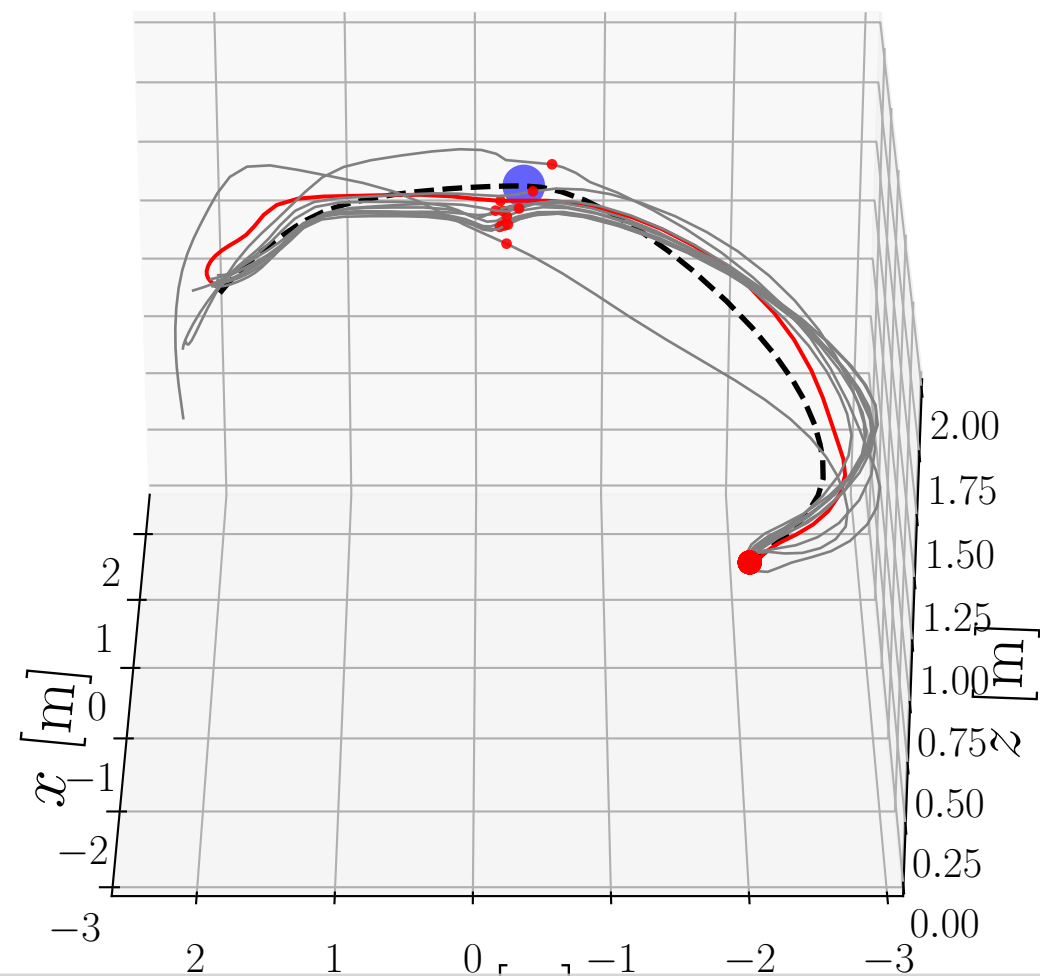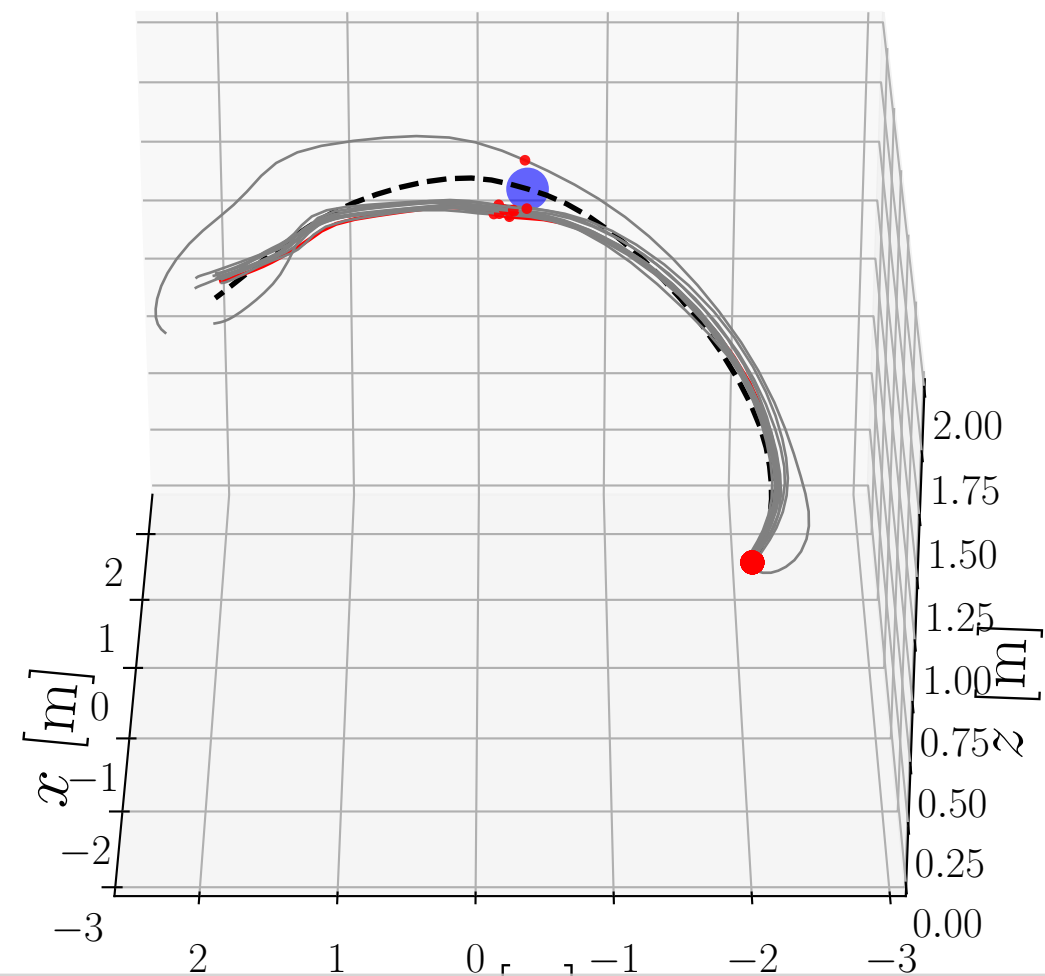INIT

PI

- ● Desired Target: $r_d(t_w)$
- - - - Reference Trajectory
- —— Nominal Controller tracking
- · closest positions to target
- —— $p \neq p_c$ Controller tracking with pertubation