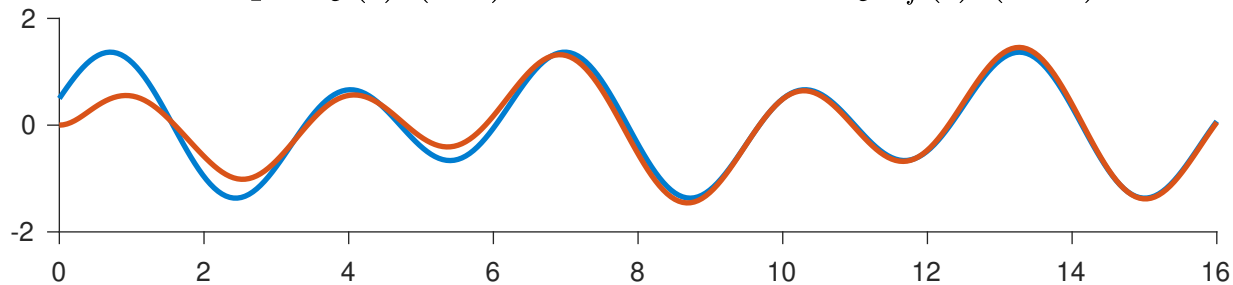
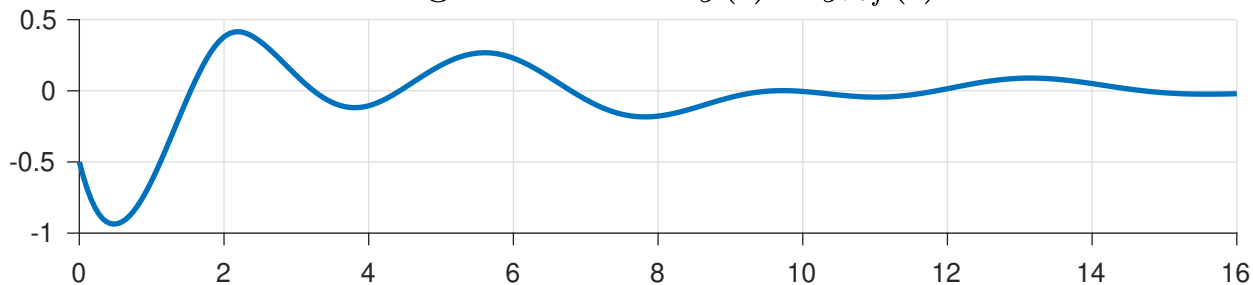


Output $y(t)$ (red) and the reference $y_{ref}(t)$ (blue)



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



Control input $u(t)$

