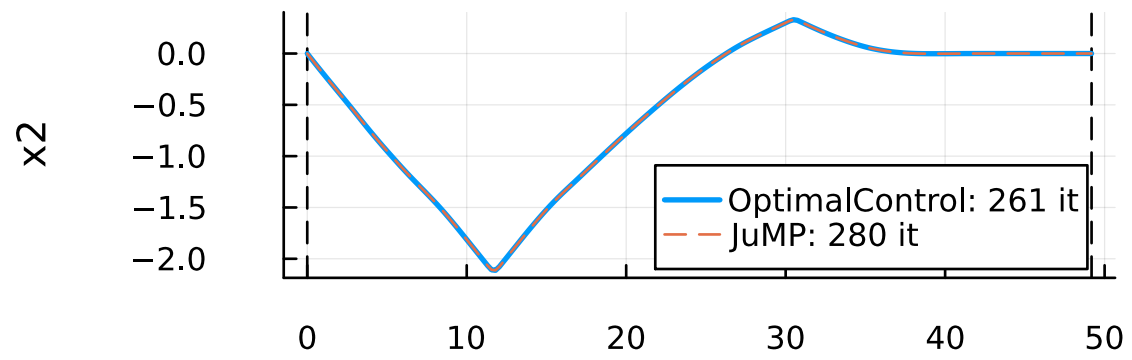
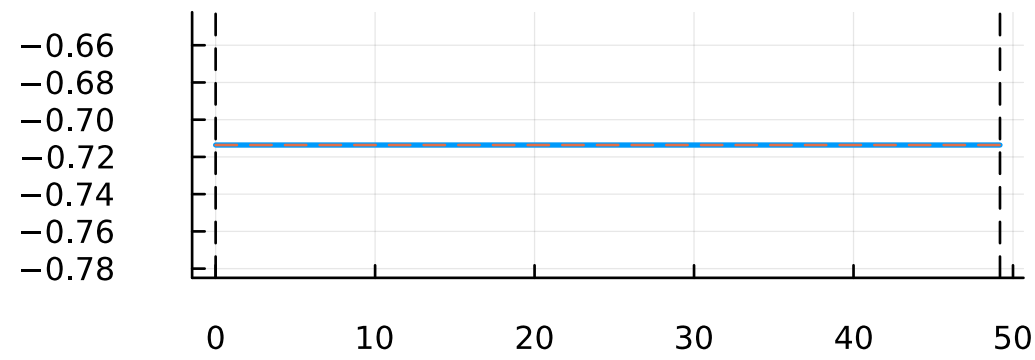


