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Chop

Repeat

SampleDelay

● ylni: 0

● Kp: [1, 0; 0, 7.5]

This model implements a discrete time version of a proportional controller. Three expressions are used to implement the controller. First, there is a gain, implemented as a matrix vector multiplication. Next, the output is constrained by using min and max functions, and, finally, the output is delayed by one time step.

