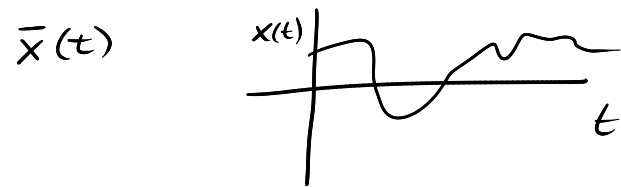


$$\dot{\bar{x}} = \bar{f}_m(\bar{x}(t), \bar{p}, t)$$

\uparrow \uparrow
 state parameter
 vector vector

$$\bar{x} = \begin{bmatrix} \bar{q} \\ \bar{u} \end{bmatrix}$$



trajectory

$$\bar{f}_m = -M_m^{-1} \bar{g}_m$$

\nwarrow \swarrow

$$\bar{X}(t) = \int_{t_0}^{t_f} \bar{f}_m(\bar{x}, \bar{p}, t) dt$$