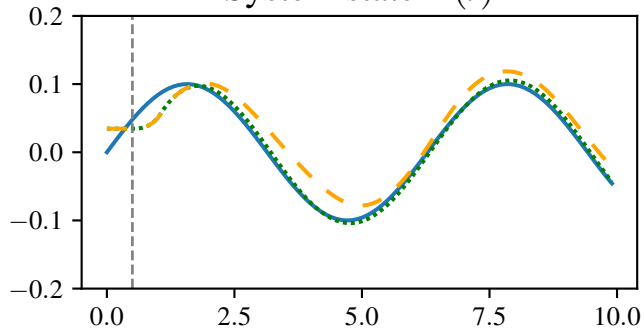
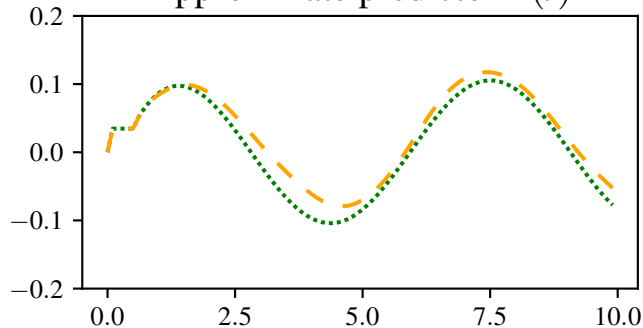
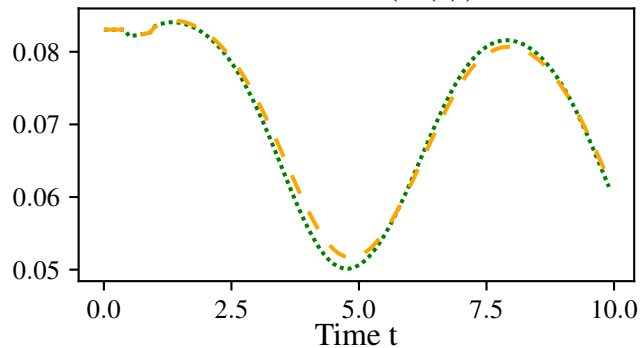


System state $X(t)$ Approximate predictor $\hat{P}(t)$ Control $\kappa(\hat{P}(t))$ Prediction error $\hat{P}(t) - X(t + D)$ 