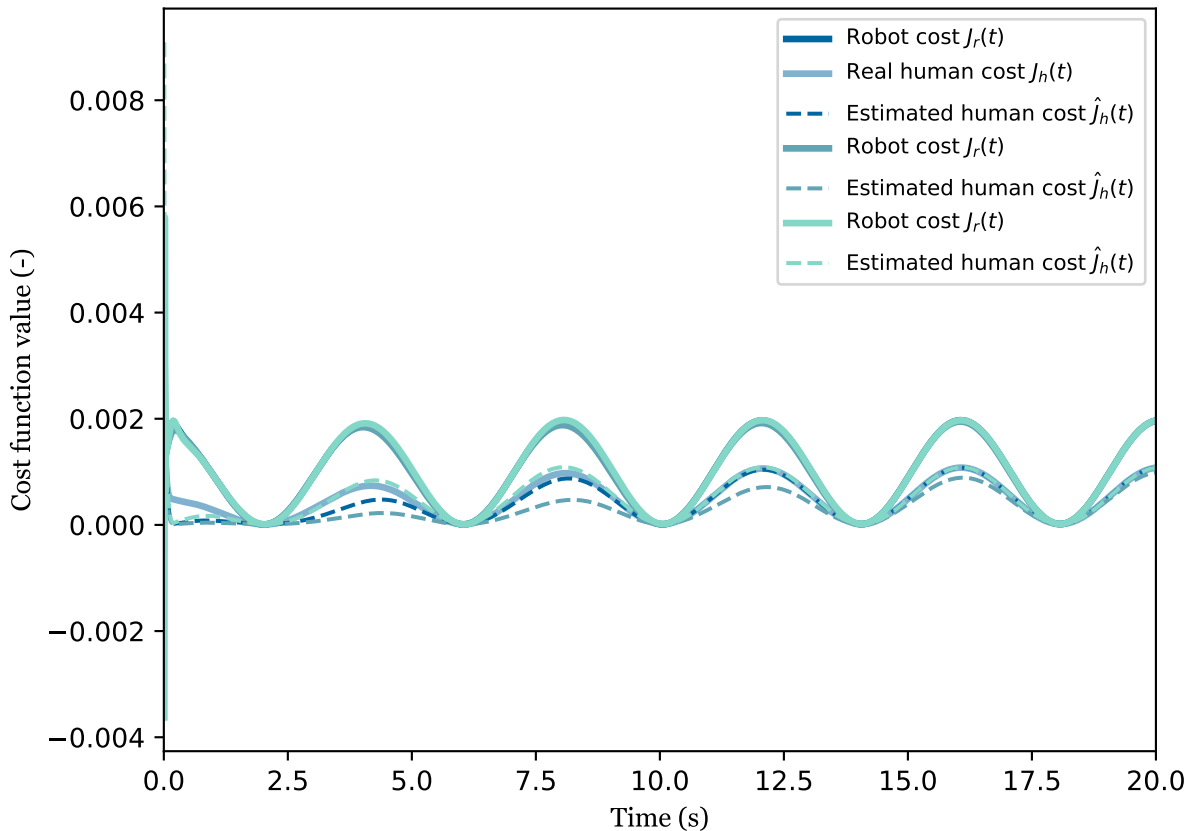
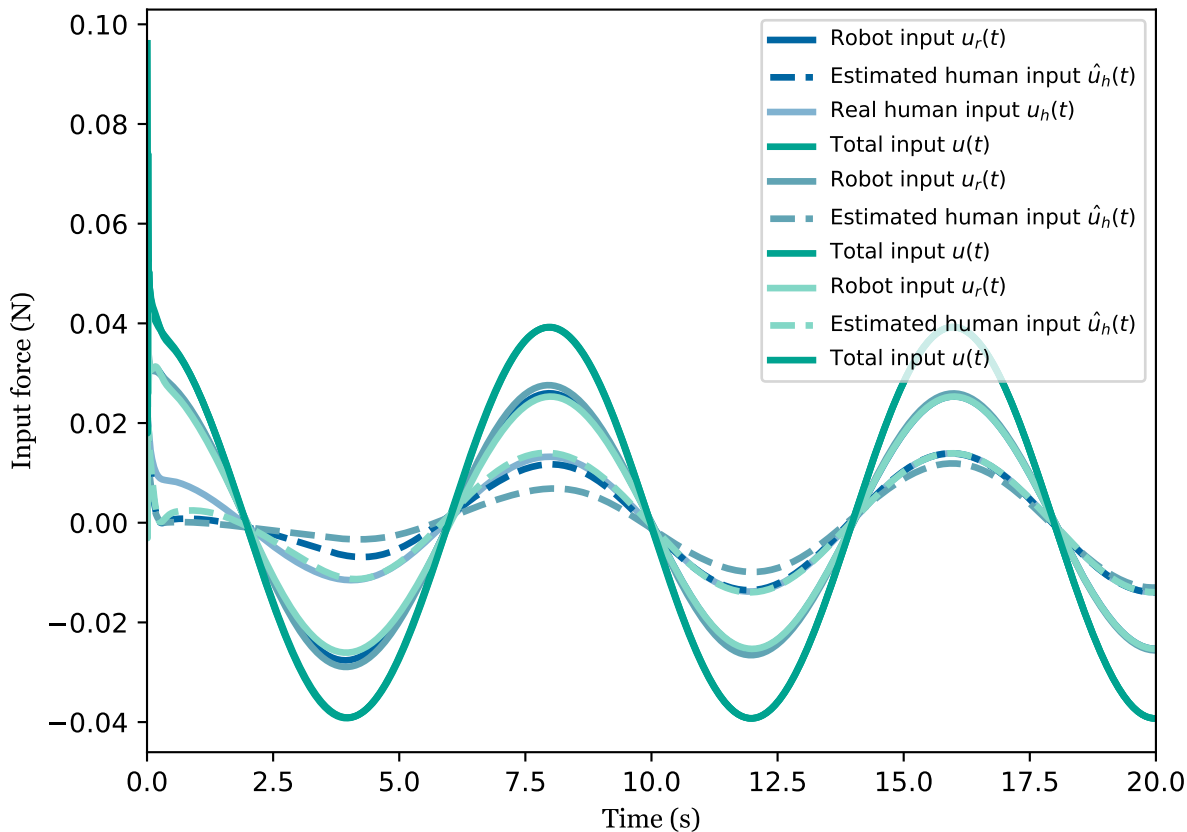


