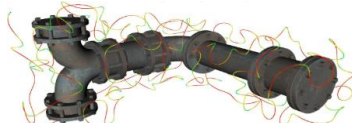


Offline

Coverage
path planner



list of
way points

Collision map
generation



HVBL0X

sdf map

Online

Entanglement-aware
path planner

$P_{tether}(t)$

Tether model

$p_{target}(t)$

MPC

$u(t)$

$x(t)$

