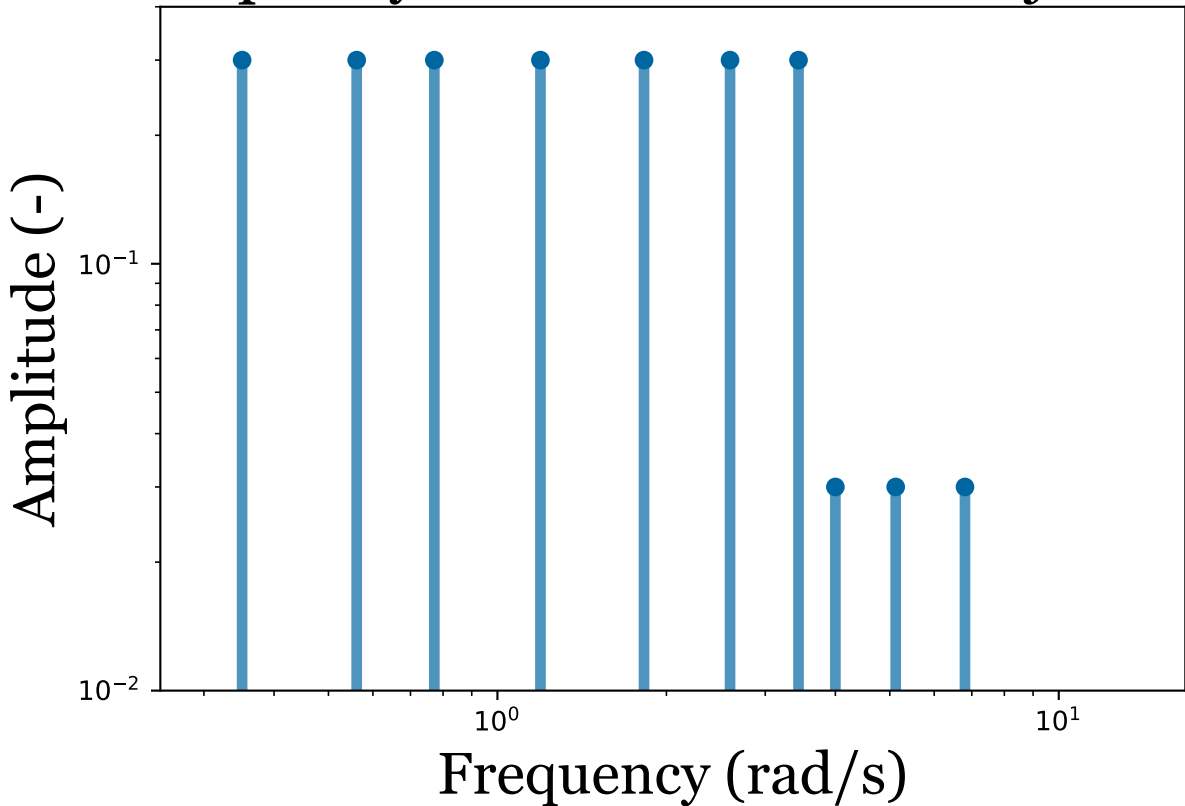
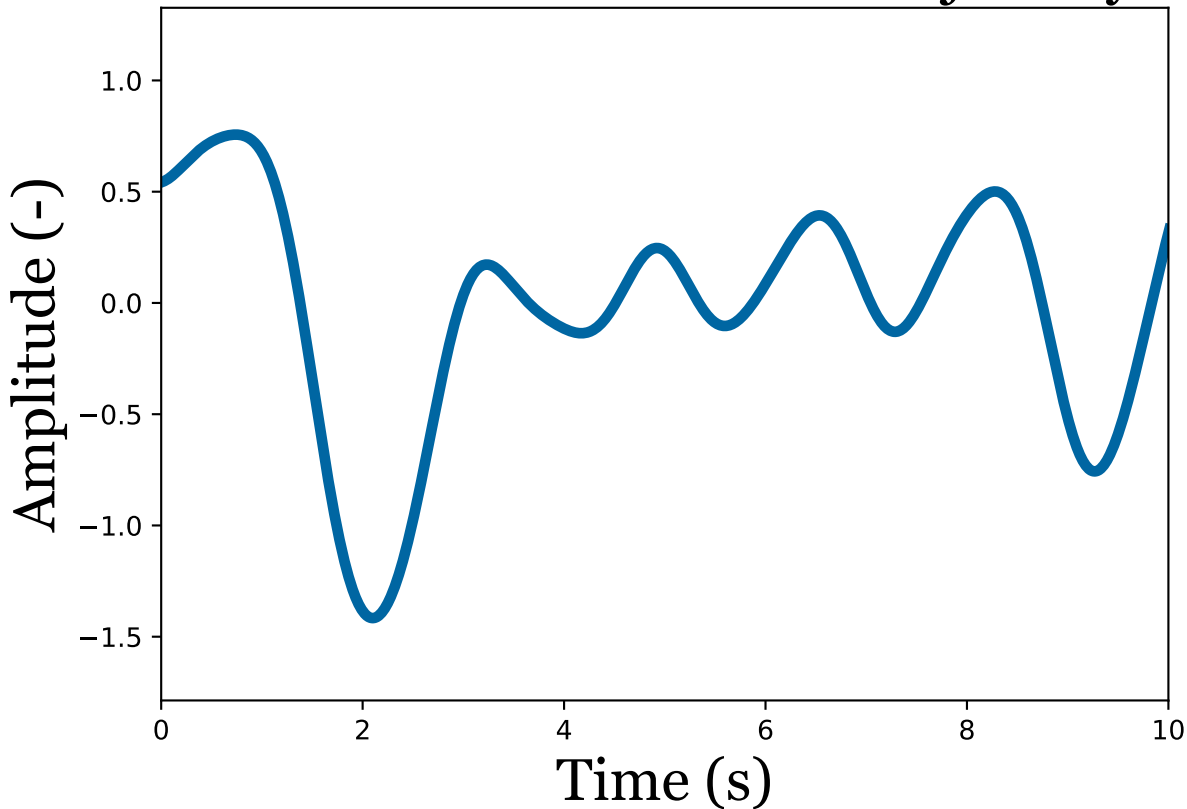


