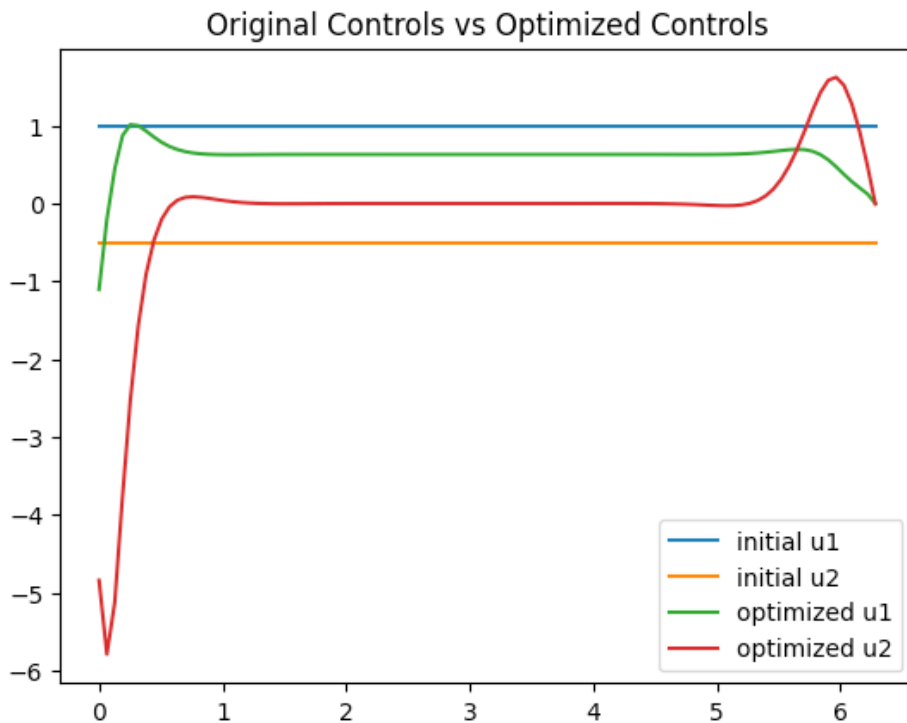
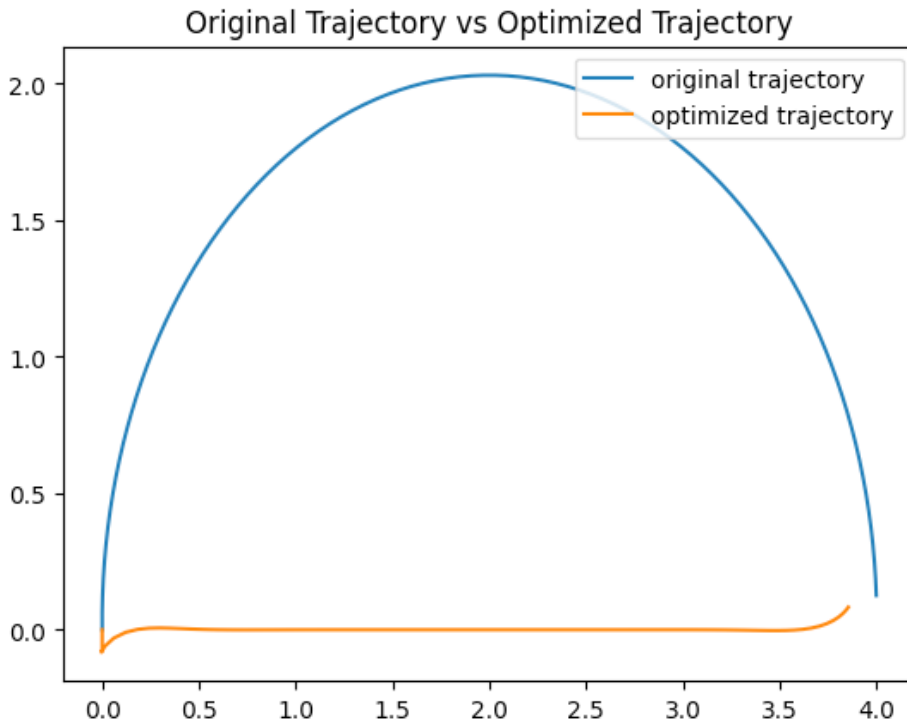


Ian Shi
ME 455 HW 2

Below are plots of the initial trajectory and optimized trajectory, as well as the original and optimized control signs.



Additionally, the table below shows the printed $DJ(\xi) \cdot \zeta$ values, illustrating how the decrease with each iteration.

```
1394.7021855728776
470.385062081771
78.22676934234055
39.49028513638771
2.6633407515093097
1.1644501992367169
0.6129789224268578
0.222965937358589
0.22118298615691973
0.1885252522305469
0.1844141717151828
0.17654633351344112
0.17589678318044916
0.18186557028123007
0.06019921017559801
0.10401204250215446
0.03322427006786262
0.06660110756681356
0.021718018883373585
0.04350796446174673
0.045189691764634166
0.014705180200720014
0.03158345003634036
0.010079597717197361
0.022487816347146496
...
0.0017771587083719623
0.003984342596287648
0.0012570140250658735
0.0027970711654899567
```