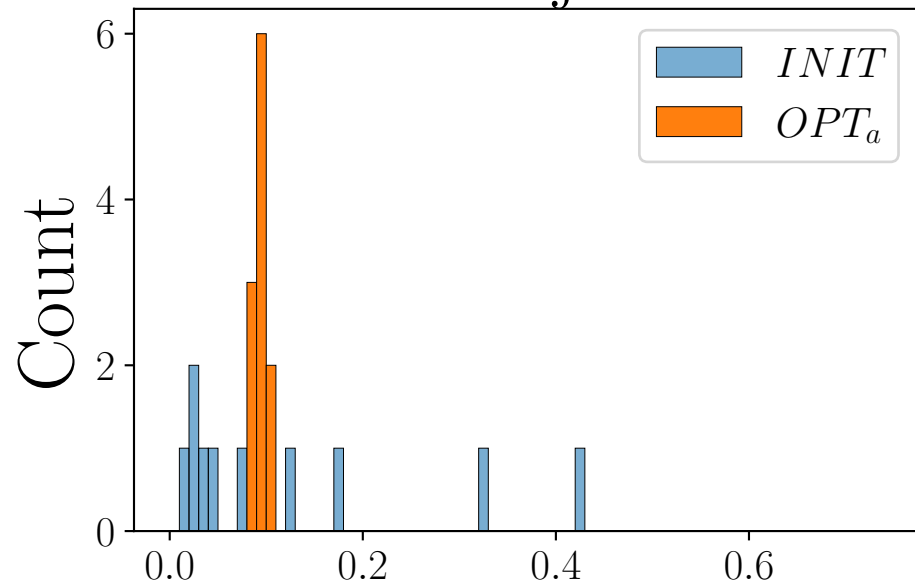
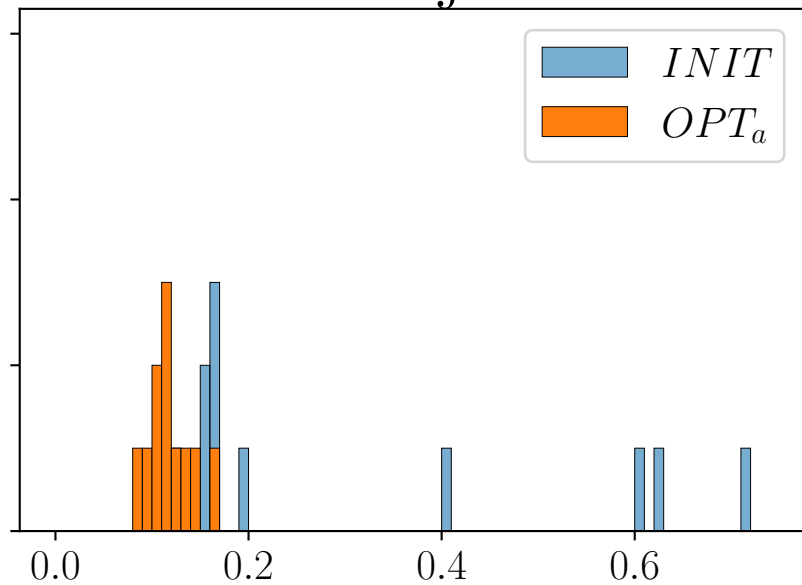


Traj1 Gazebo



Gazebo

Traj2

Distance to the desired target  $r_d(t_w)$