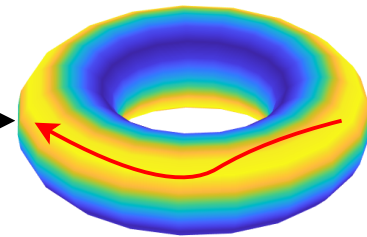
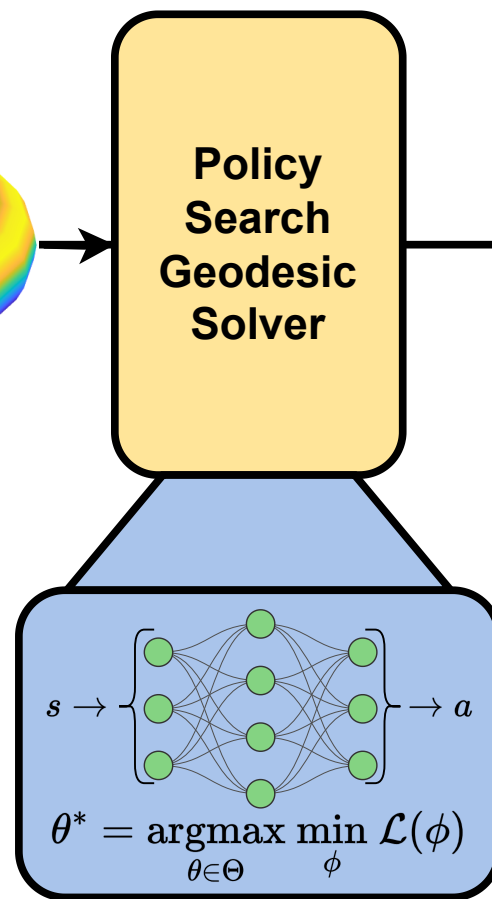
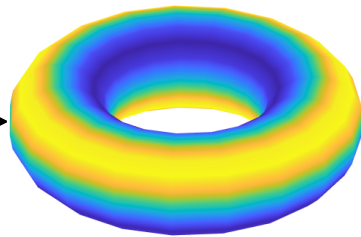
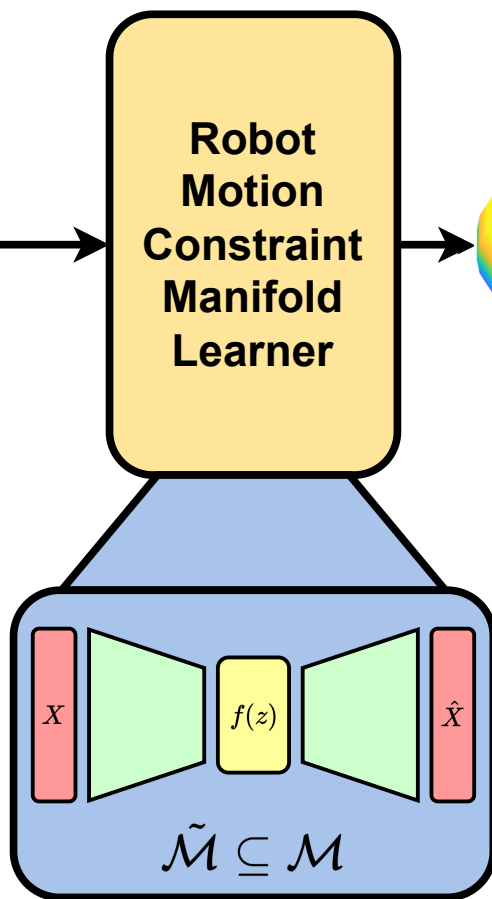


Robot kinematic
model \mathbf{T}_e^0

Task constraint
Information \mathbb{C}



Continuous
optimal
trajectory τ^*
that adheres to
on-manifold
constraints