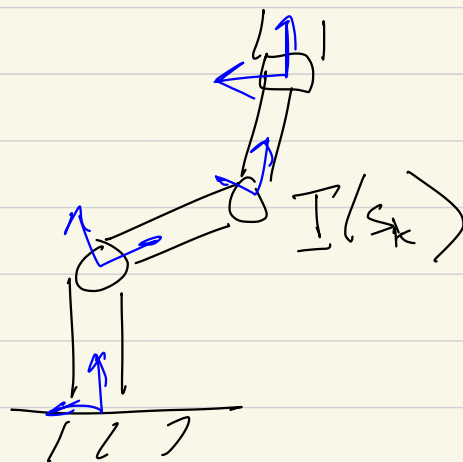
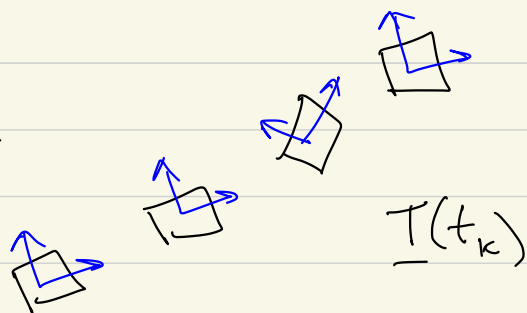


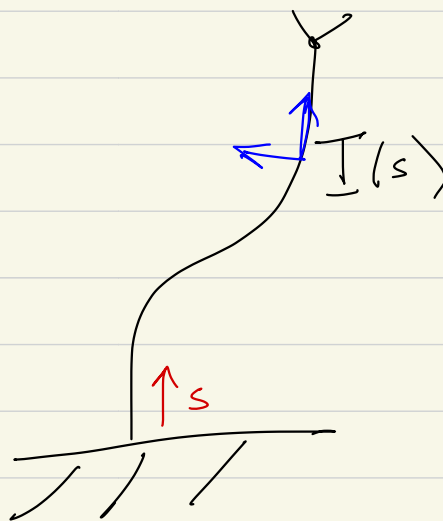
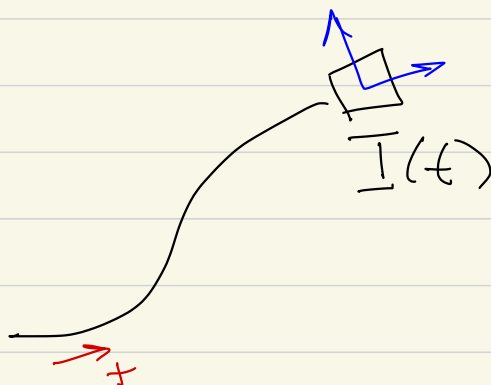
mobile
robot

manipulator

discrete



continuous

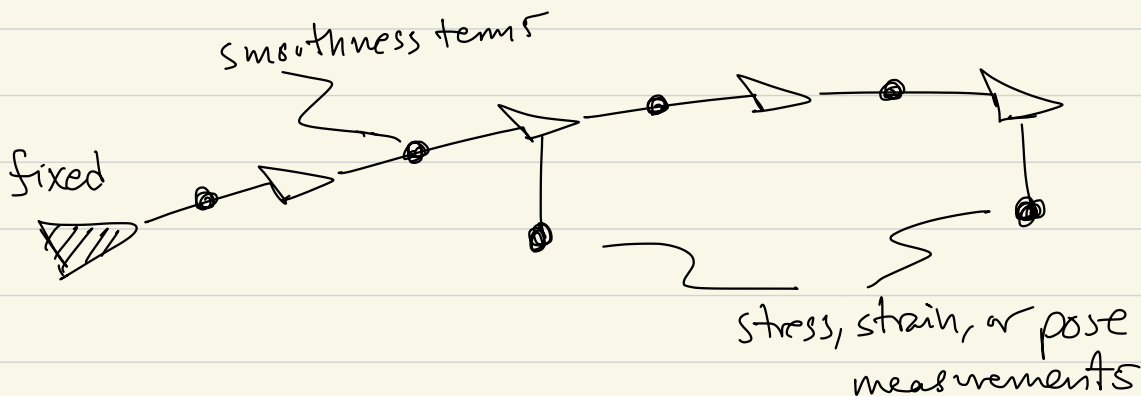


$$\frac{d}{dt} \underline{T} = \underline{\omega}^\wedge \underline{T}$$

$$\frac{d}{dt} \underline{\omega} = \underline{M}^{-1} \underline{\omega}^\wedge \underline{M} \underline{\omega} + \underline{f}$$

$$\frac{d}{ds} \underline{T} = \underline{\omega}^\wedge \underline{T}$$

$$\frac{d}{ds} \underline{\omega} = -\underline{K}^{-1} \underline{\omega}^\wedge \underline{K} \underline{\omega} + \underline{f}$$



prior + data = posterior

prior