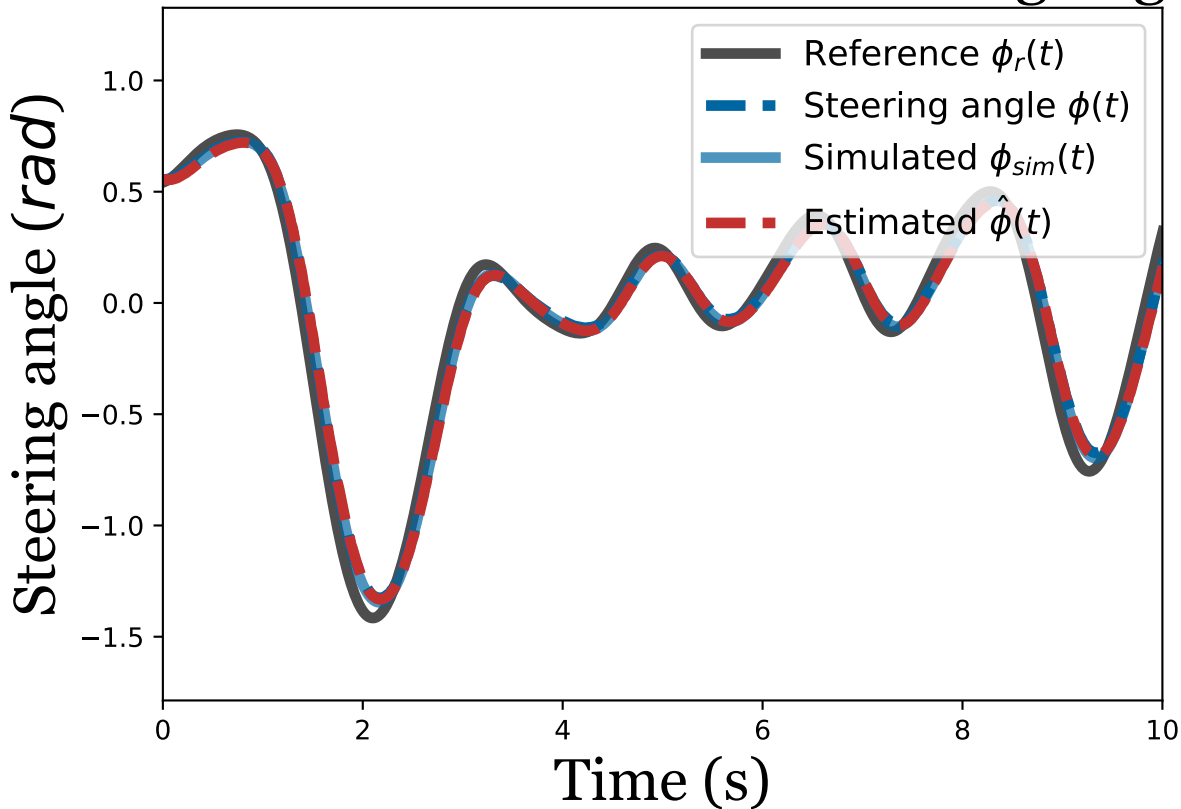
# Frequency domain reference trajectory

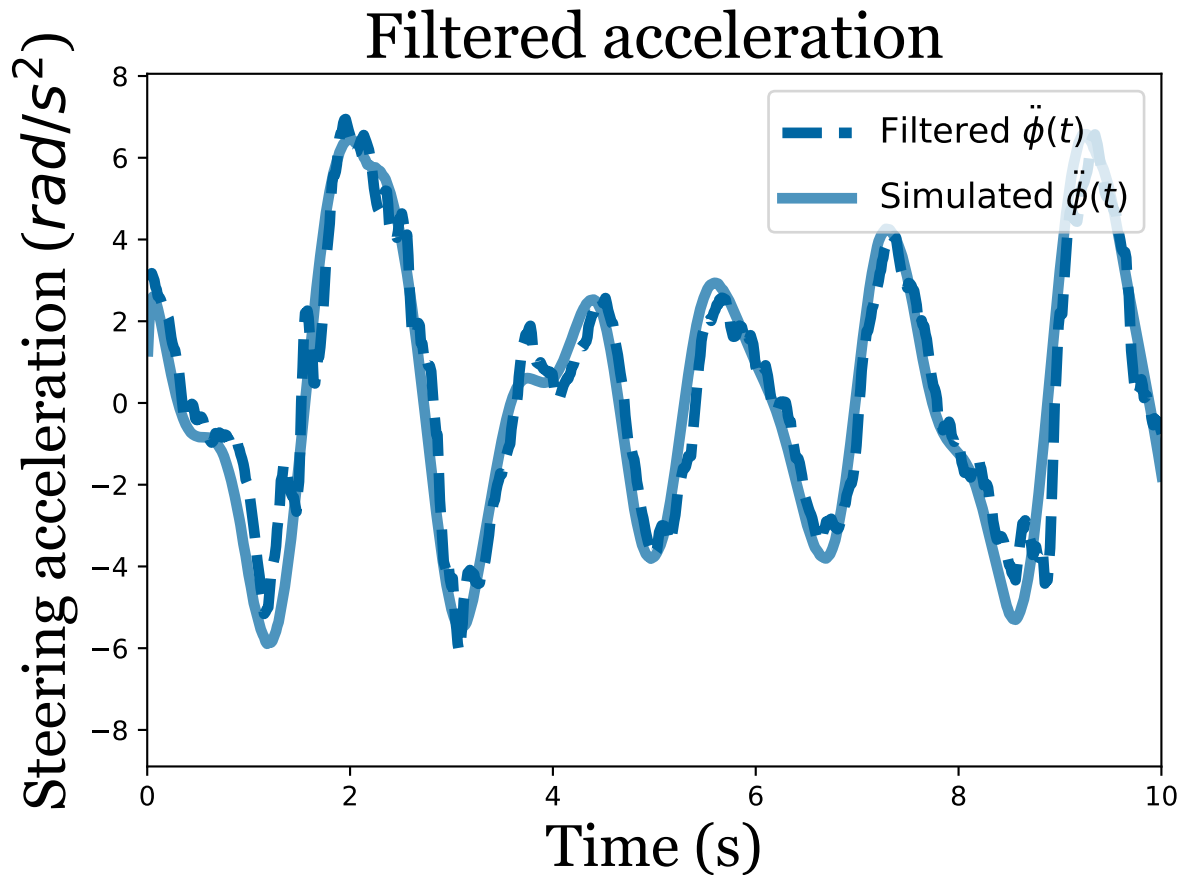


