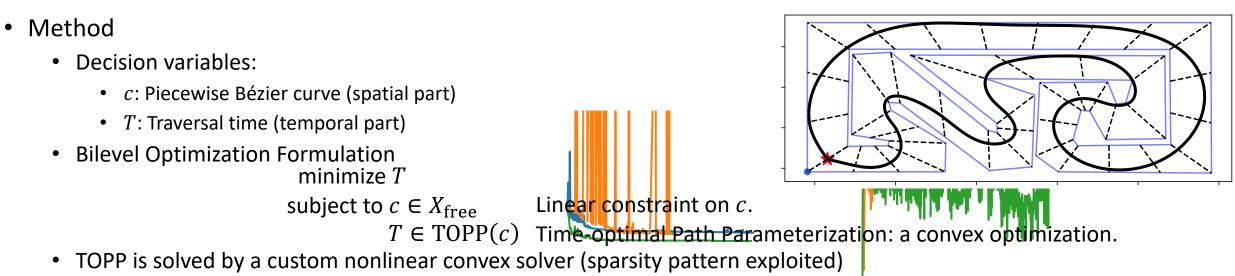
Time-Optimal Trajectory Generation for Dynamic Vehicles: A Bilevel Optimization Approach

• Goal: Find minimum-time trajectories for cars/drones in piecewise convex safe corridor.



- Results
 - Less constraint violation than IPOPT

DUKE ROBOTICS

• Lower cost than SNOPT

Intelligent

Motion

