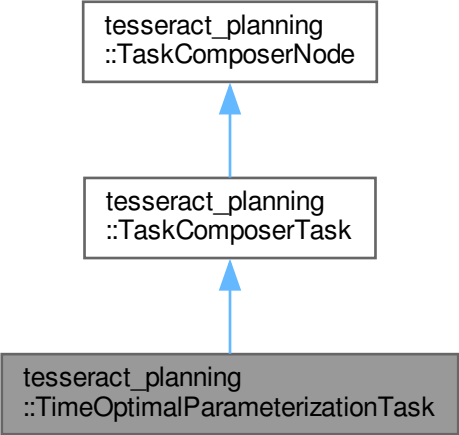


tesseract\_planning  
::TaskComposerNode



```
graph BT; A[tesseract_planning::TimeOptimalParameterizationTask] --> B[tesseract_planning::TaskComposerTask]; B --> C[tesseract_planning::TaskComposerNode];
```

tesseract\_planning  
::TaskComposerTask

tesseract\_planning  
::TimeOptimalParameterizationTask