CONSTRAINTS

KINEMATIC

HOLONOMIC

INEQUALITY
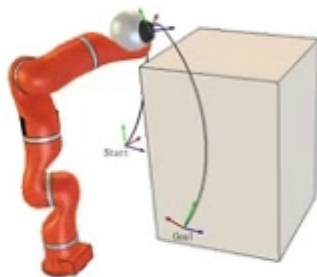
MOTION EQUATION
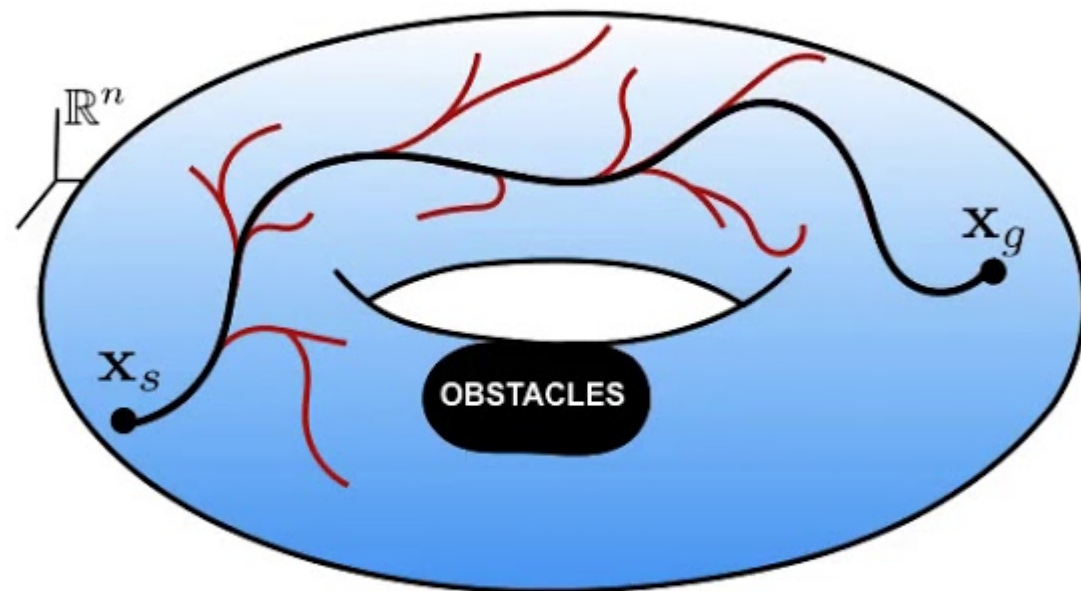
DYNAMIC

FORCE BOUNDS

$\mathbf{u}_i$

min   max

dependent coordinates

$\mathbb{R}^n$

$\mathbf{x}_g$

$\mathbf{x}_s$

OBSTACLES

kinodynamic RRT