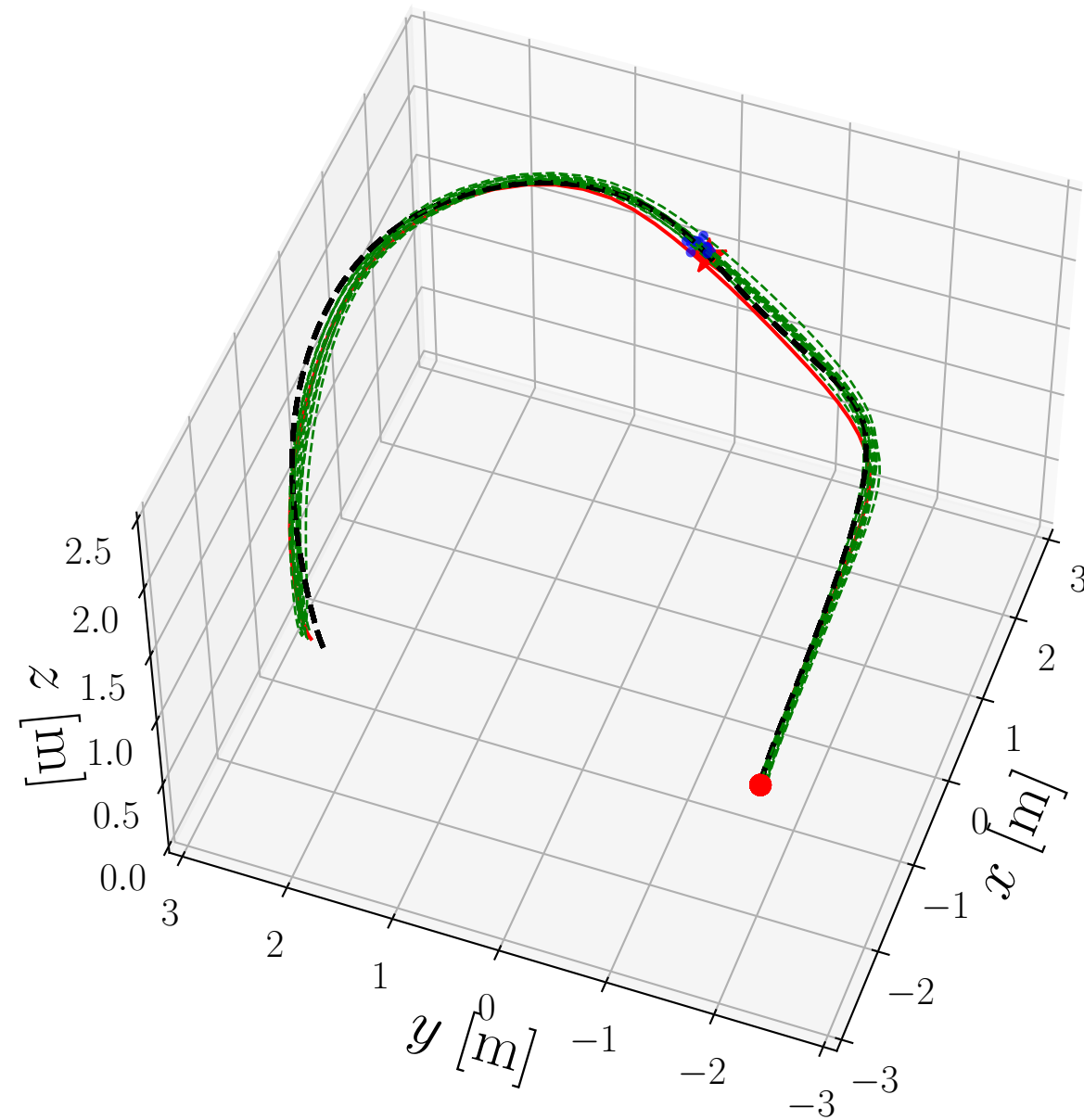
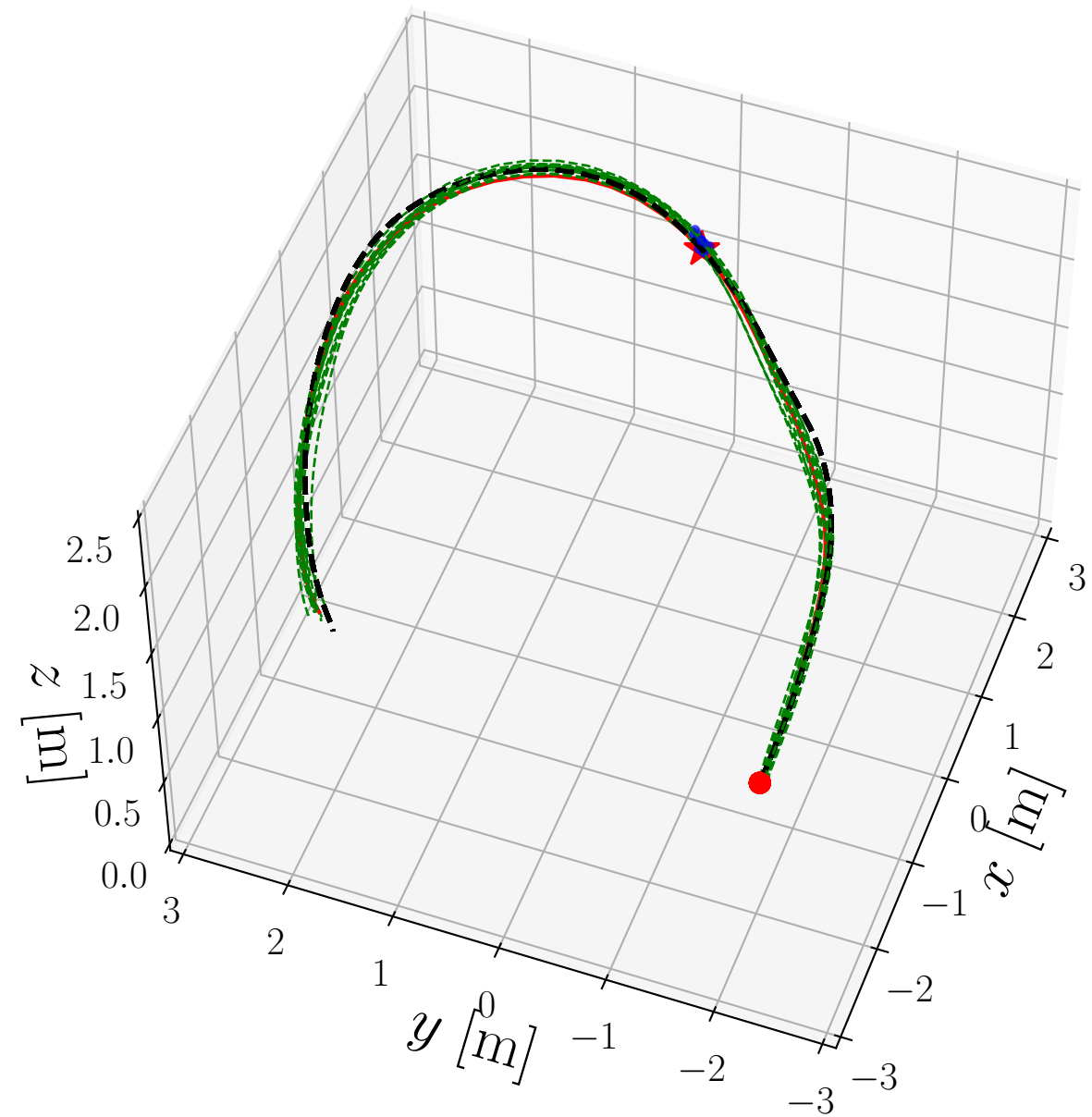


# INIT



# PI



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