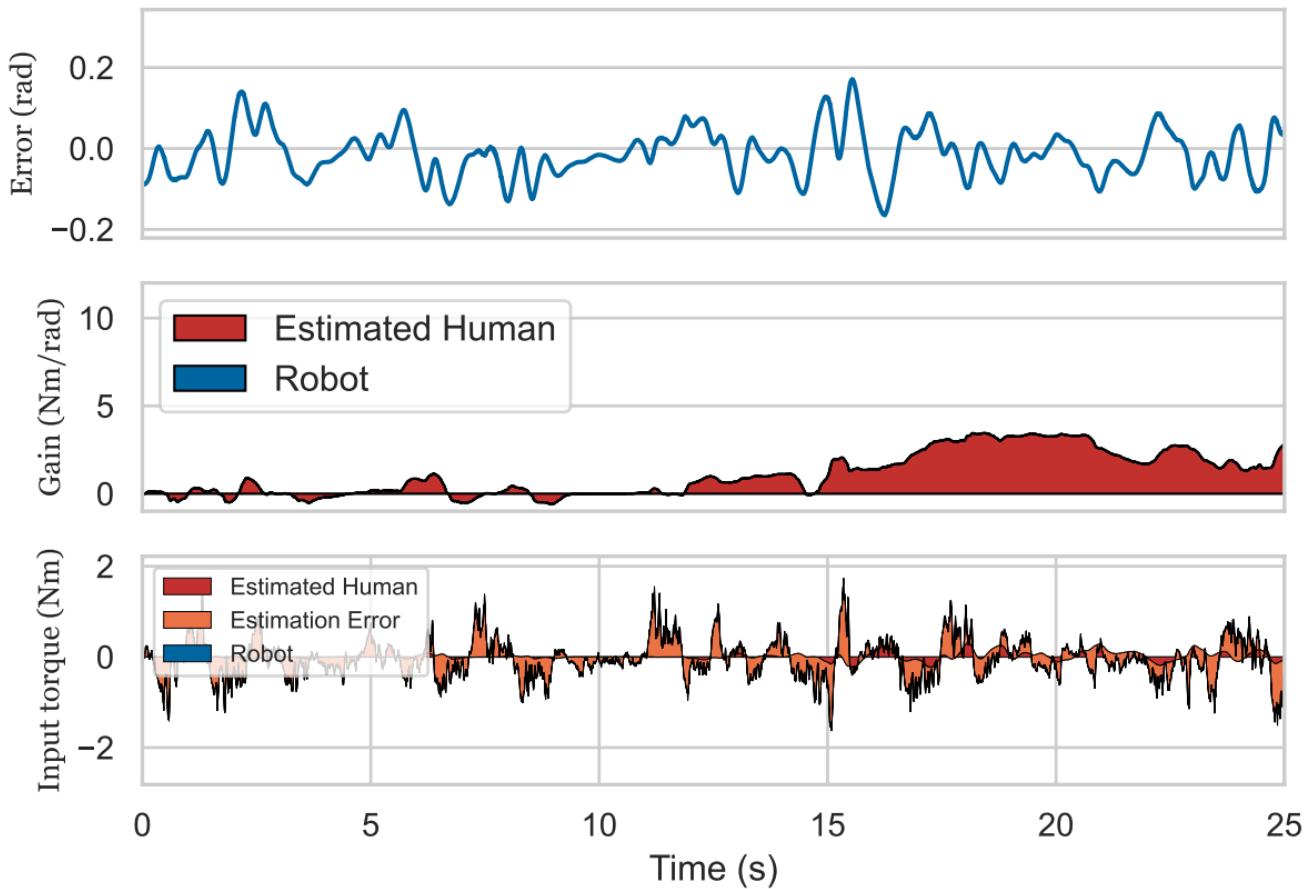


Mixed Re.

