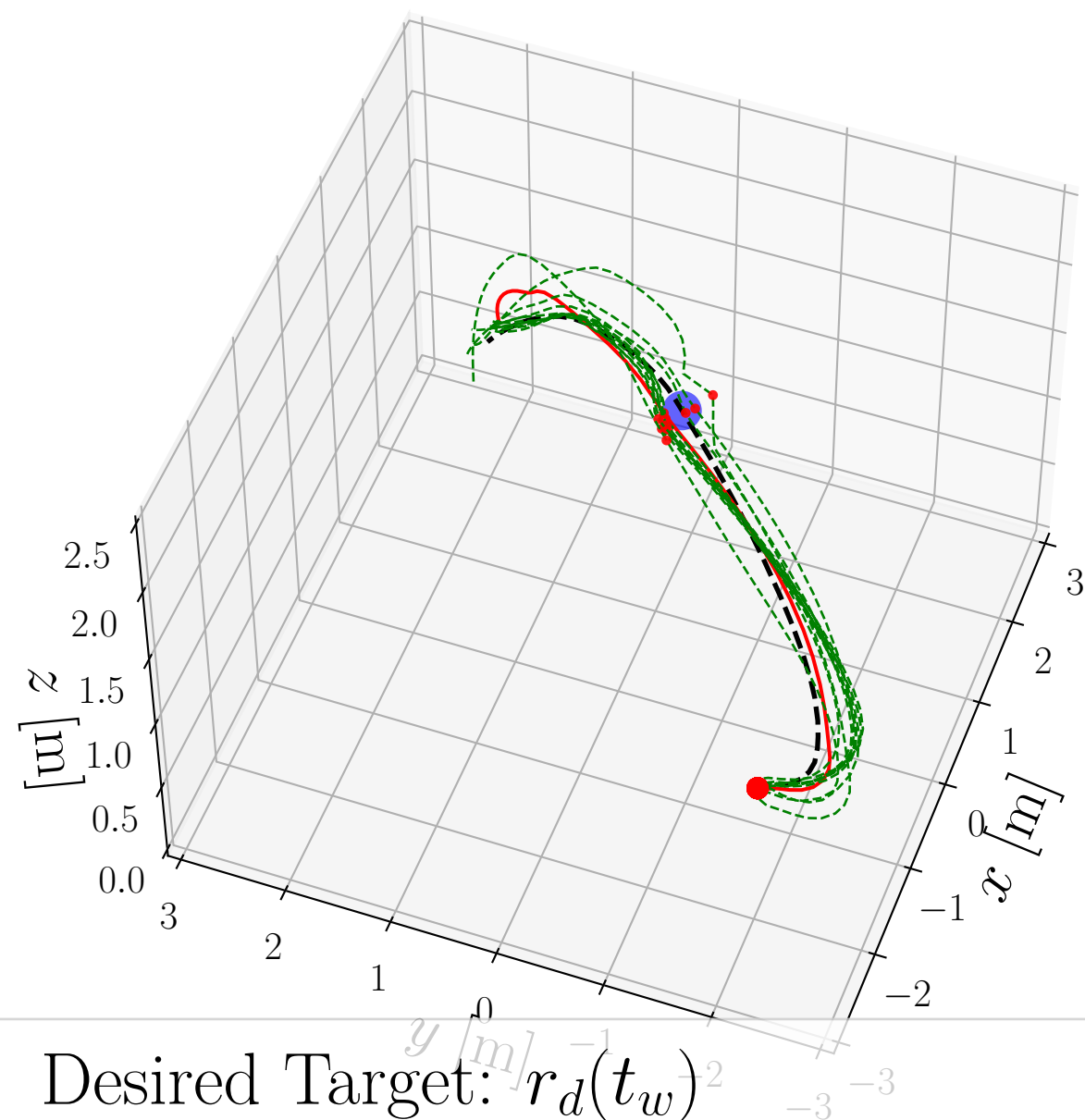
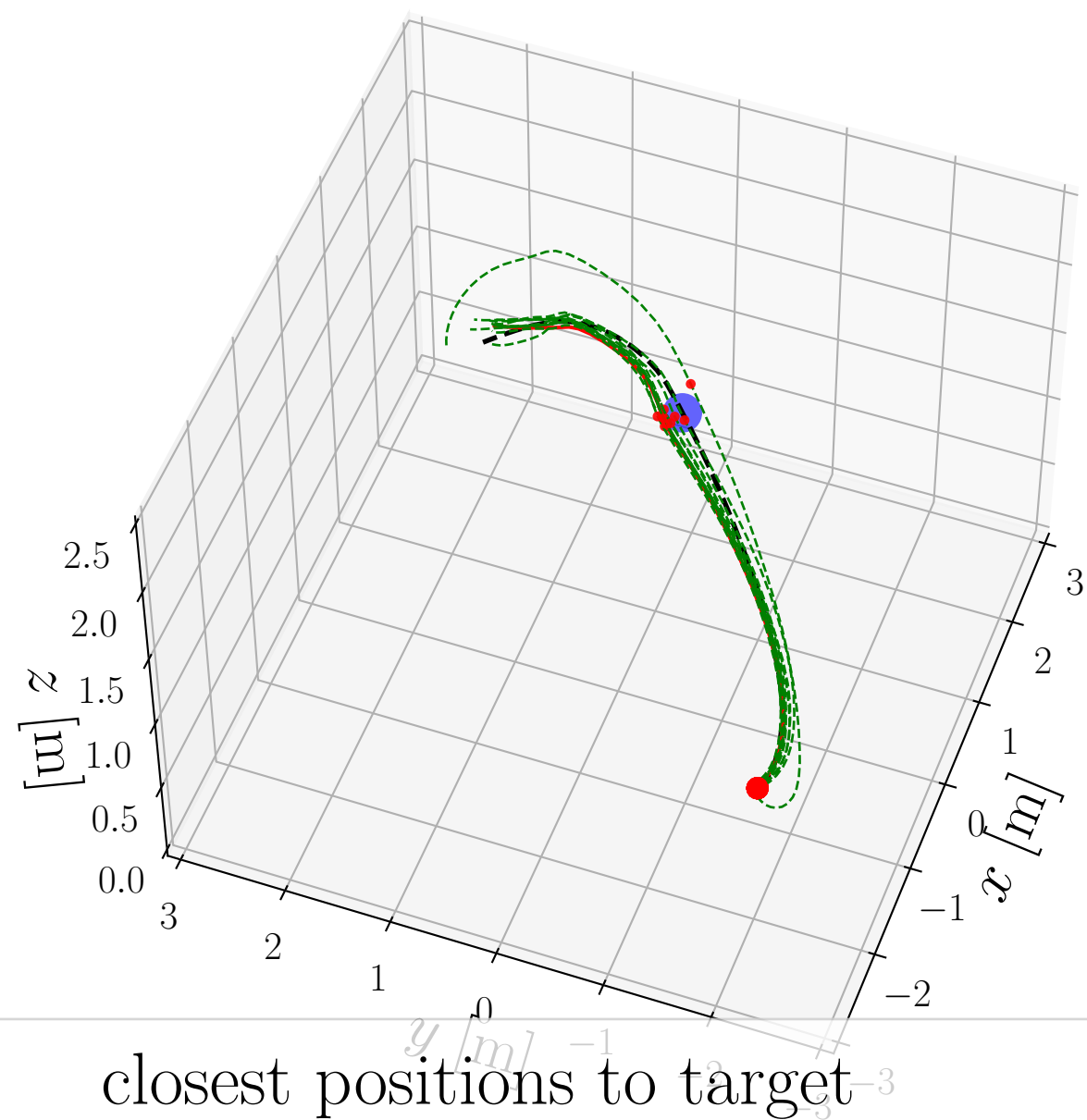


# INIT



# PI



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