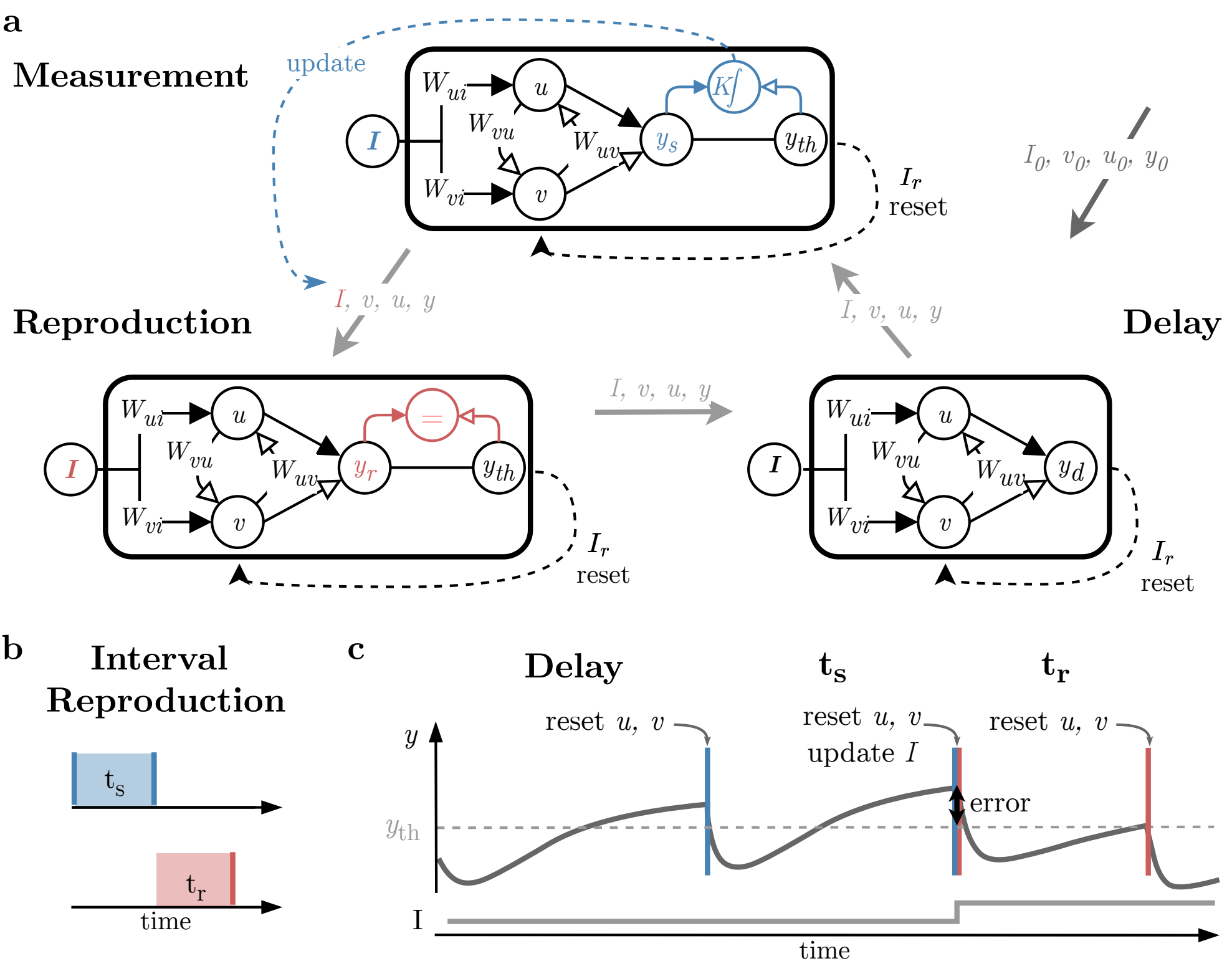
a
Measurement
update
W_{ui}
u
W_{vu}
W_{uv}
$K\int$
I
y_s
y_{th}
W_{vi}
v
I_r
reset
$I_0,\ v_0,\ u_0,\ y_0$
$I,\ v,\ u,\ y$
$I,\ v,\ u,\ y$
Reproduction
Delay
$I,\ v,\ u,\ y$
$=$
y_r
y_d
b
Interval
Reproduction
t_s
t_r
time
c
Delay
t_s
t_r
reset $u,\ v$
reset $u,\ v$
update I
reset $u,\ v$
y
error
y_{th}
I
time