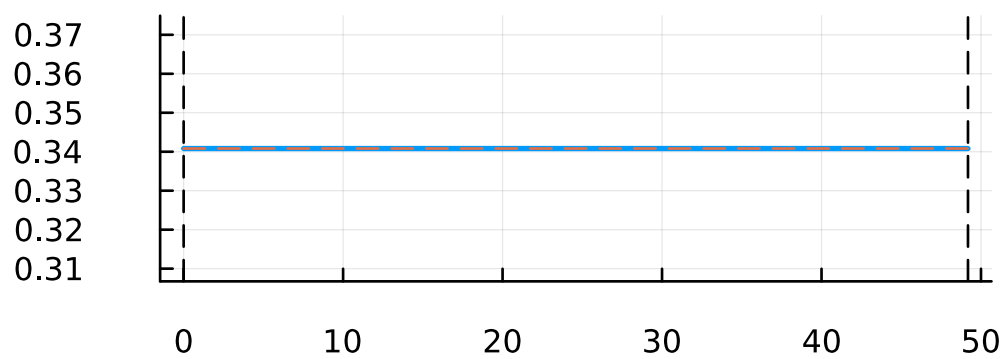
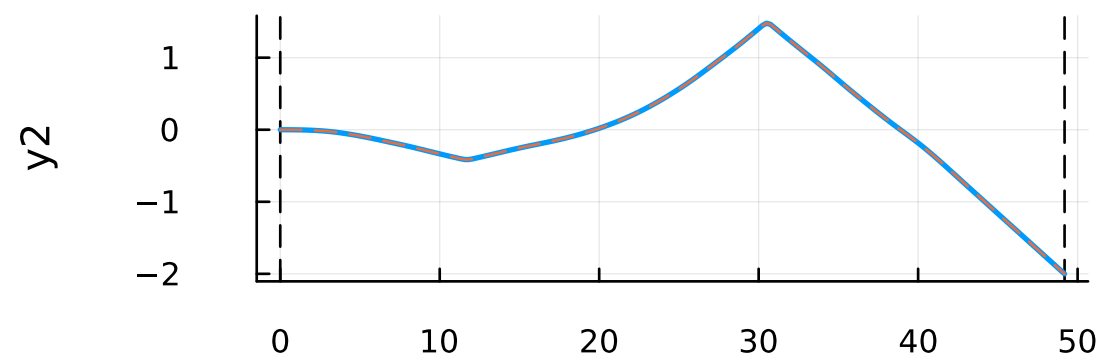
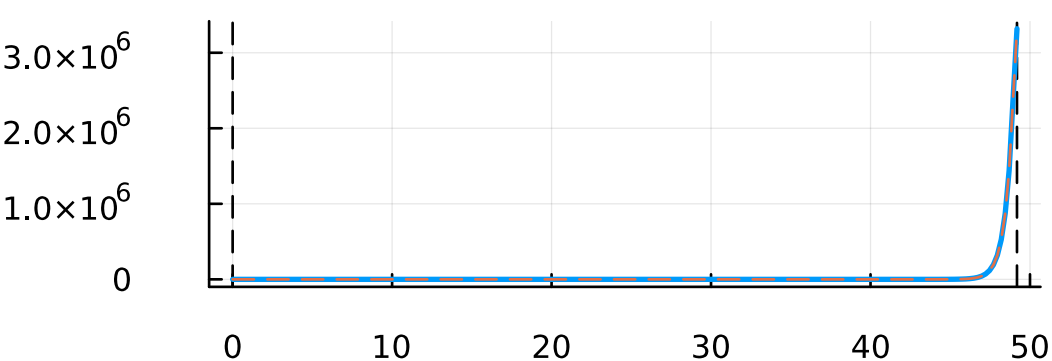
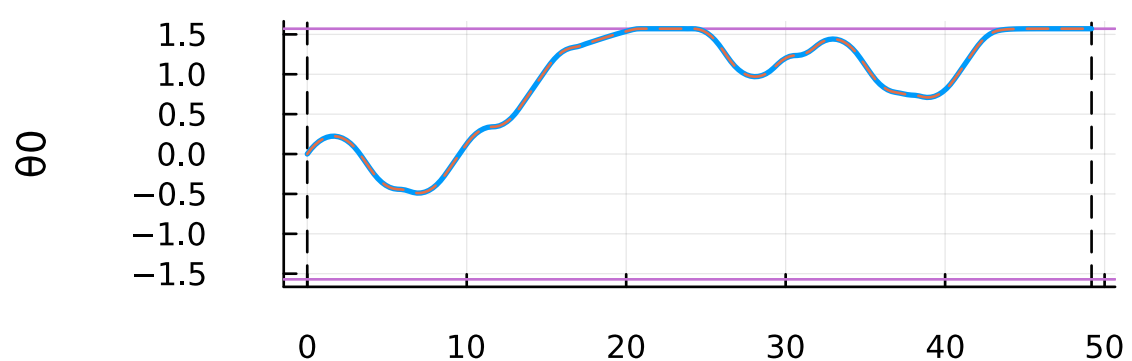
