

PathPlanner::get_continuity
_constraint_mat



```
graph LR; A[PathPlanner::get_continuity  
_constraint_mat] --> B[time_scaling_mat]; A --> C[t_vec]
```

The diagram illustrates a function call and its outputs. On the left, a gray rectangular box contains the text 'PathPlanner::get_continuity' followed by '_constraint_mat' on a new line. Two blue arrows originate from the right side of this box. The top arrow points to a white rectangular box containing the text 'time_scaling_mat'. The bottom arrow points to a white rectangular box containing the text 't_vec'.

time_scaling_mat

t_vec