Befor starting with the control parts…

* The goal is to control the bar pendulum at the upside position (180°)
* In the downside position (0°), since it is a stable position, the goal of the control is to bring the bar pendulum at 0° faster than the case we allow the syst to stabilze itself without the control.

In the Robustness test: parameter variation

* What they cause, does the changes relevant,