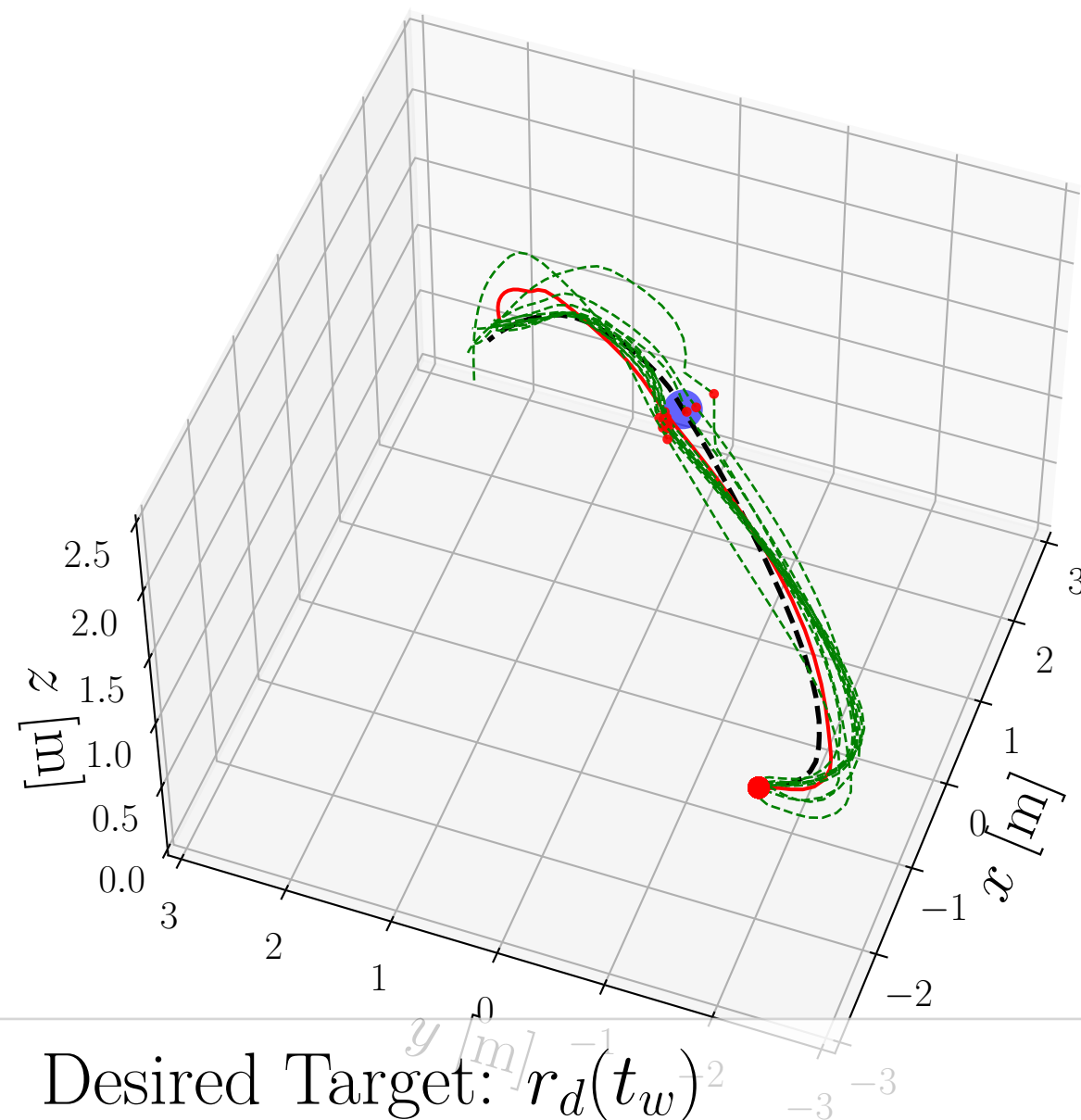
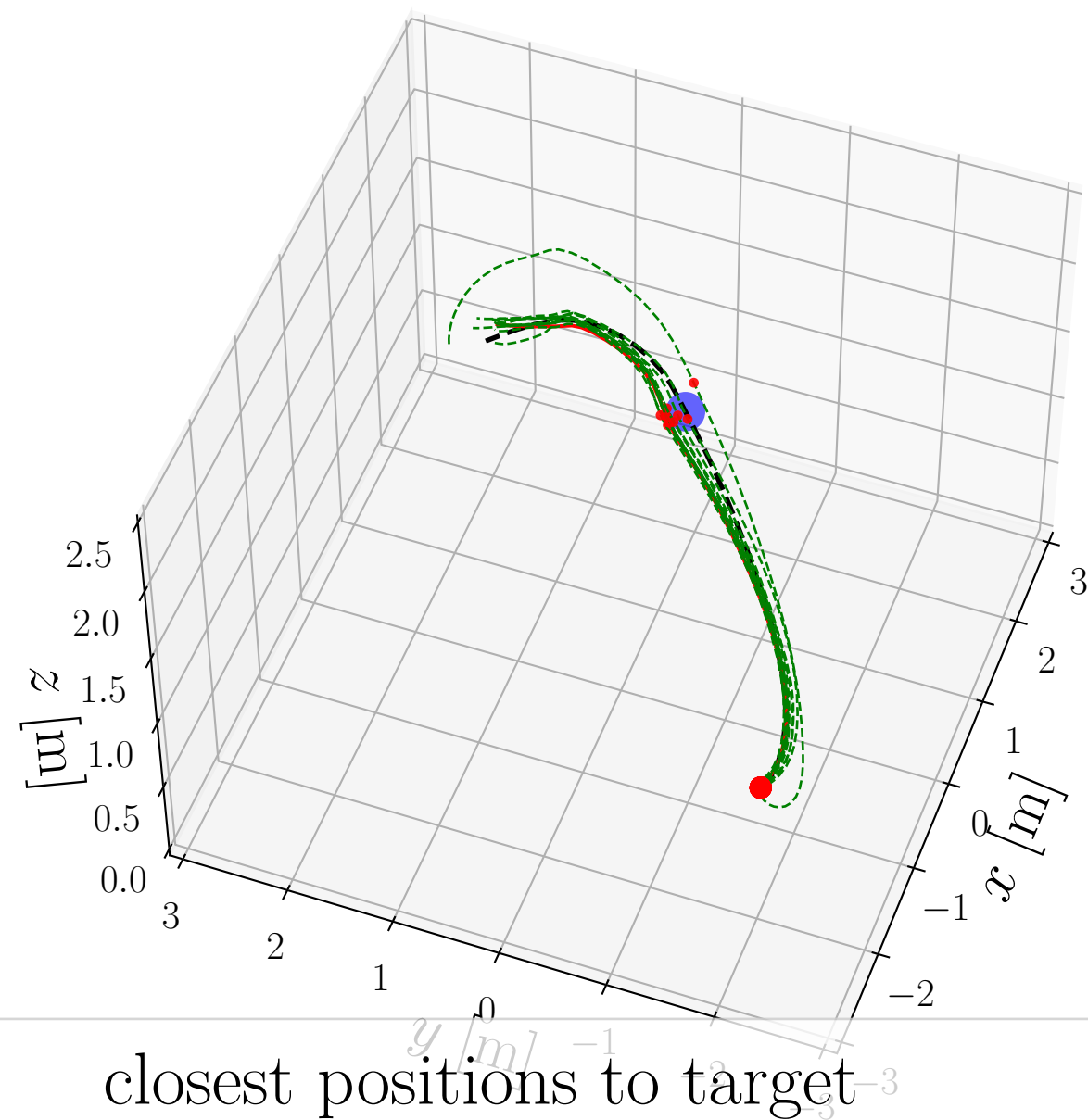


INIT



OPT_a



- Desired Target: $r_d(t_w)$
- Reference Trajectory
- Nominal Controller tracking
- closest positions to target
- $p \neq p_c$ Controller tracking with perturbation