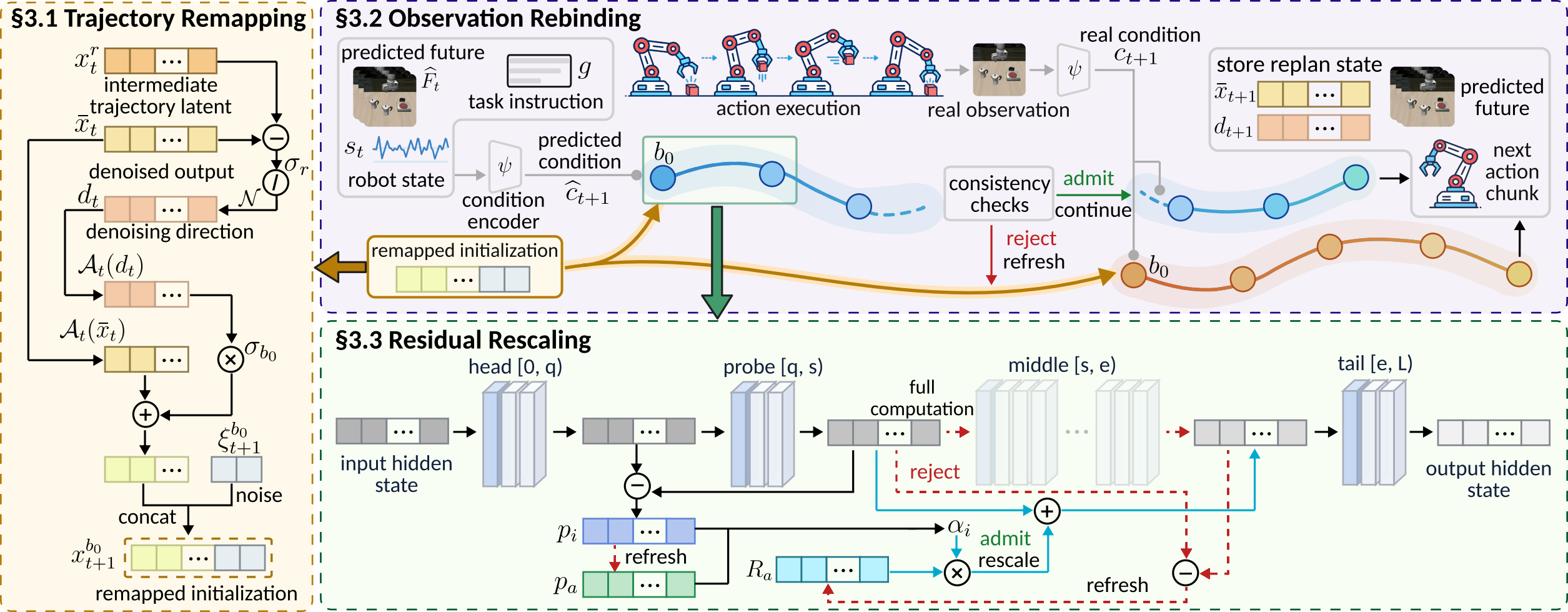

§3.1 Trajectory Remapping
intermediate trajectory latent
denoised output
denoising direction
noise
concat
remapped initialization
§3.2 Observation Rebinding
predicted future
task instruction
action execution
real observation
real condition
store replan state
predicted future
next action chunk
robot state
condition encoder
predicted condition
consistency checks
admit
continue
reject
refresh
remapped initialization
§3.3 Residual Rescaling
head [0, q)
probe [q, s)
full computation
middle [s, e)
tail [e, L)
input hidden state
output hidden state
reject
refresh
admit
rescale
refresh