# Time domain reference trajectory

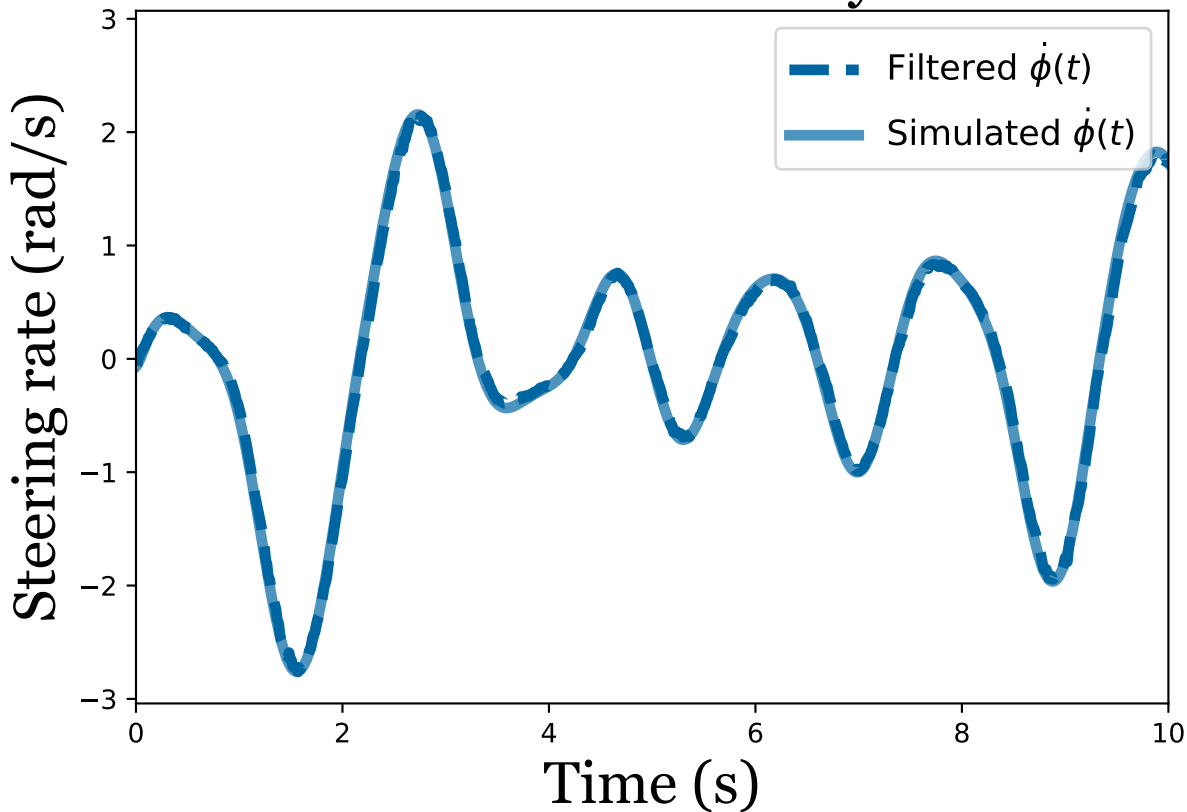


# Measured and estimated