

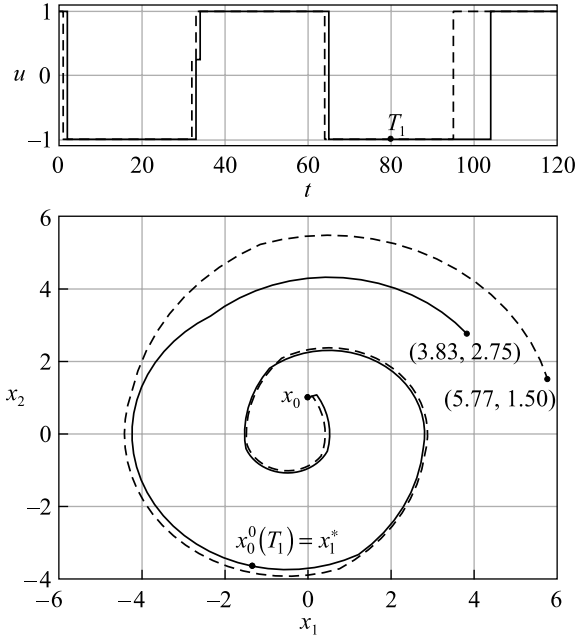


Fig. 2. Optimal control and trajectories in example 1 under the worst-case disturbance $w^*(\cdot)$