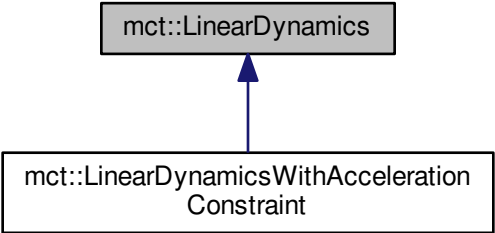


mct::LinearDynamics



```
graph BT; A[mct::LinearDynamicsWithAccelerationConstraint] --> B[mct::LinearDynamics]
```

mct::LinearDynamicsWithAcceleration
Constraint