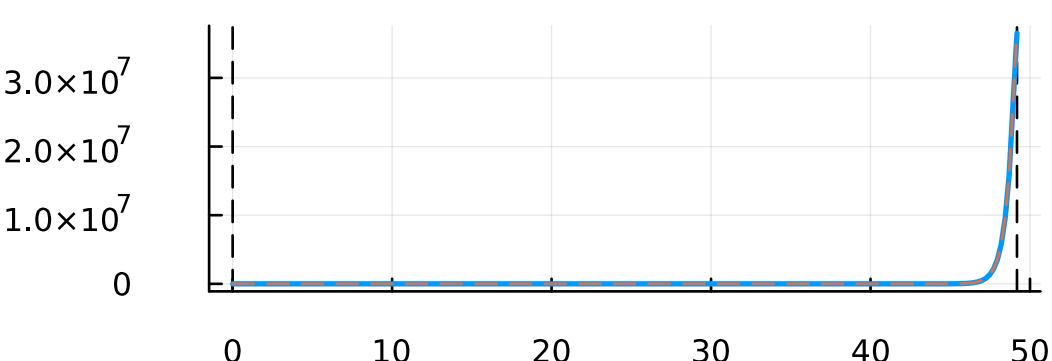
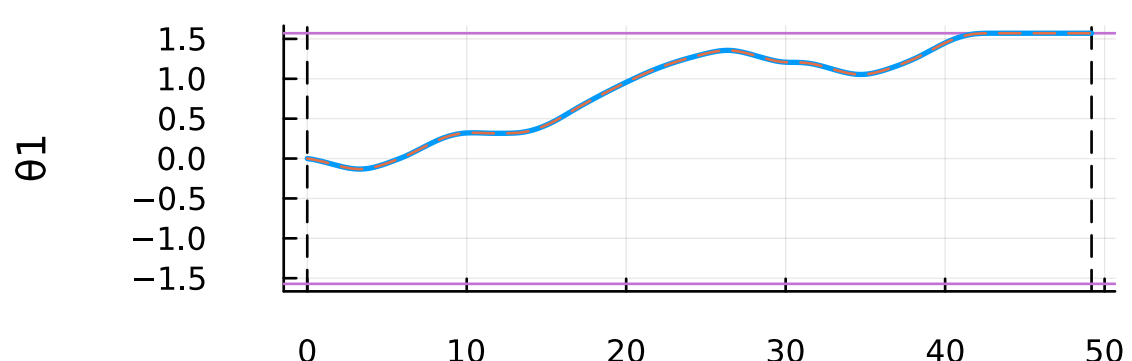
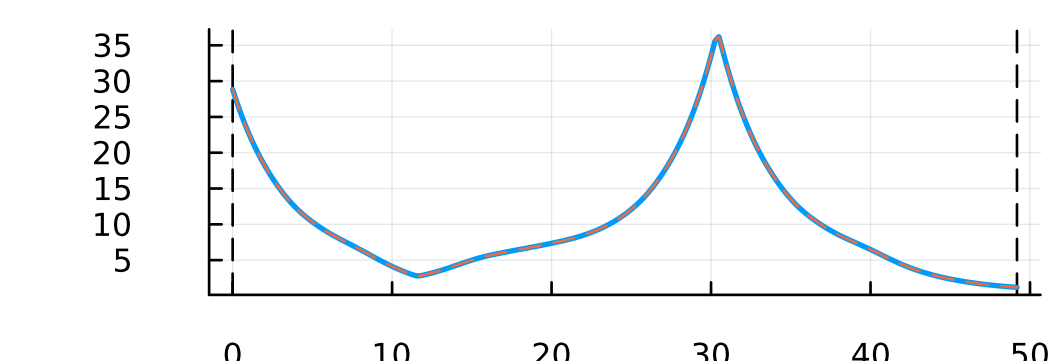
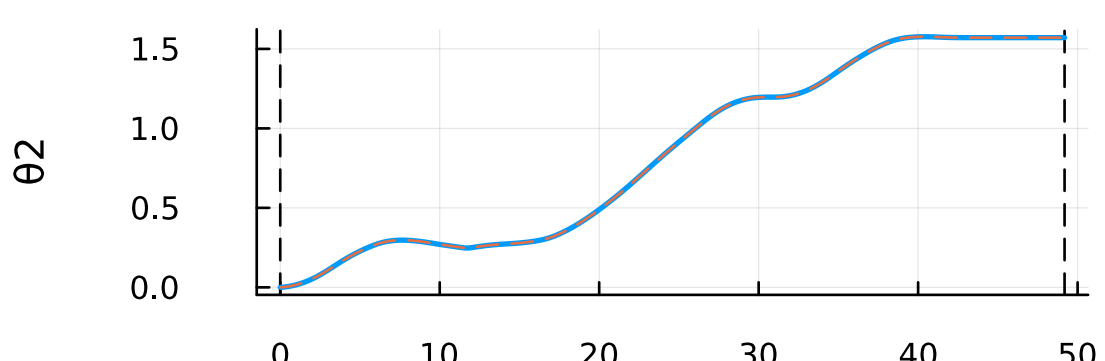
state