steering angle



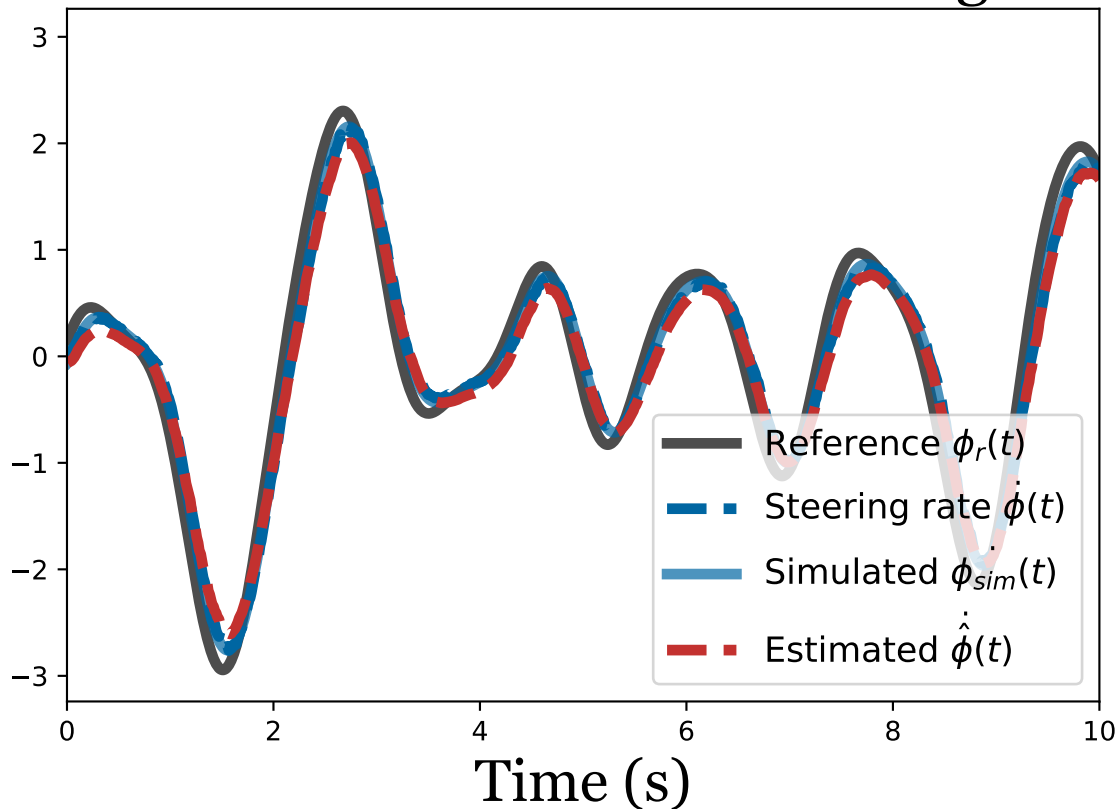


# Filtered velocity

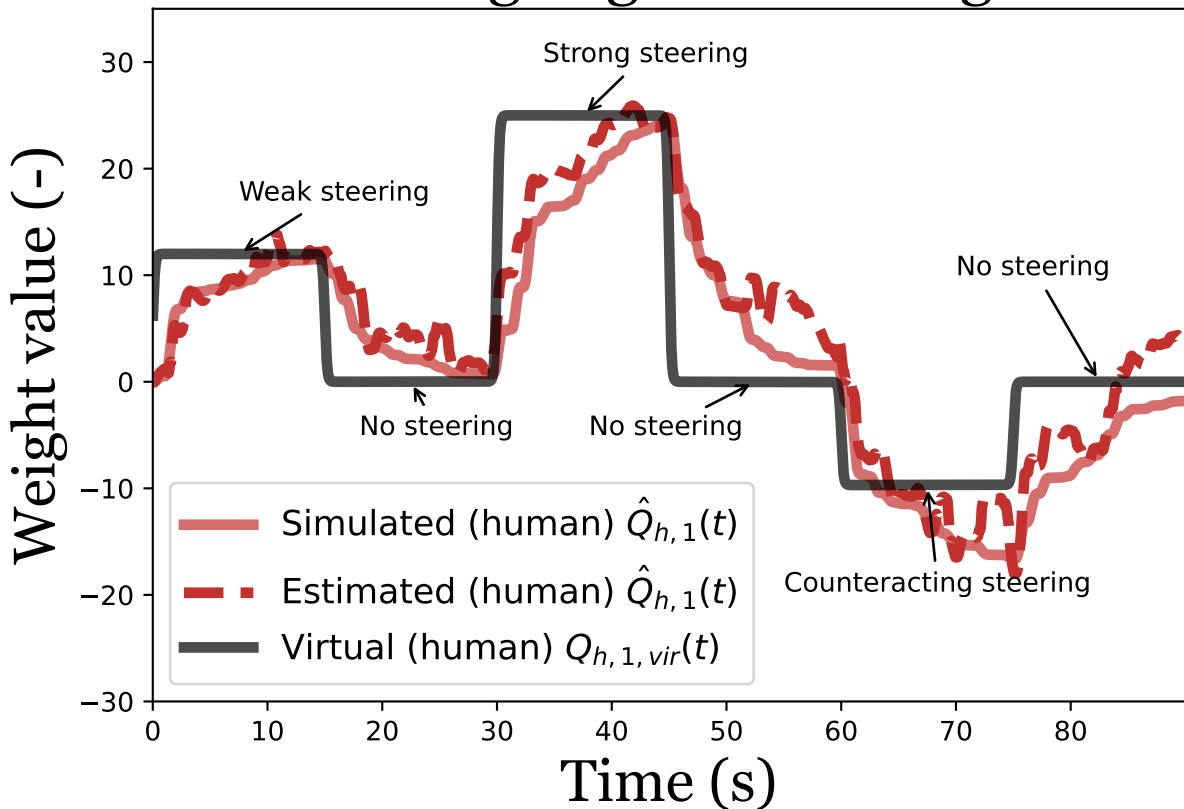


