Benchmark OptimalControl Results

Model	Discretization	Iterations	Total Time	Ipopt Time	Objective Value	Flag
cart_pendulum	100	237	6.12214	2.026	1.74413	Solve_Succeeded
cart_pendulum	500	495	11.9102	11.522	1.74373	Solve_Succeeded
robot	100	75	1.91878	0.411	9.14269	Solve_Succeeded
robot	500	649	22.4402	21.154	9.14099	Solve_Succeeded
electrical_vehicle	100	16	2.08206	0.183	1.22905e6	Solve_Succeeded
electrical_vehicle	500	1000	13.3213	13.187	231779.0	Maximum_Iterations_Exceeded
double_oscillator	100	5	1.2394	0.098	0.000908244	Solve_Succeeded
double_oscillator	500	5	0.384104	0.096	0.000910921	Solve_Succeeded
ducted_fan	100	162	2.73244	1.198	1832.95	Solve_Succeeded
ducted_fan	500	163	161.063	158.598	1831.66	Solve_Succeeded
steering	100	11	0.466564	0.044	0.554595	Solve_Succeeded
steering	500	17	0.420257	0.19	0.554572	Solve_Succeeded
glider	100	230	4.57505	2.992	1254.61	Solve_Succeeded
glider	500	755	1244.69	1244.01	1247.98	Solve_Succeeded
rocket	100	21	1.9544	0.266	1.01283	Solve_Succeeded
rocket	500	77	22.8172	21.647	1.01284	Solve_Succeeded
chain	100	7	1.28504	0.13	5.06978	Solve_Succeeded
chain	500	14	0.826377	0.432	5.06858	Solve_Succeeded
dielectrophoretic_particle	100	38	2.54432	0.386	-9.97699e-9	Infeasible_Problem_Detected
dielectrophoretic_particle	500	38	6.08859	5.63	-9.99545e-9	Infeasible_Problem_Detected