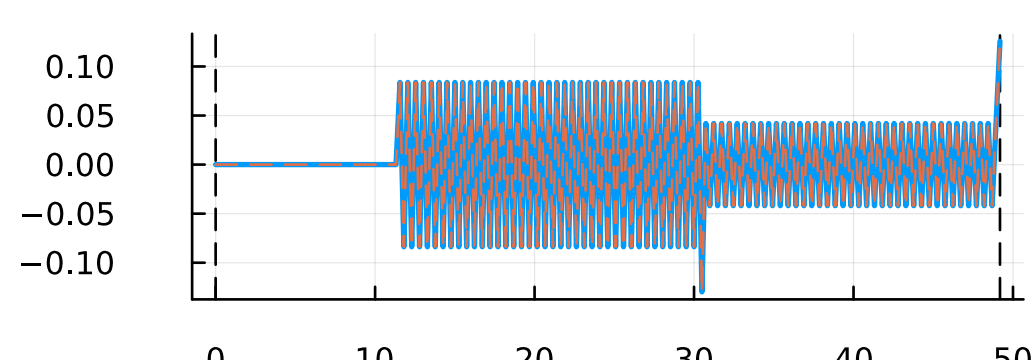
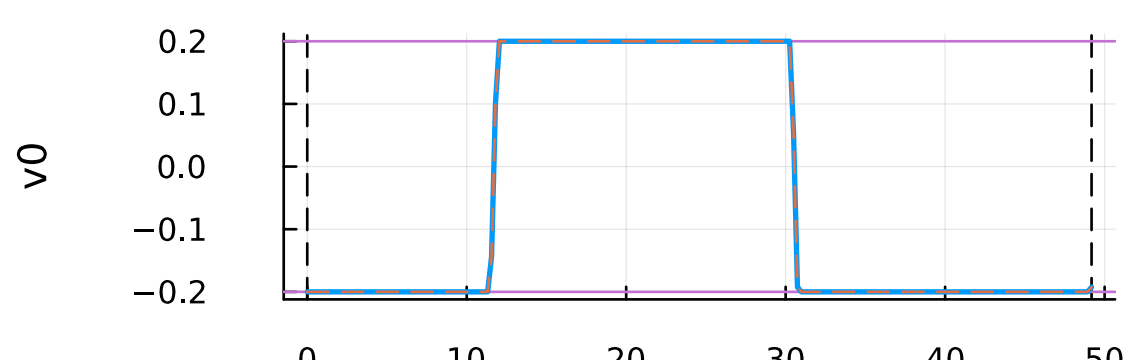
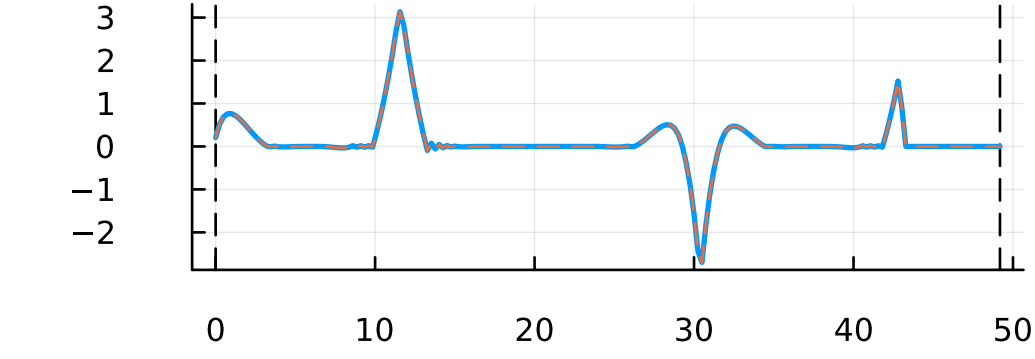
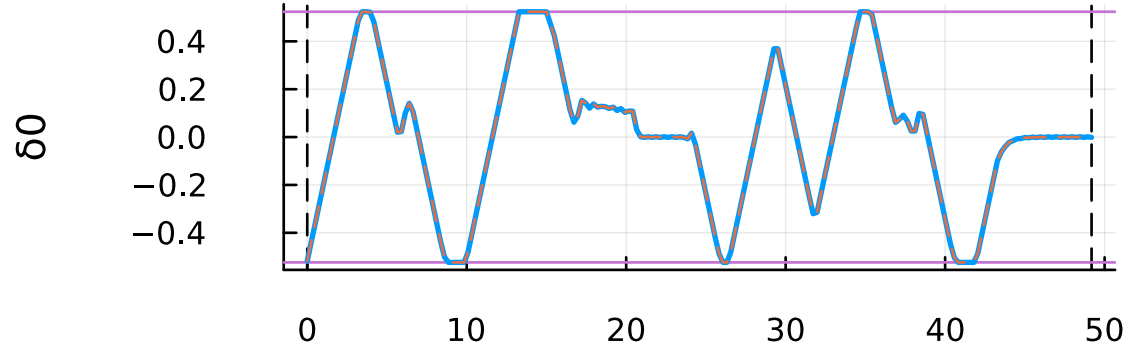
costate



