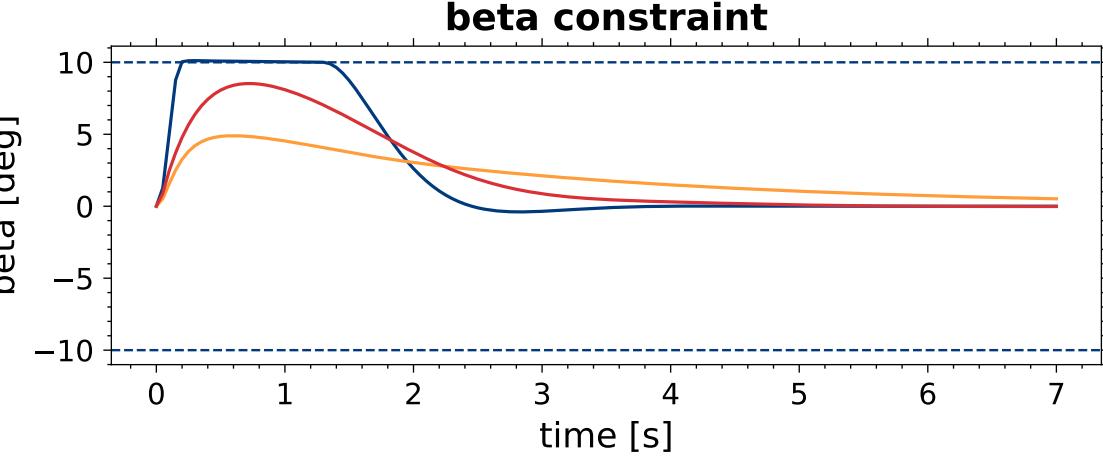
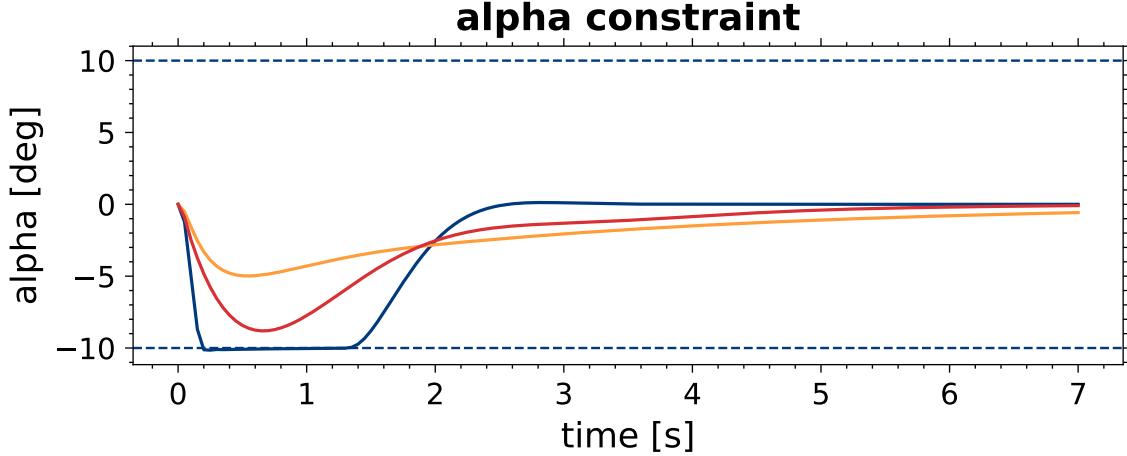
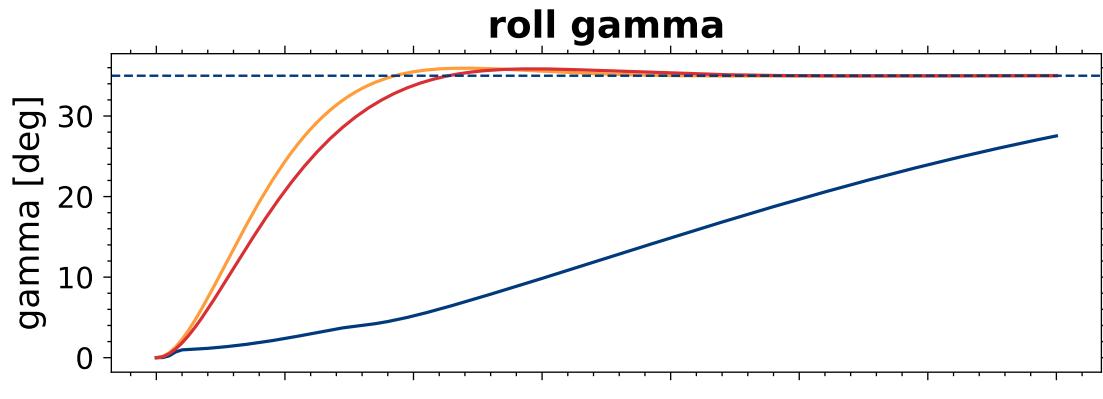
