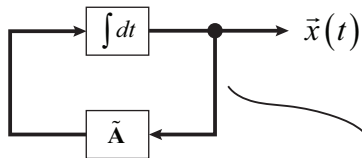
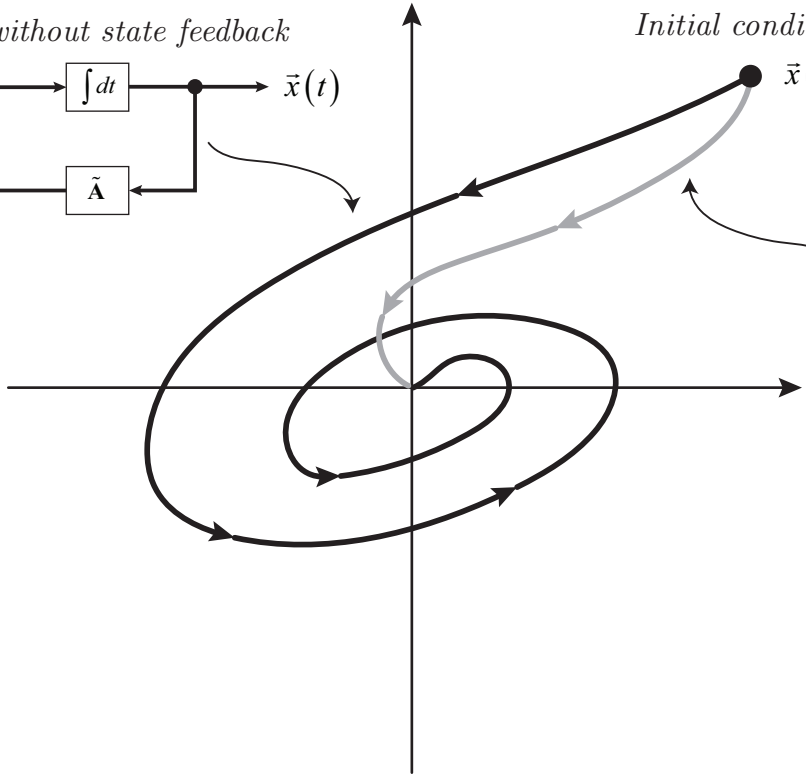


*Trajectory without state feedback*



*Initial condition*

$\bar{x}(0)$



*Trajectory with state feedback*

