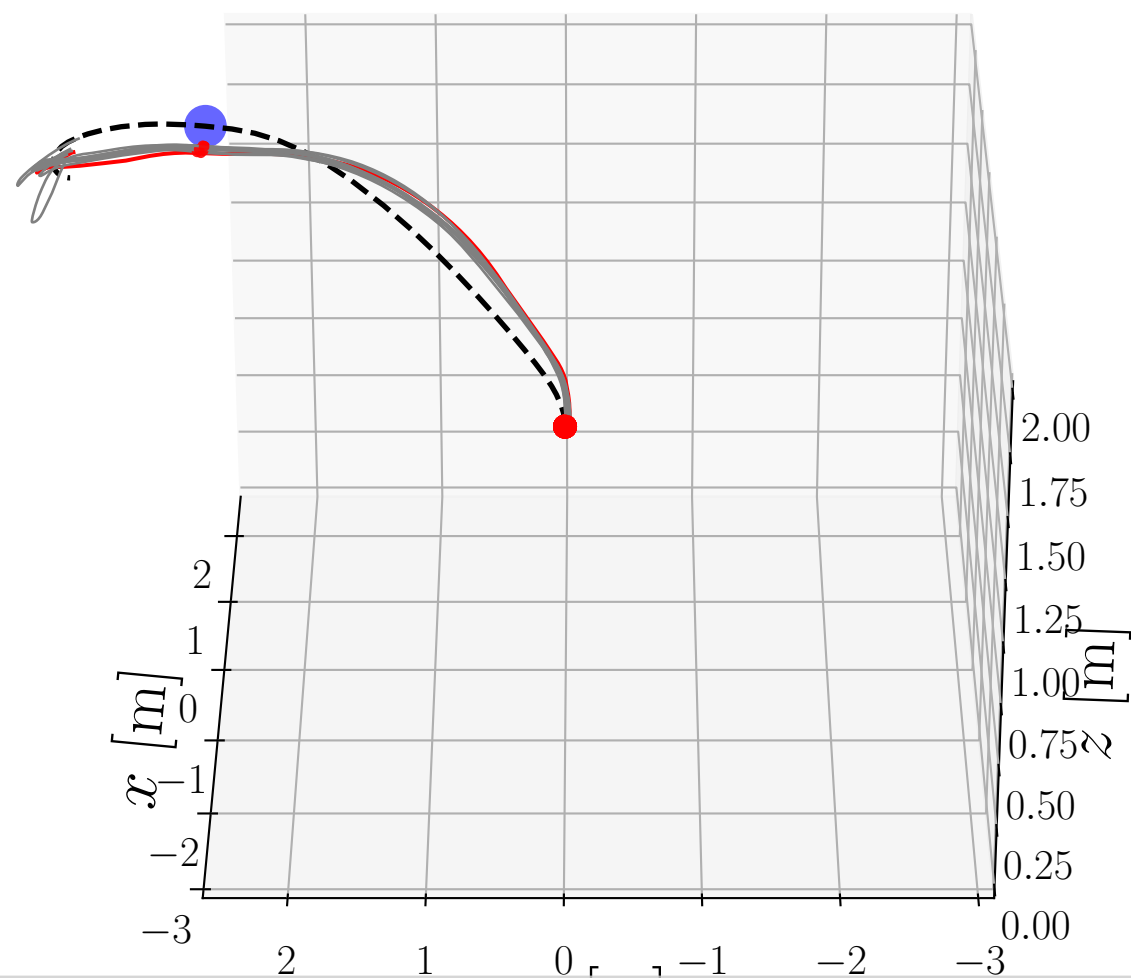
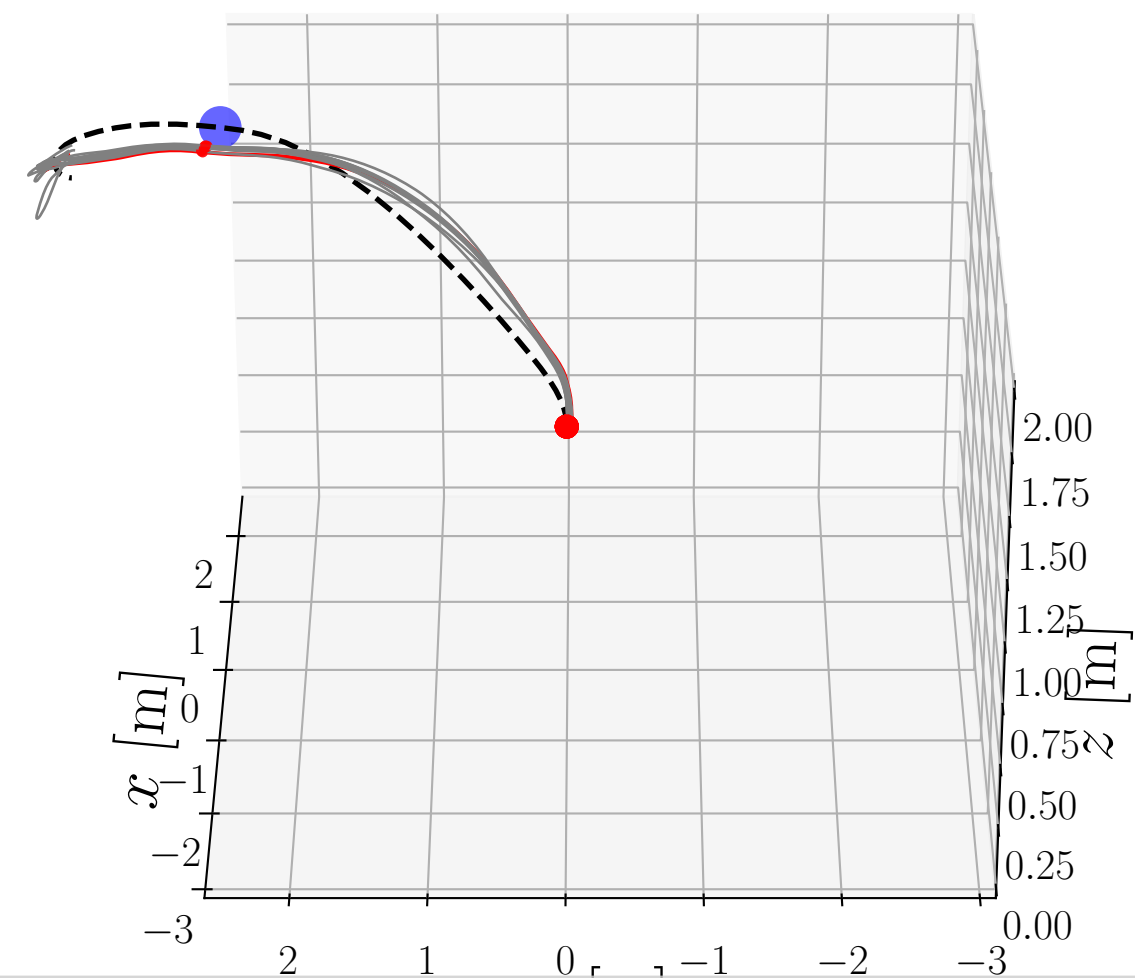


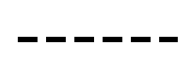
# INIT



# PI



Desired Target:  $r_d(t_w)$



Reference Trajectory



Nominal Controller tracking



closest positions to target



$p \neq p_c$  Controller tracking with perturbation