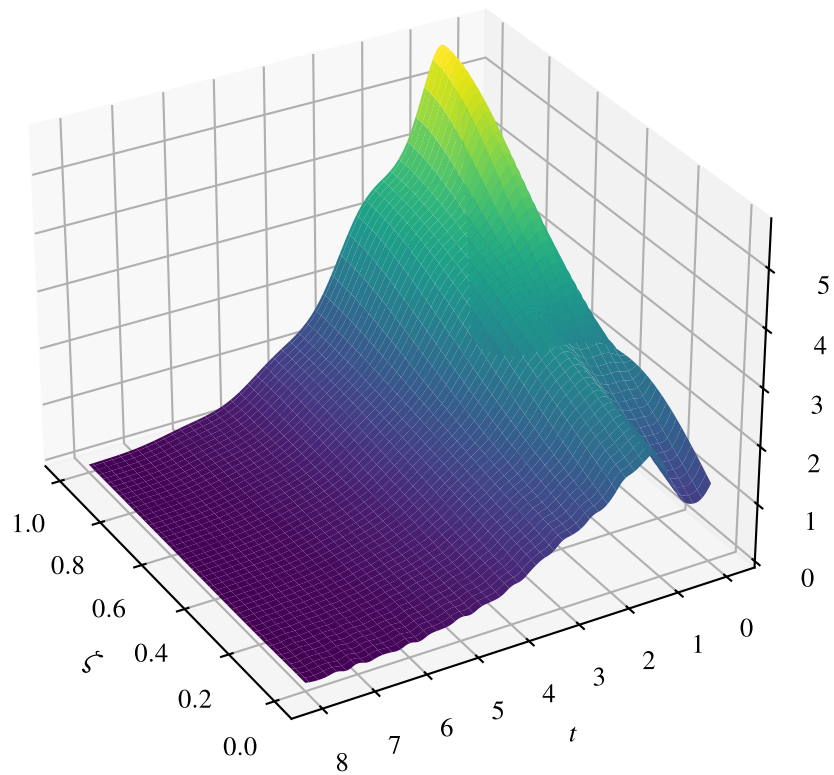


MPC-driven State Response:  $x_1(\zeta, t)$



MPC-driven State Response:  $x_2(\zeta, t)$