# Measured and estimated steering rate

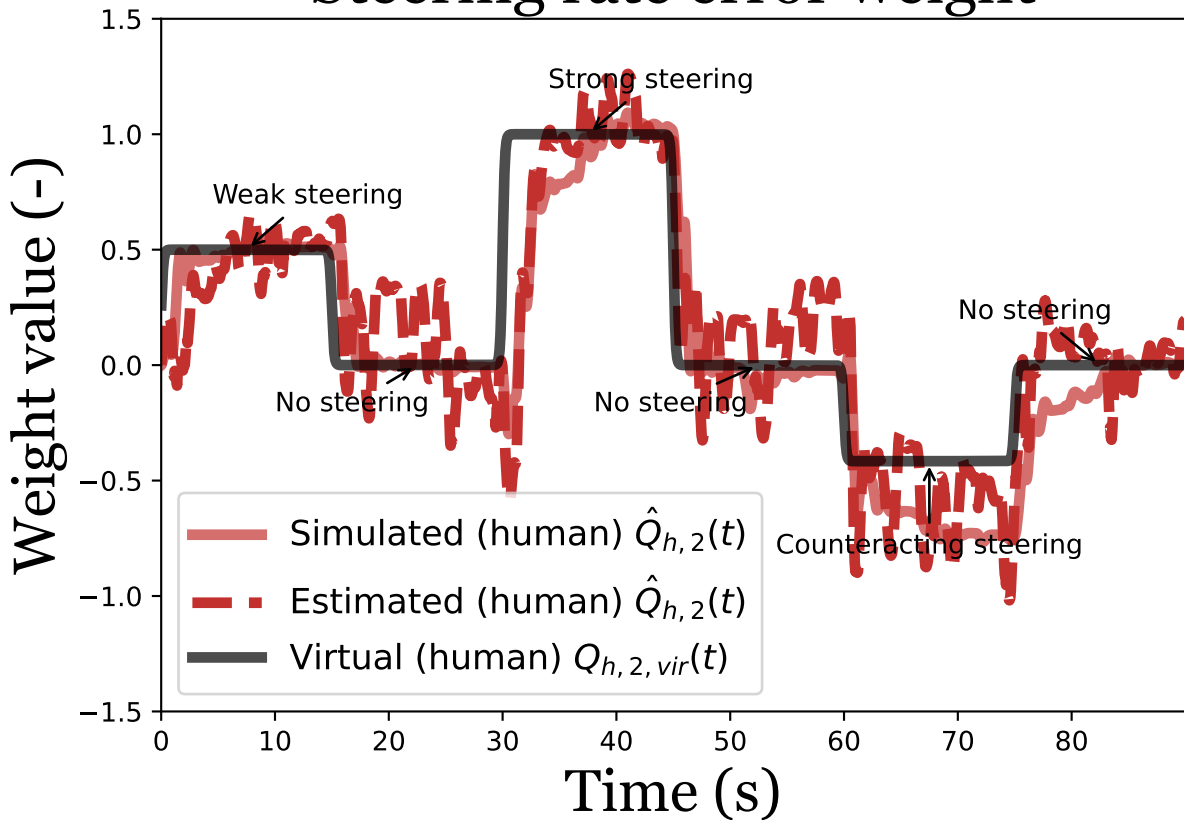
Steering angle (rad)



