

No operator cost internalization, operator safety subsidy

$$(x_1, x_2, x_3)|_{t=0} = (0.8, 0.2, 0.7)$$

$$(f_1, f_2, f_3, f_u, c_1, c_2, c_3) = (2, 0, -0.1, 0, 0.5, 0.4, 0.1)$$