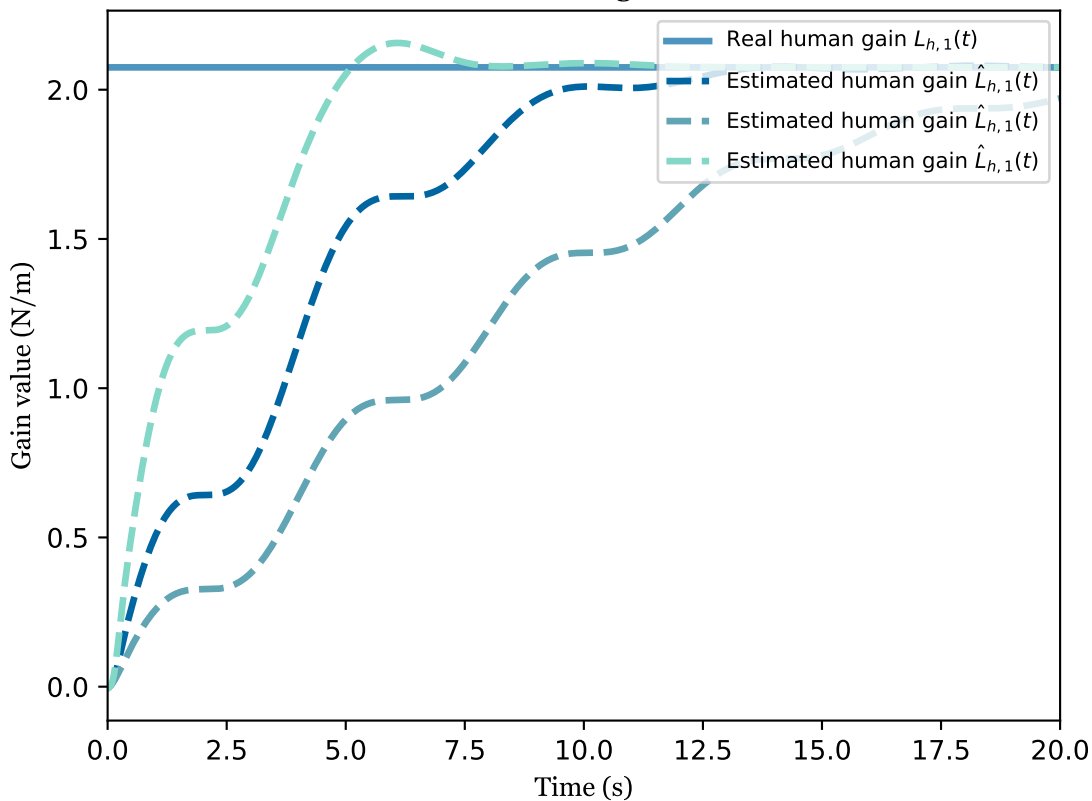
Cost function