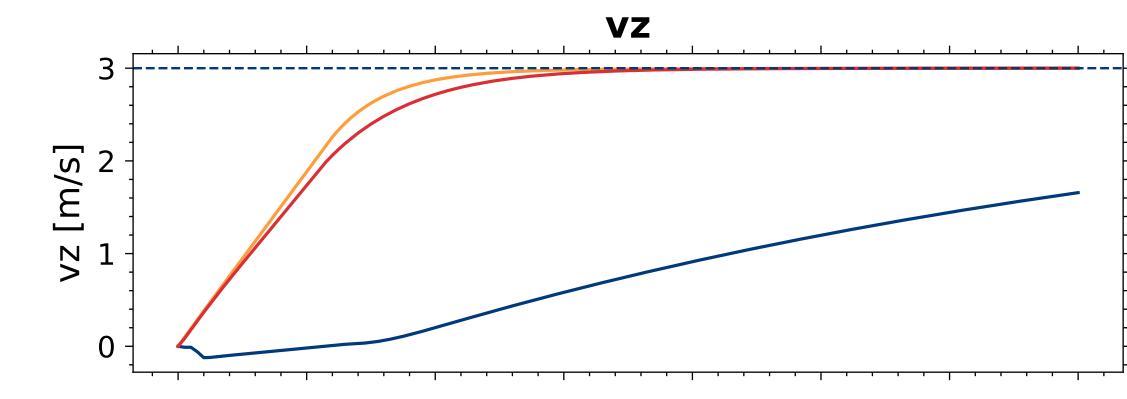
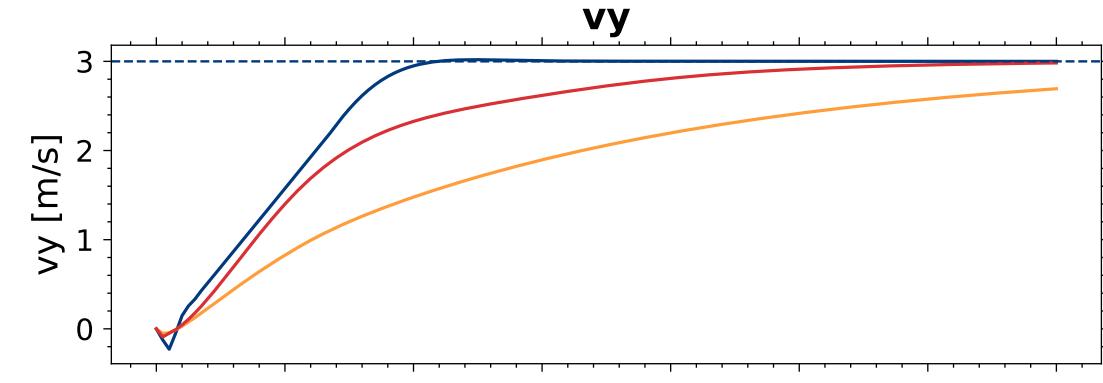
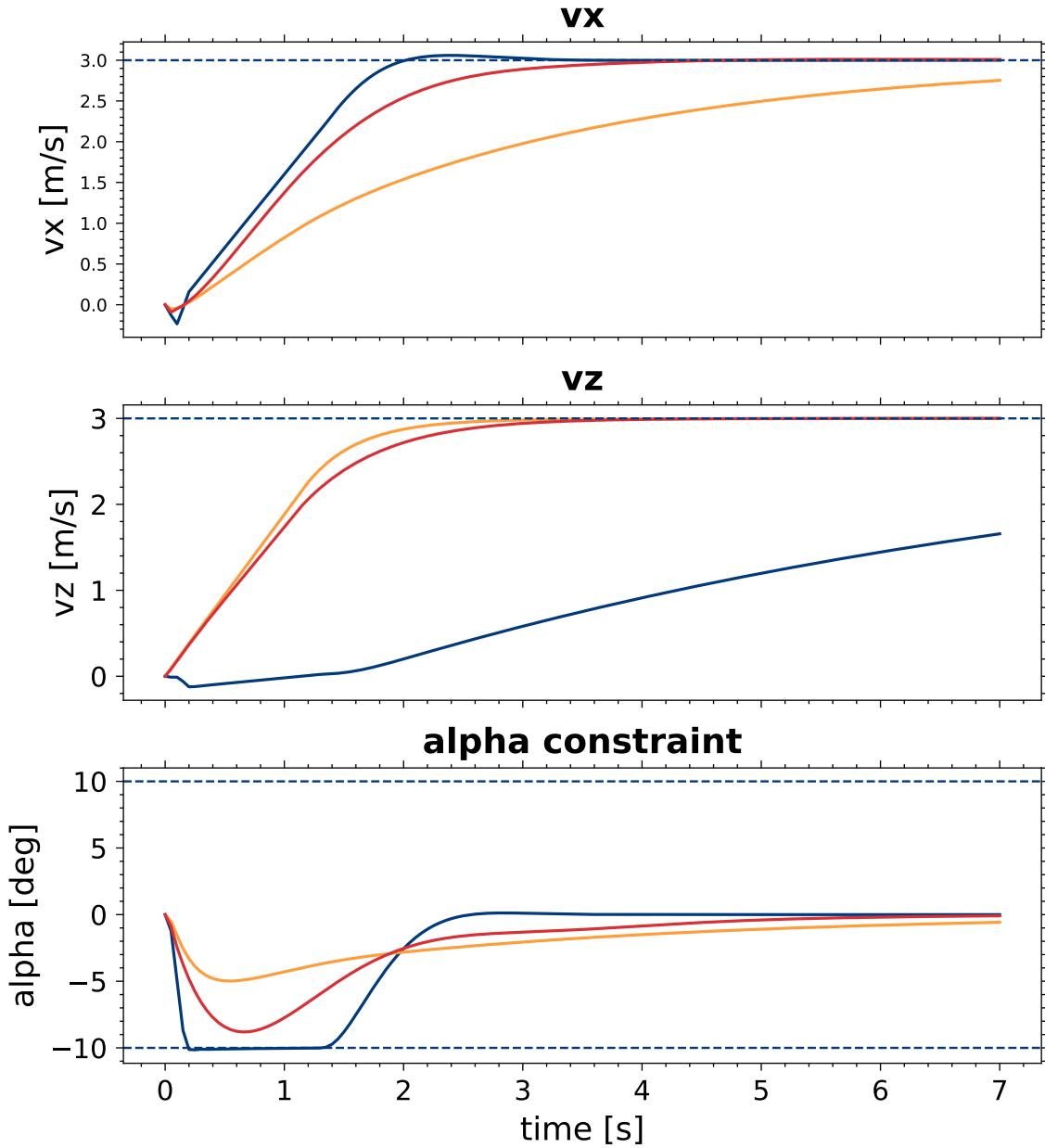


Closed-loop MPC tracking + angle constraints



— Identity $Q = I, R = I$	— Final tuned
— Heuristic $Q_{ii} = 1/x_{i,\max}^2, R_{ii} = 1/u_{i,\max}^2$	