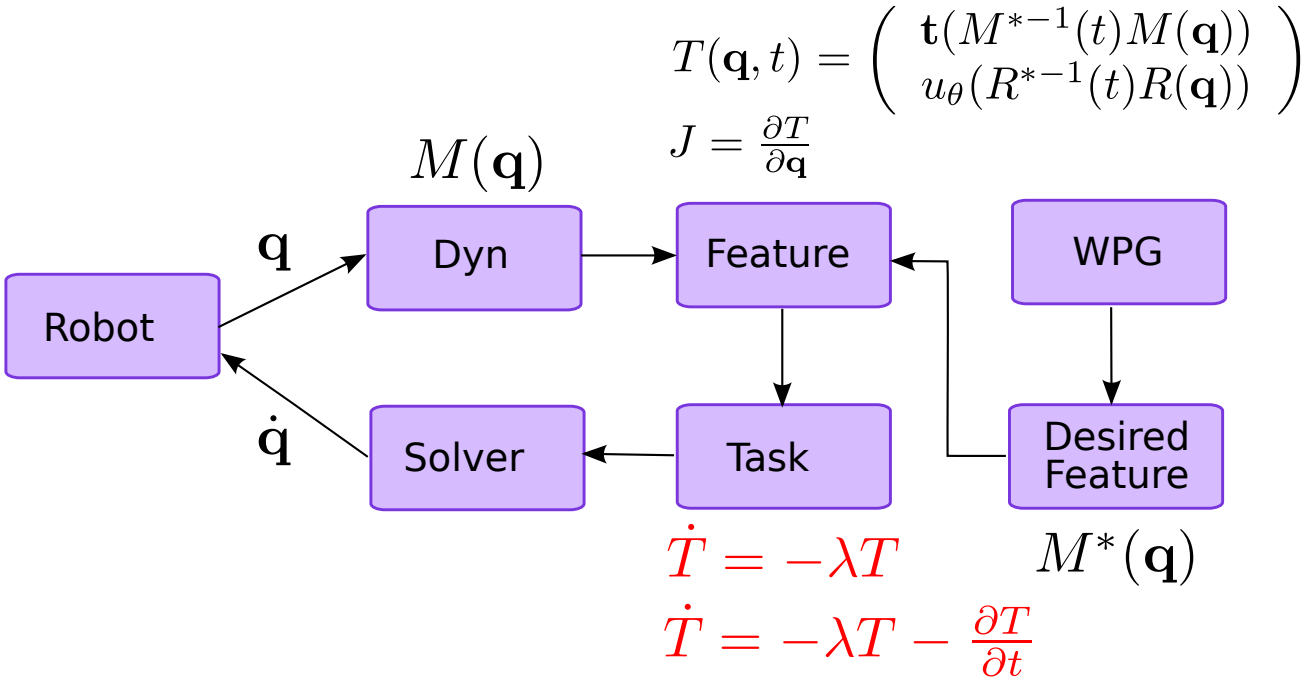
$T(\mathbf{q},t) = \begin{pmatrix} \mathbf{t}(M^{*-1}(t)M(\mathbf{q})) \\ u_\theta(R^{*-1}(t)R(\mathbf{q})) \end{pmatrix}$
$J = \frac{\partial T}{\partial \mathbf{q}}$
$M(\mathbf{q})$
$\mathbf{q}$
Dyn
Feature
WPG
Robot
$\dot{\mathbf{q}}$
Solver
Task
Desired Feature
$\dot{T} = -\lambda T$
$M^*(\mathbf{q})$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