# Steering angle error weight

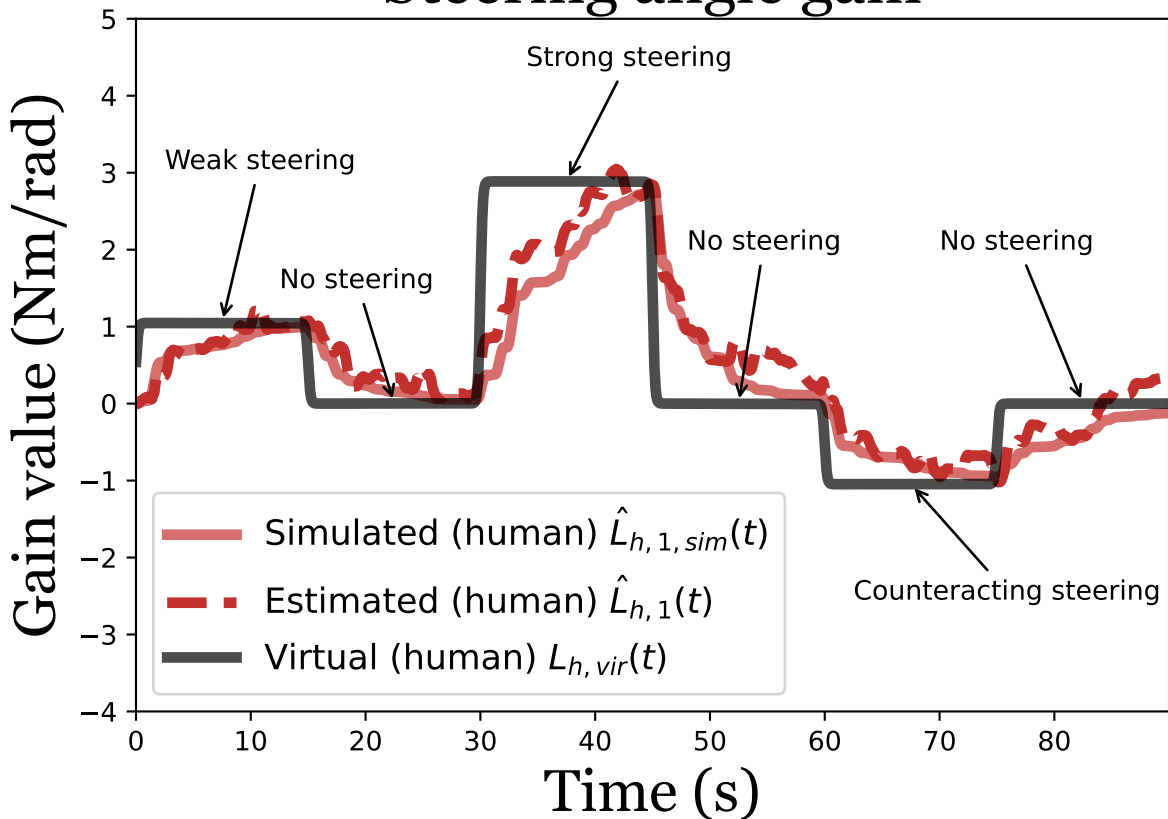


# Steering rate error weight



