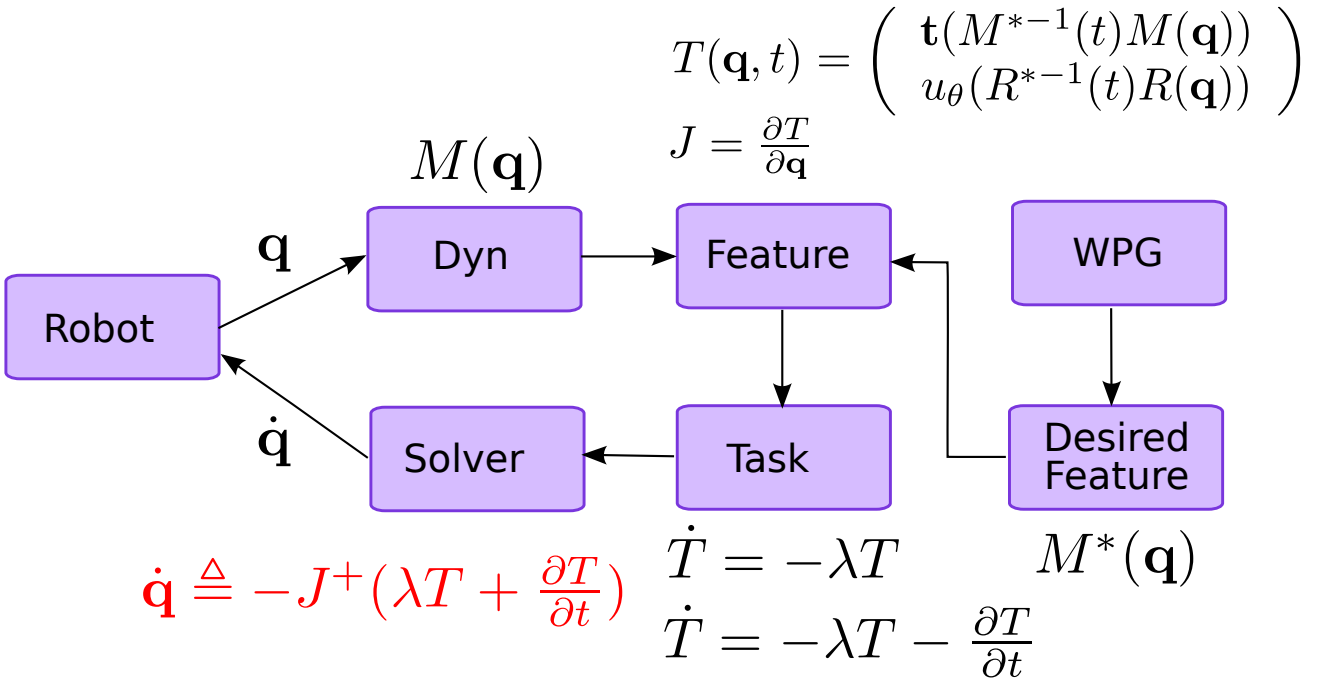
$T(\mathbf{q},t) = \begin{pmatrix} \mathbf{t}(M^{*-1}(t)M(\mathbf{q})) \\ u_\theta(R^{*-1}(t)R(\mathbf{q})) \end{pmatrix}$
$J = \frac{\partial T}{\partial \mathbf{q}}$
$M(\mathbf{q})$
$\mathbf{q}$
$\dot{\mathbf{q}}$
Robot
Dyn
Feature
WPG
Solver
Task
Desired Feature
$M^*(\mathbf{q})$
$\dot{T} = -\lambda T$
$\dot{T} = -\lambda T - \frac{\partial T}{\partial t}$
$\dot{\mathbf{q}} \triangleq -J^+(\lambda T + \frac{\partial T}{\partial t})$