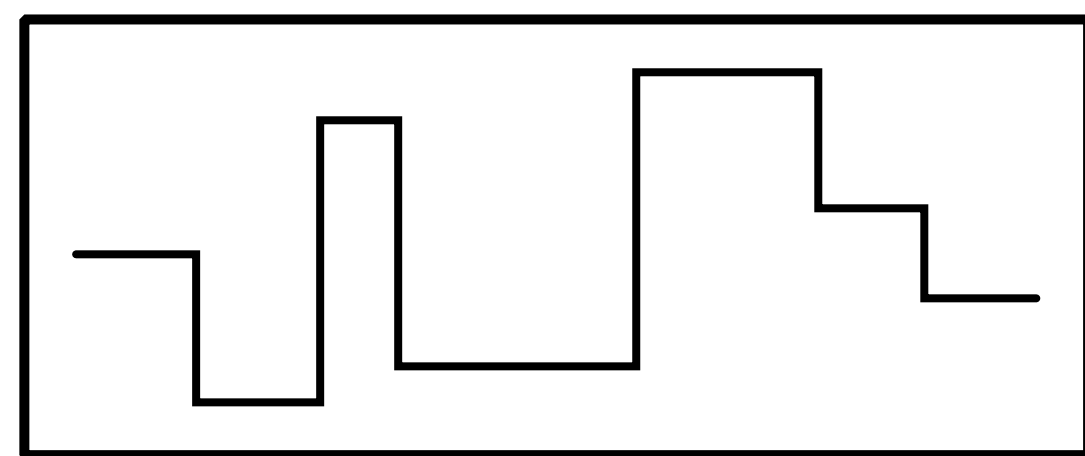
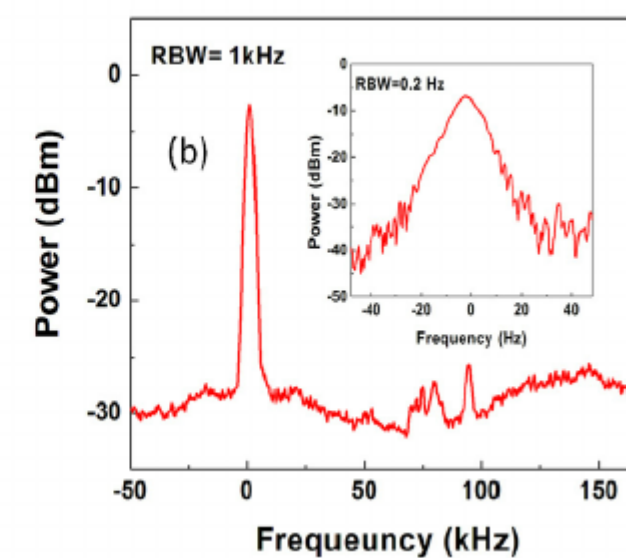
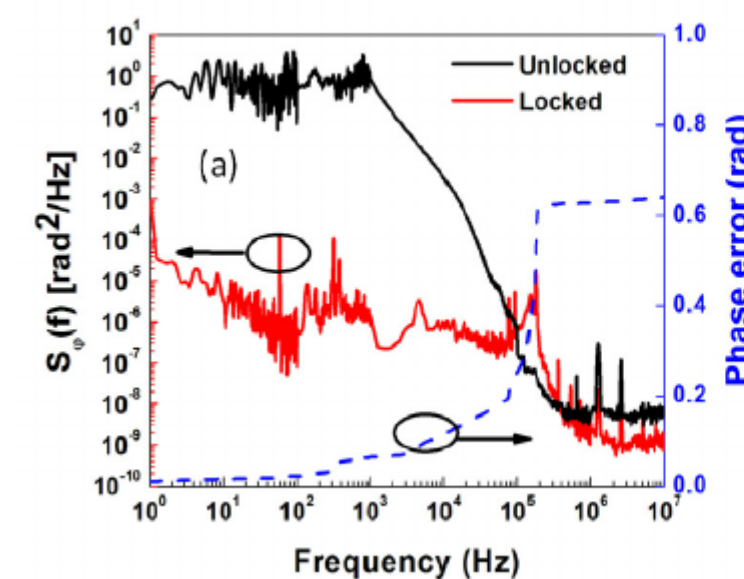
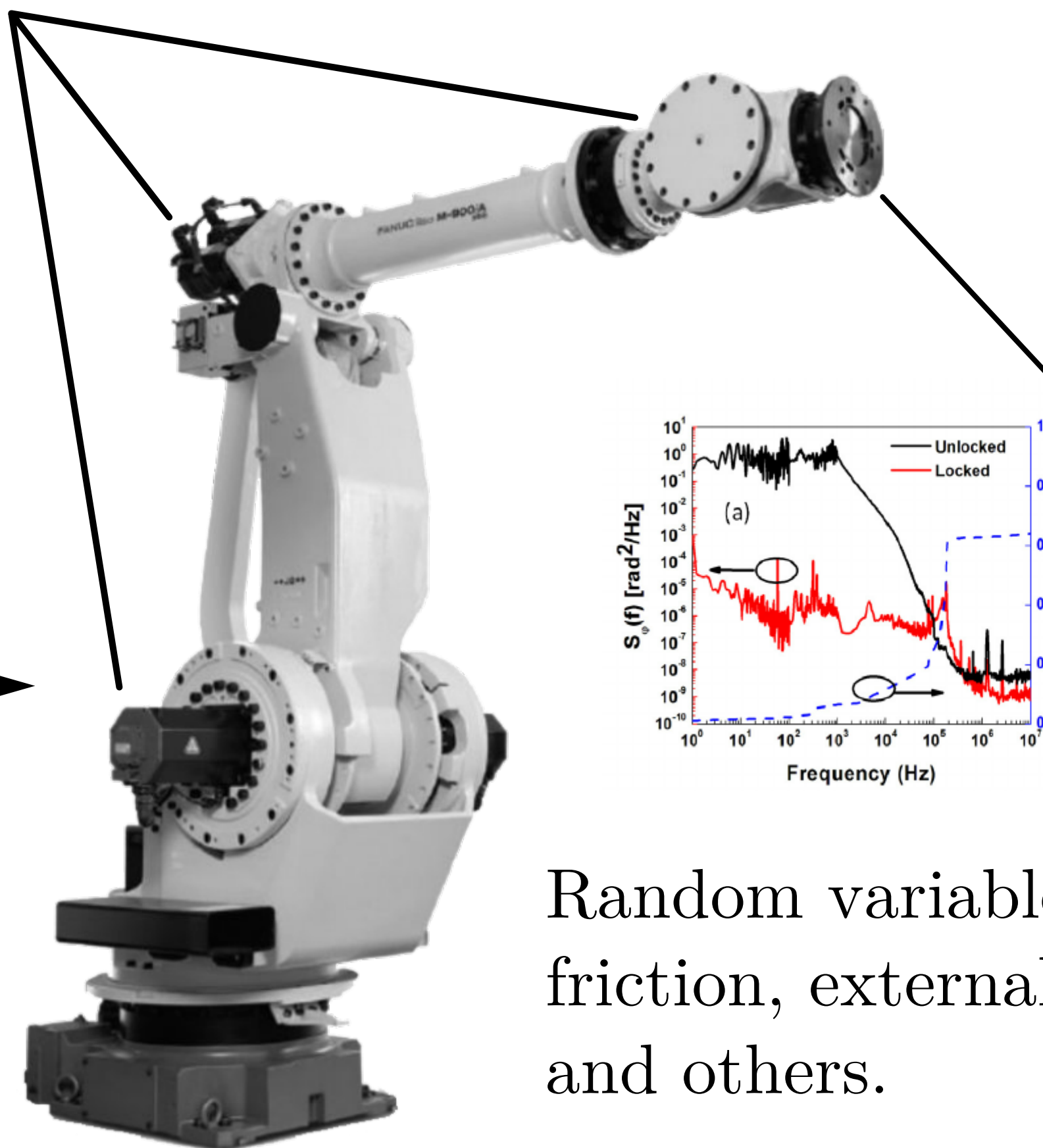
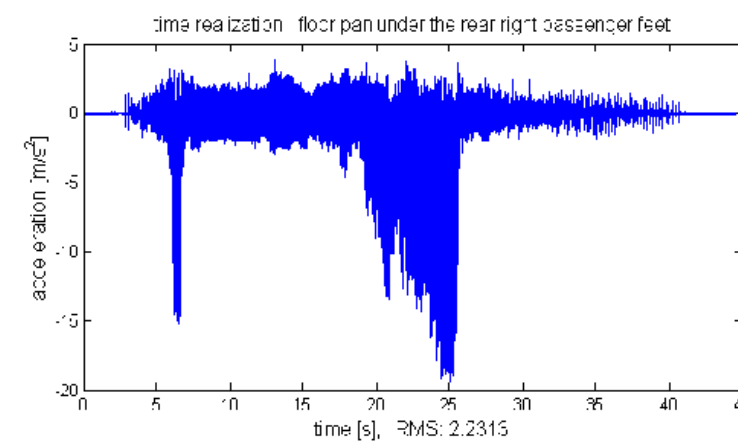
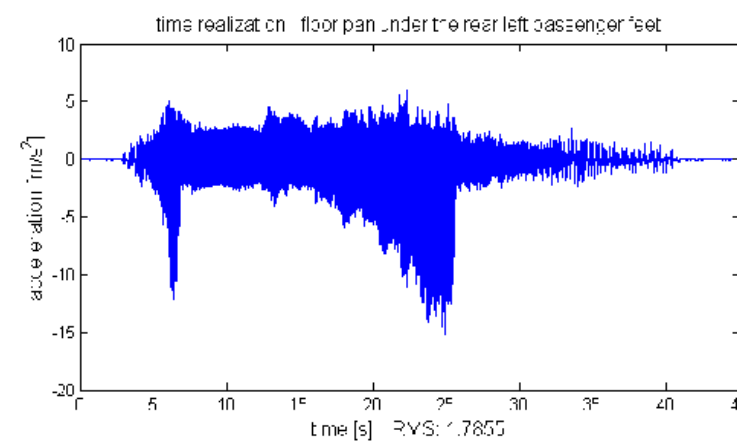


# Noise sensors



Control Input  $u$   
+ perturbation



Random variables:  
friction, external interaction,  
and others.