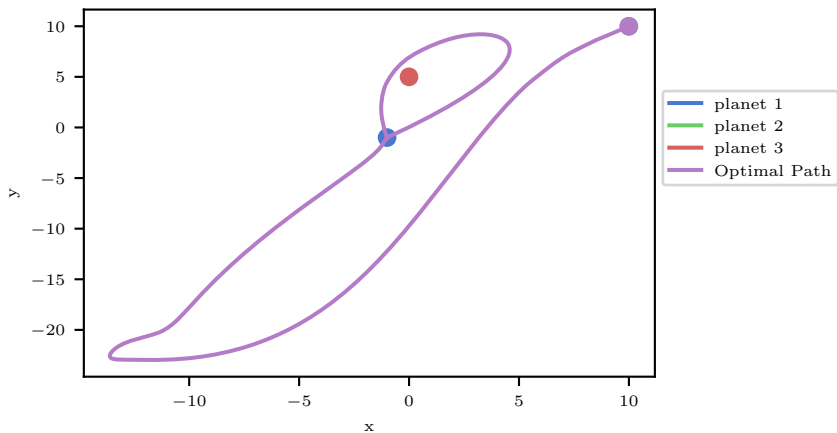


Optimal Path



Optimal Control

