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 $J = \partial_j \partial_{x_i} F = \frac{1}{2} \|J \cdot x - R\|_2^2 \nabla f = J^T J \cdot x - R = 0$
 $x_{min} = -J^{-1} J^T \cdot R$
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Law Makes Use Of The Desirable Property That A Pair
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...

568 IEEE TRANSACTIONS ON ROBOTICS AND
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Motivation For The Development Of Learning Control
Approach. Elaborating On This Idea, One Can Add That
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