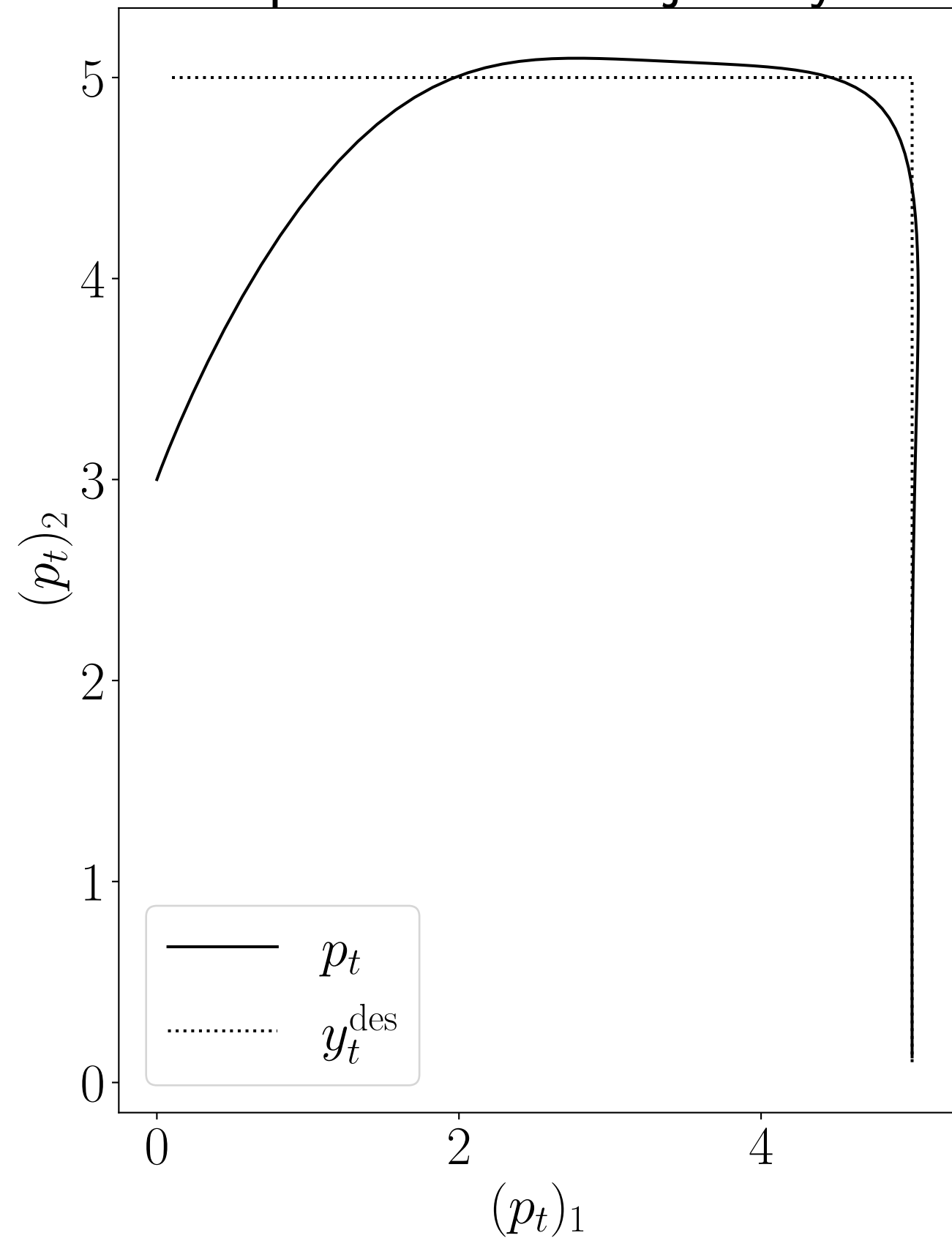


optimal state trajectory



optimal input trajectory

