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

Model	Discretization	Total Time JuMP	Total Time OC
robot	100	0.04	0.14
robot	400	0.19	15.92
rocket	100	0.04	0.13
rocket	400	0.26	1.09
glider	100	3.08	0.68
glider	400	81.6	20.8
electrical_vehicle	100	0.01	0.2
electrical_vehicle	400	0.04	0.89