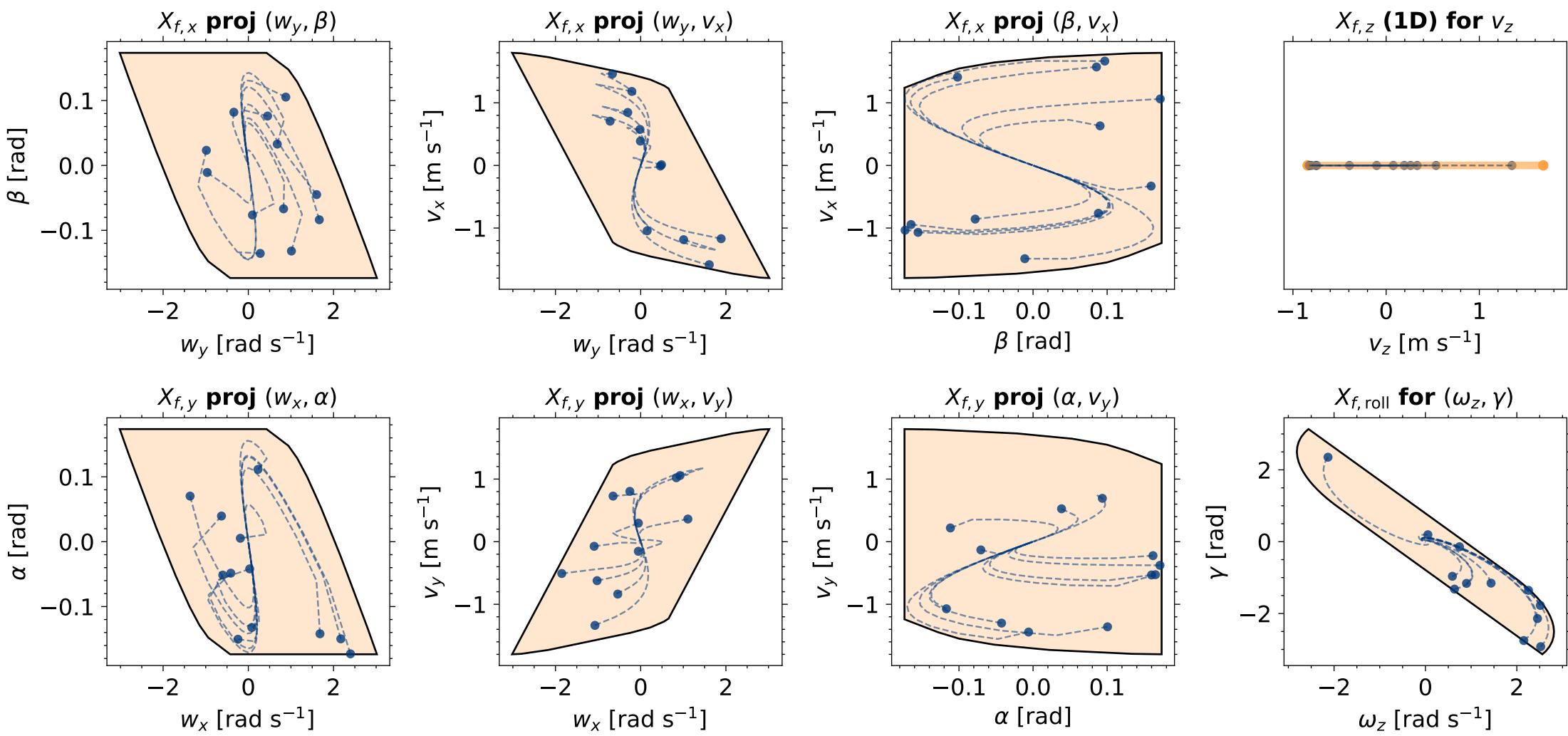


Terminal invariant sets X_f for each MPC subsystem with closed-loop trajectories



----- traj ($\Delta x_0 \in X_f$)