y2

 θ_0  θ_1  θ_2 

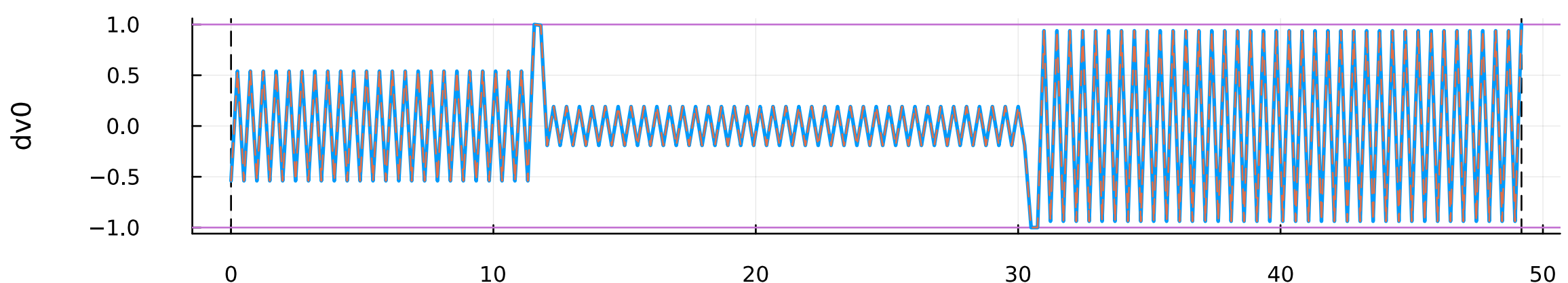
v0

 δ_0 

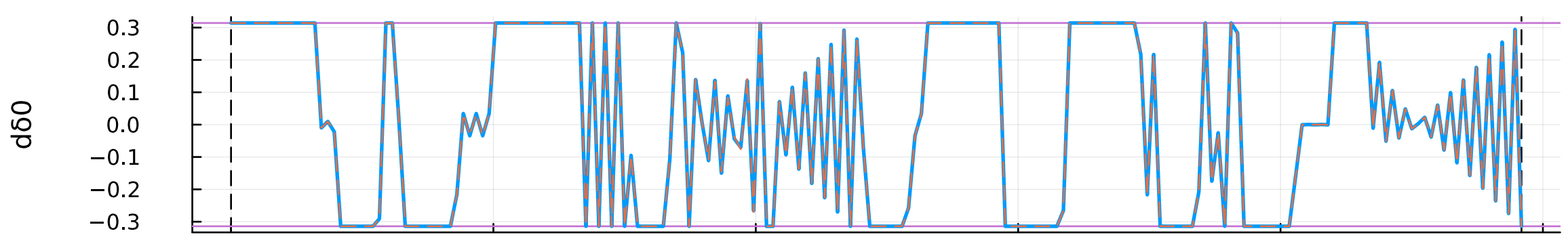
t

t

control

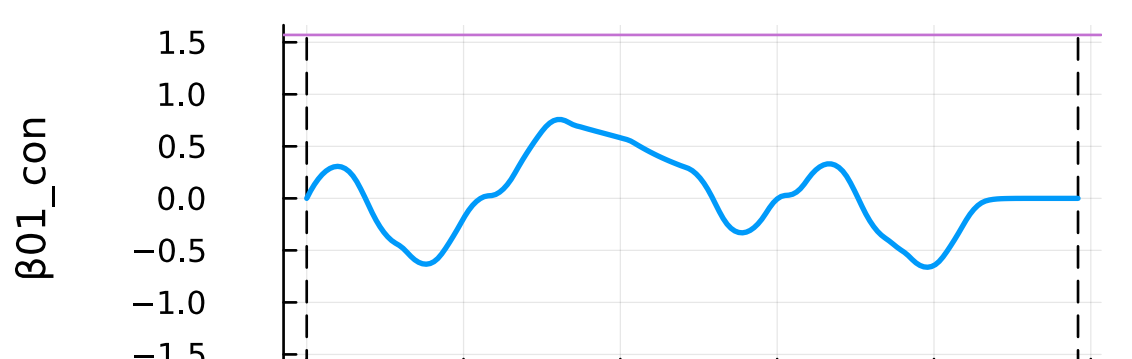


