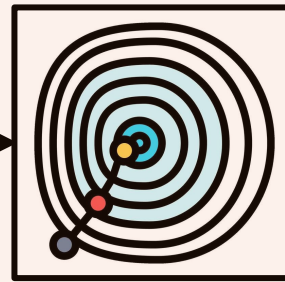


Model Learning

Motion Data
(e.g., Shape Evolution)

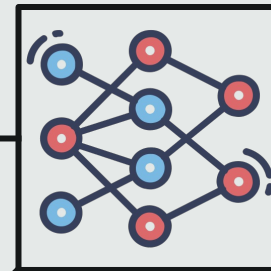
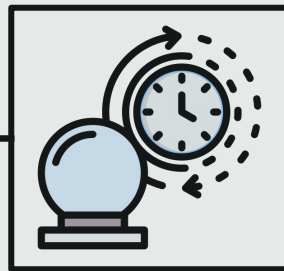


Model Optimization
(e.g., SGD)



Prediction
Error

Learned
Prediction Dynamical Model

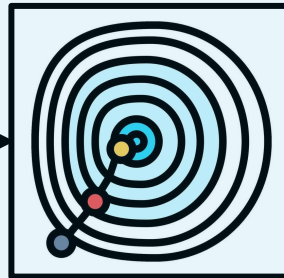


Predicted State Sequence
 $(q_k, \dot{q}_k) \forall k \in 1, \dots, H$

Reference



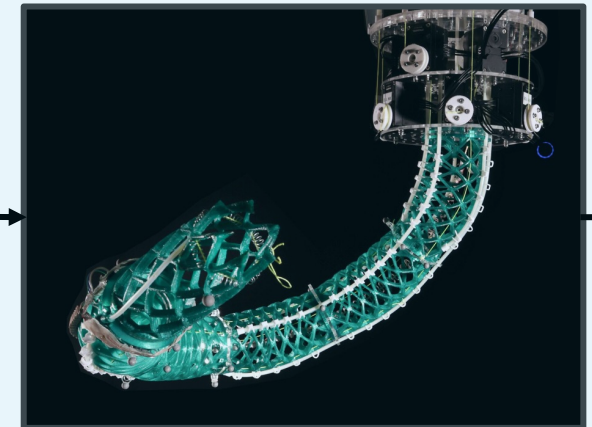
Control Optimization
(e.g., MPC)



Error

Actuation τ

Continuum Soft Robot



State Feedback (q, \dot{q})

Optimal Control