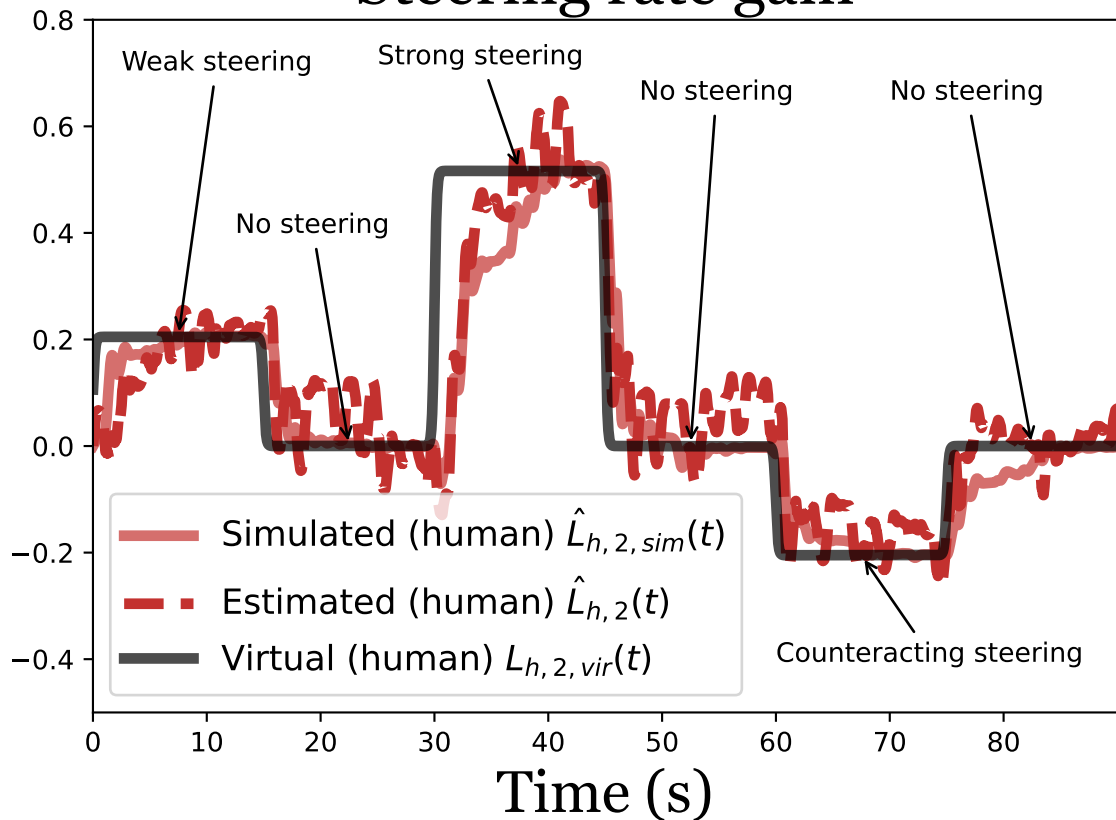


# Steering angle gain

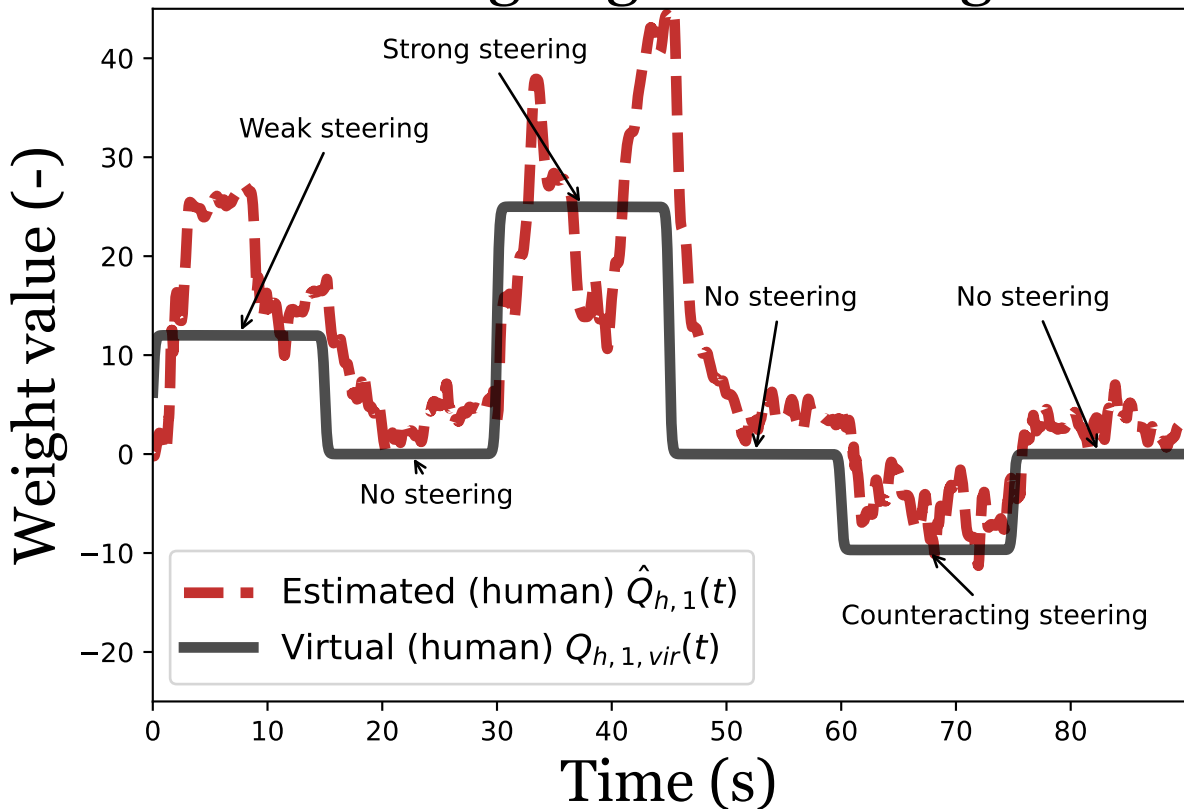


