

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
rocket	JuMP	100	405	304	19	0.03	0.03	1.01283	Solve Succeeded
rocket	JuMP	400	1605	1204	40	0.31	0.29	1.01284	Solve Succeeded
rocket	OptimalControl	100	405	304	22	0.32	0.24	1.01283	Solve Succeeded
rocket	OptimalControl	400	1605	1204	30	7.1	6.11	1.01284	Solve Succeeded
glider	JuMP	100	506	407	223	4.69	4.66	1254.61	Solve Succeeded
glider	JuMP	400	2006	1607	497	113.09	113.05	1247.97	Solve Succeeded
glider	OptimalControl	100	506	407	126	2.93	0.64	1254.78	Solve Succeeded
glider	OptimalControl	400	2006	1607	1000	49.84	49.25	106.778	Iterations Exceeded