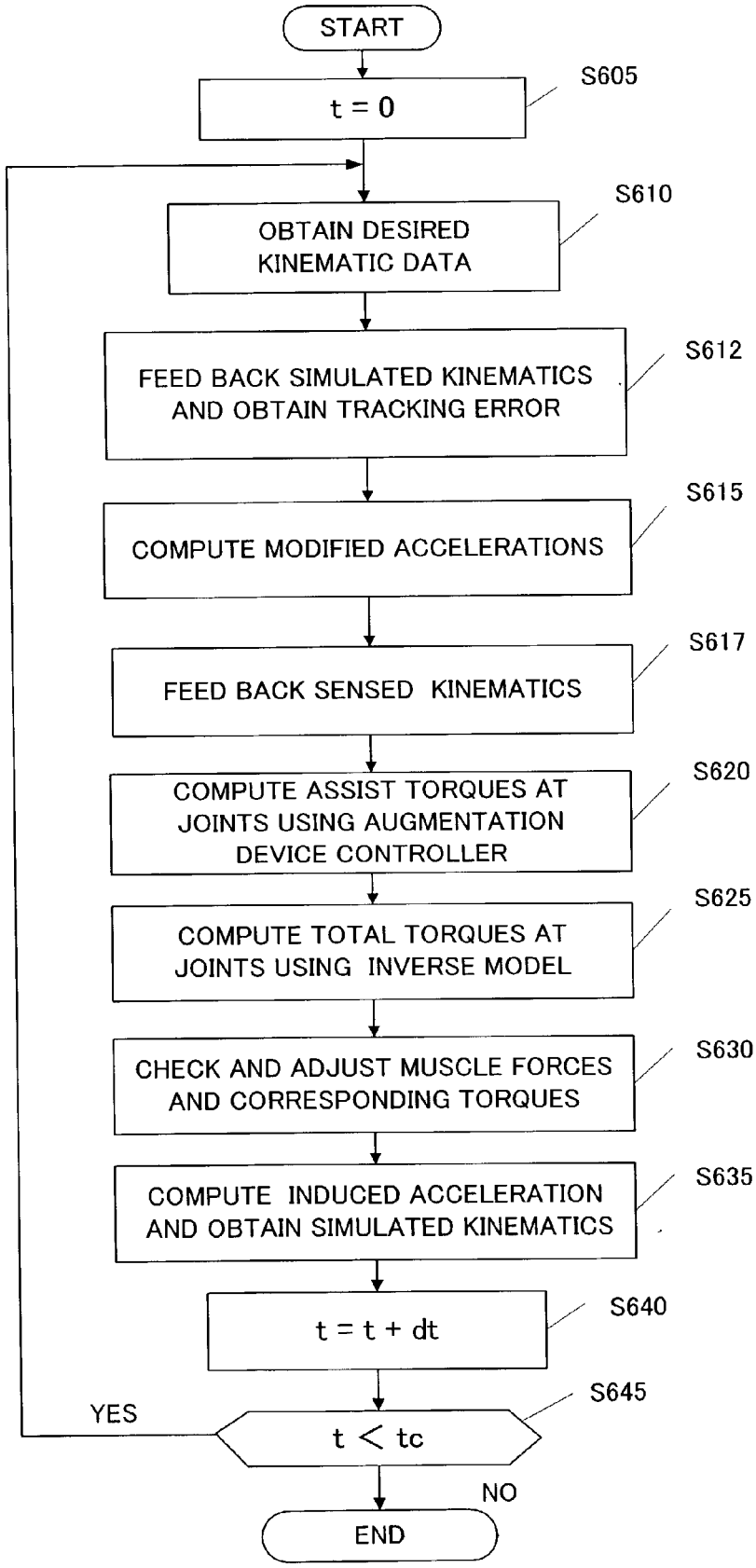
FIG. 6


START
t = 0
S605
OBTAIN DESIRED KINEMATIC DATA
S610
FEED BACK SIMULATED KINEMATICS AND OBTAIN TRACKING ERROR
S612
COMPUTE MODIFIED ACCELERATIONS
S615
FEED BACK SENSED KINEMATICS
S617
COMPUTE ASSIST TORQUES AT JOINTS USING AUGMENTATION DEVICE CONTROLLER
S620
COMPUTE TOTAL TORQUES AT JOINTS USING INVERSE MODEL
S625
CHECK AND ADJUST MUSCLE FORCES AND CORRESPONDING TORQUES
S630
COMPUTE INDUCED ACCELERATION AND OBTAIN SIMULATED KINEMATICS
S635
t = t + dt
S640
t < tc
S645
YES
NO
END