

o TrajectoryProblem

- ✗ setTimeBounds($t_{\theta Low}$, $t_{\theta Upp}$, t_{FLow} , t_{FUpp})
- ✗ setStateBounds(x_{Low} , x_{Upp})
- ✗ setControlBounds(u_{Low} , u_{Upp})
- ✗ setScaling(type, factors)
- ✗ setConstraints(hBoundary, hPath)
- ✗ setParameters(parameters)