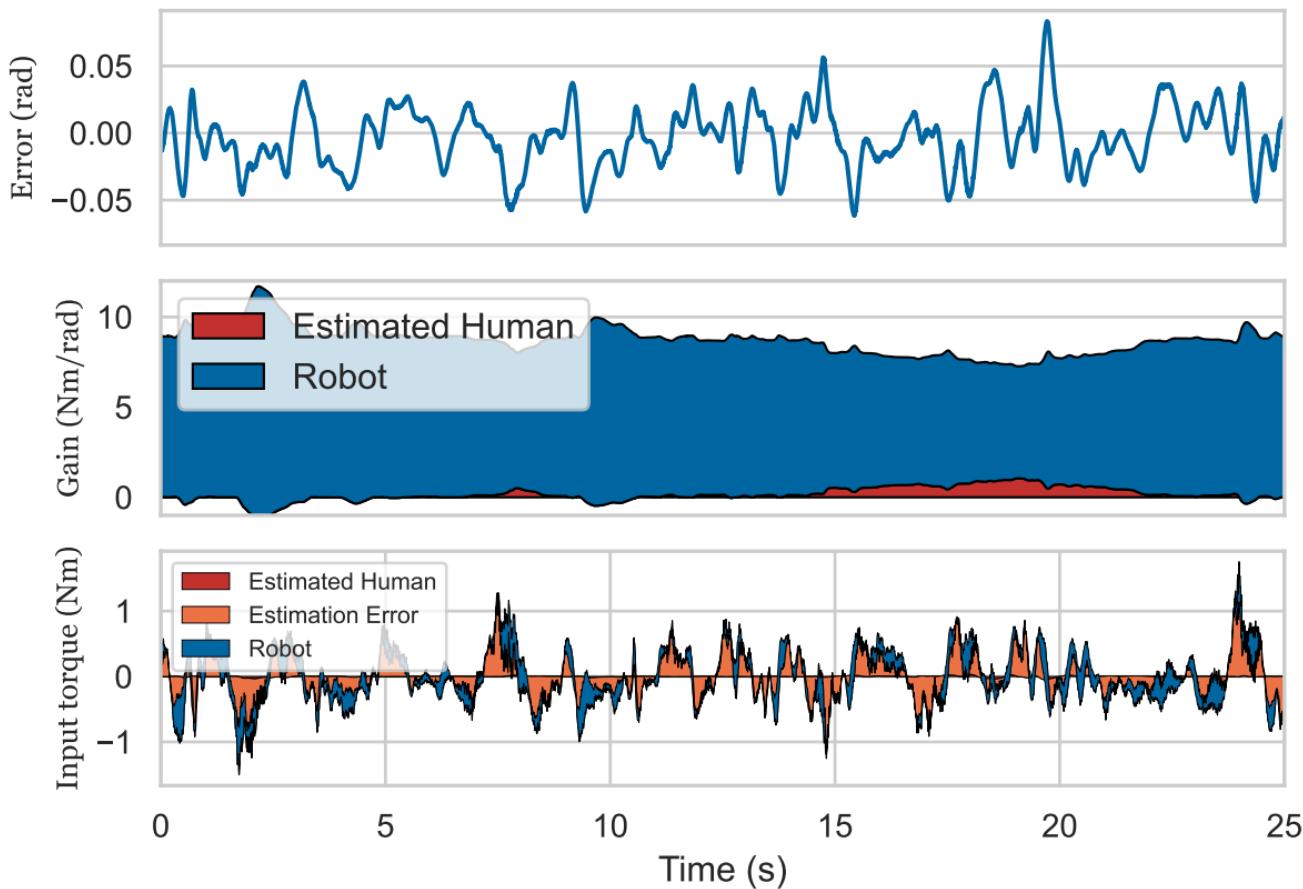


0 25 50 Time (s)

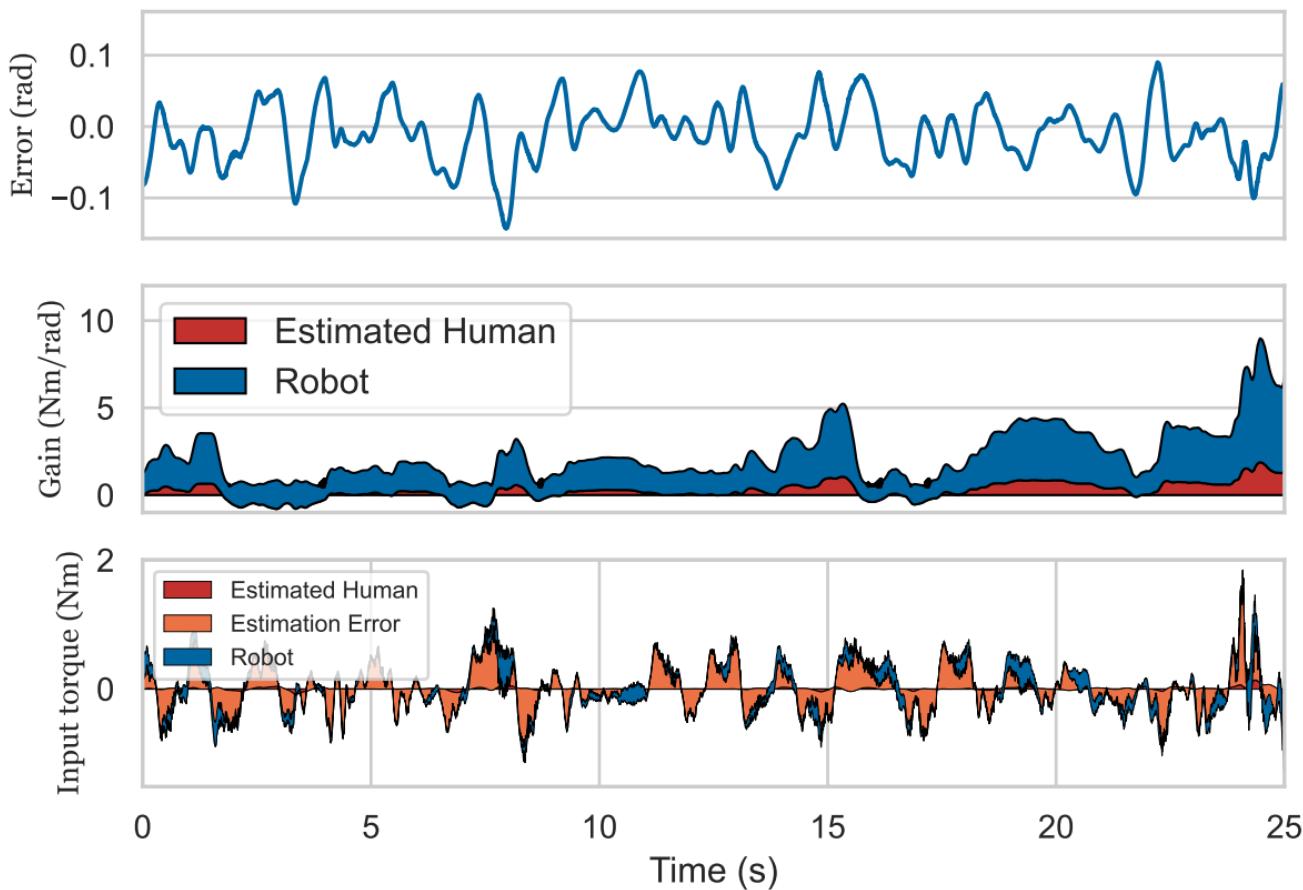
# Manual Control



# Negative Reinforcement



# Positive Reinforcement



# Mixed Reinforcement

