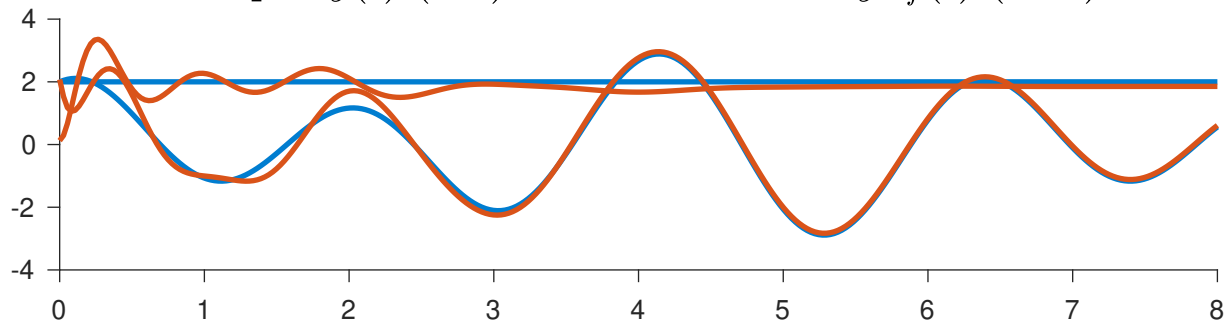
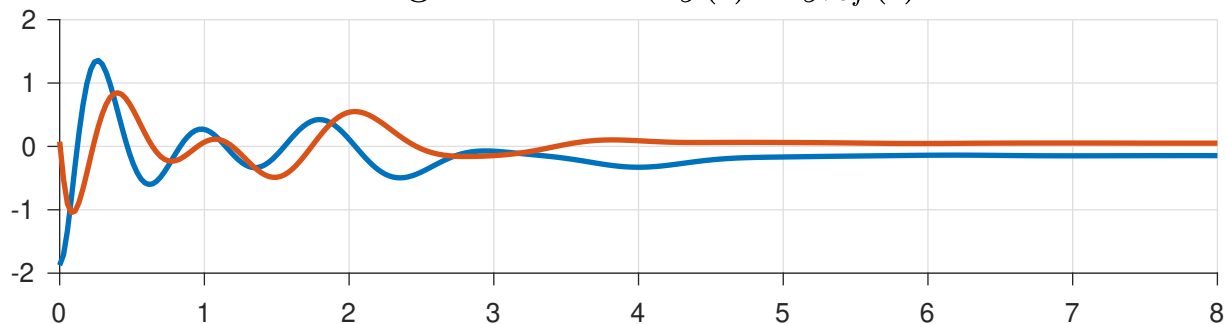


Output  $y(t)$  (red) and the reference  $y_{ref}(t)$  (blue)



Regulation error  $y(t) - y_{ref}(t)$



Control input  $u(t)$

