

Desired gripper pose

Gripper pose and current readings

$e_{irp,g}$

$^c_x e_{irp,g}$

$^c_y e_{irp,g}$

Control subsystem buffers

Virtual Effector  
(fo suction gripper)

$^e e_{irp,g}$

Memory

Real effector buffers

$^E_y e_{irp,g}$

$^E_x e_{irp,g}$

Suction control

Encoders and current readings