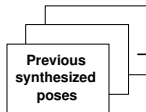
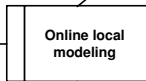




$[\mathbf{q}_1, \dots, \mathbf{q}_N]$

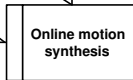


$[\tilde{\mathbf{q}}_1, \dots, \tilde{\mathbf{q}}_{t-1}]$

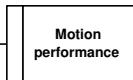


Human pose prior

Local linear model



$\tilde{\mathbf{q}}_t$



Low-dimensional control signals

$\tilde{\mathbf{c}}_t$

Control term

Root position and orientation

$\tilde{\mathbf{z}}_t$