d60

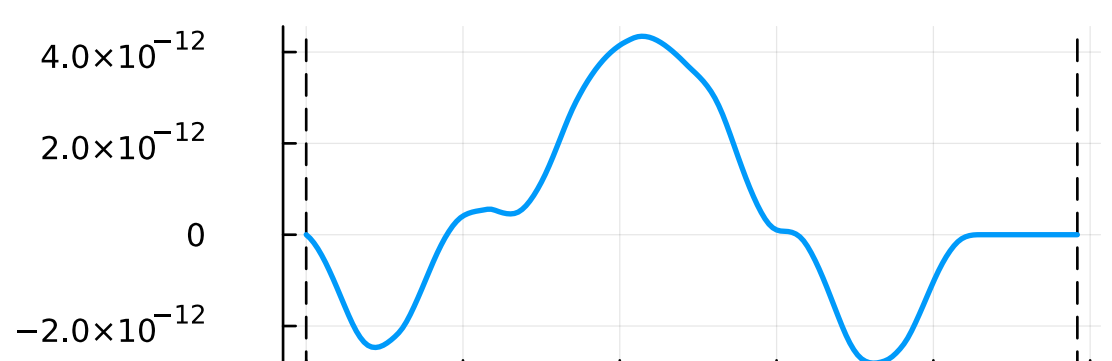
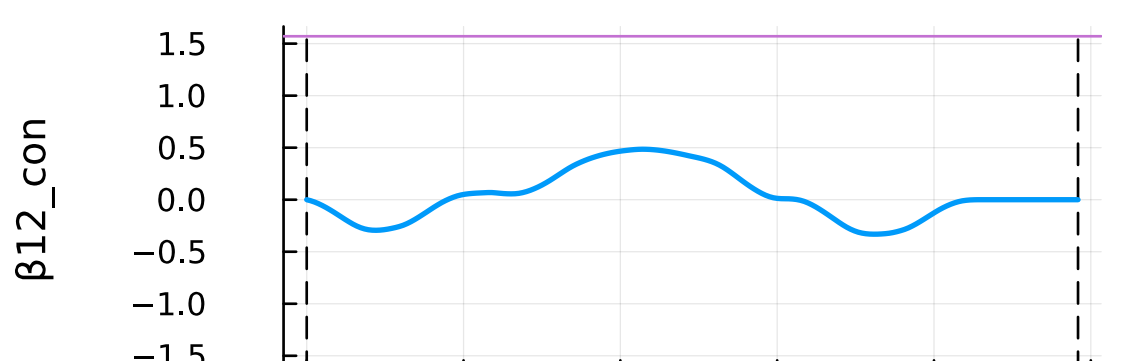


t

path constraints



dual

 β_{12_con} 

t

t