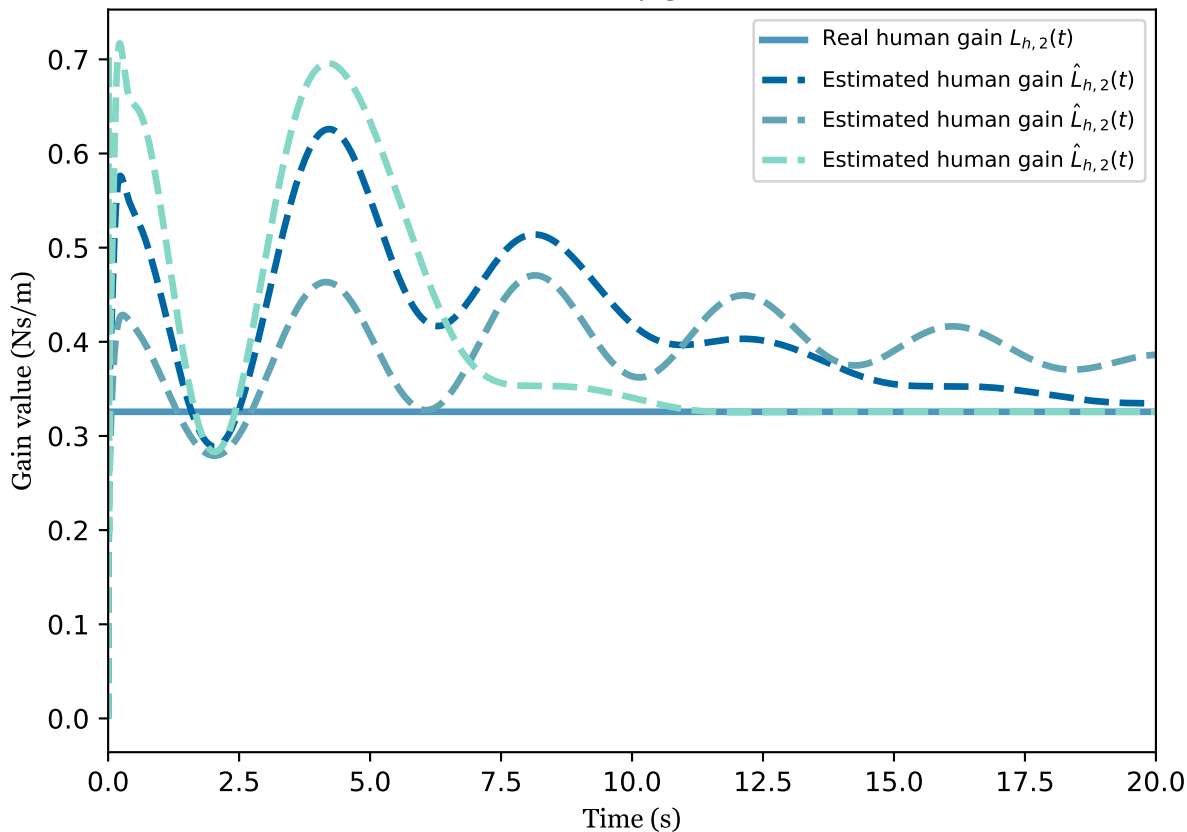
Control action



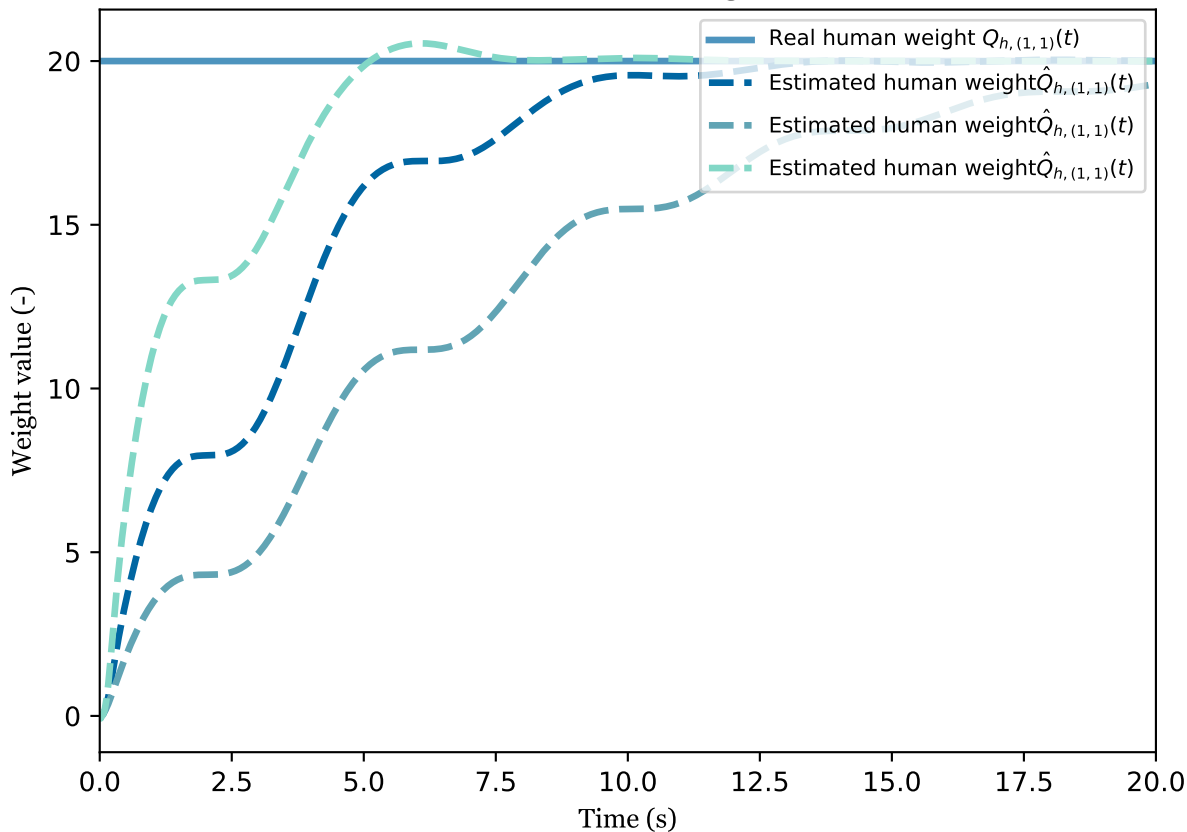
Position gain



Velocity gain



Position cost weight



Velocity cost weight

