

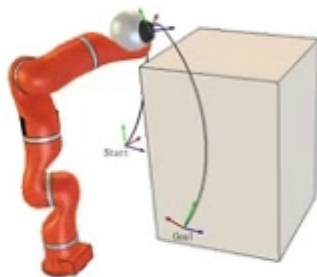
CONSTRAINTS

KINEMATIC

HOLONOMIC



INEQUALITY



MOTION EQUATION

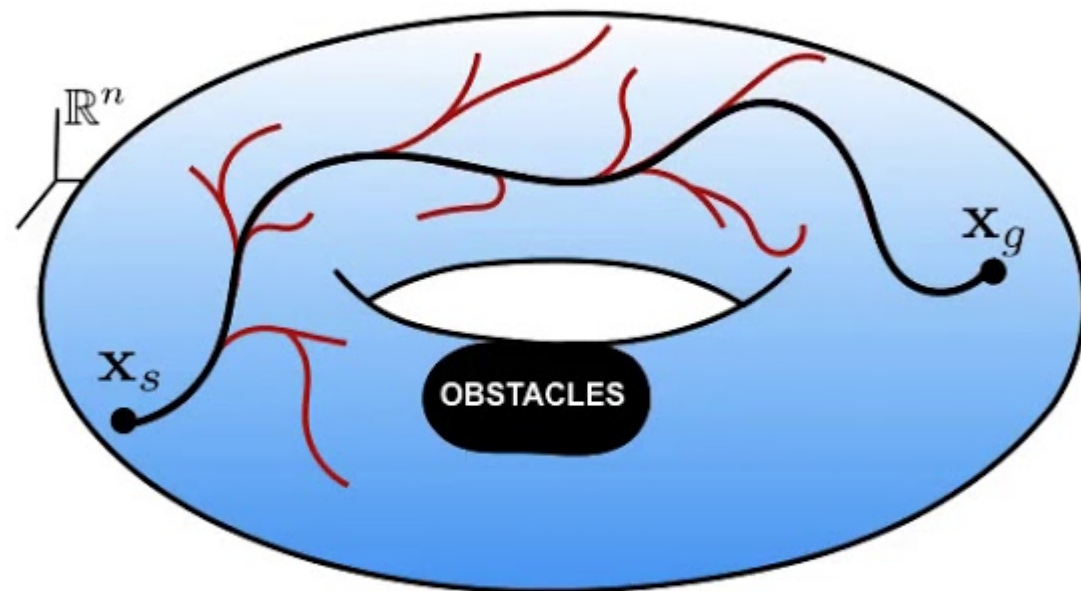


DYNAMIC

FORCE BOUNDS



dependent coordinates



kinodynamic RRT

