

Benchmark models with JuMP and OptimalControl
max iter = 1000, tol = 1.0e-8, constr viol tol = 1.0e-6, solver = ma57

Solver	Model	Discretization	Variables	Constraints	Iterations	Total Time	Ipopt Time	Objective Value	Flag
robot	JuMP	100	910	612	18	2.75	2.75	9.14269	Solve Succeeded
robot	JuMP	400	3610	2412	20	0.22	0.21	9.14103	Solve Succeeded
robot	OptimalControl	100	910	612	20	1.73	0.1	9.142	Solve Succeeded
robot	OptimalControl	400	3610	2412	49	15.11	14.74	9.14099	Solve Succeeded
rocket	JuMP	100	405	304	19	0.03	0.03	1.01283	Solve Succeeded
rocket	JuMP	400	1605	1204	40	0.24	0.24	1.01284	Solve Succeeded
rocket	OptimalControl	100	405	304	22	0.1	0.05	1.01283	Solve Succeeded
rocket	OptimalControl	400	1605	1204	30	1.18	1.03	1.01284	Solve Succeeded
glider	JuMP	100	506	407	223	3.09	3.09	1254.61	Solve Succeeded
glider	JuMP	400	2006	1607	497	73.81	73.74	1247.97	Solve Succeeded
glider	OptimalControl	100	506	407	169	2.87	0.69	1254.78	Solve Succeeded
glider	OptimalControl	400	2006	1607	1000	21.99	21.83	107.51	Iterations Exceeded
electrical_vehicle	JuMP	100	303	204	5	0.1	0.01	1.24629e8	Solve Succeeded
electrical_vehicle	JuMP	400	1203	804	5	0.02	0.02	4.93167e8	Solve Succeeded
electrical_vehicle	OptimalControl	100	404	305	21	2.87	0.26	1.22906e6	Solve Succeeded
electrical_vehicle	OptimalControl	400	1604	1205	17	0.9	0.73	1.22861e6	Solve Succeeded