# Steering rate gain

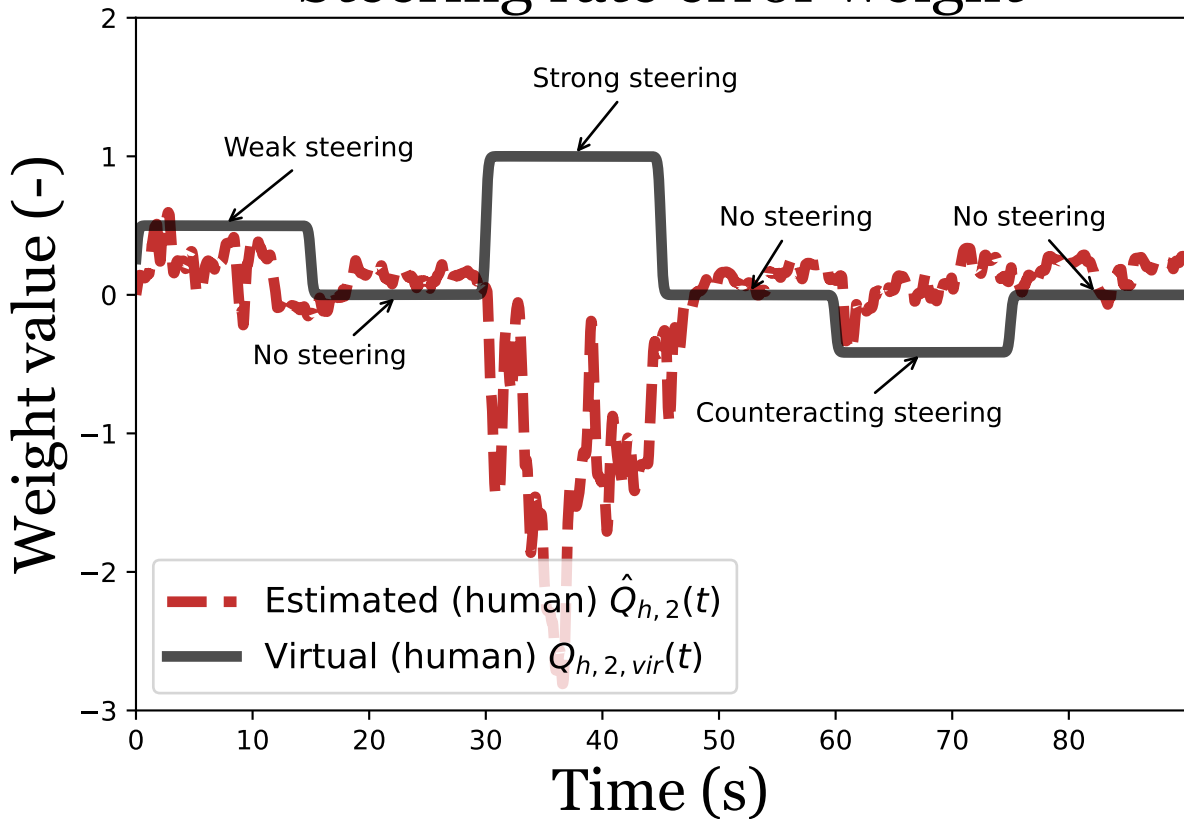
Gain value (Nms/rad)



# Steering angle error weight

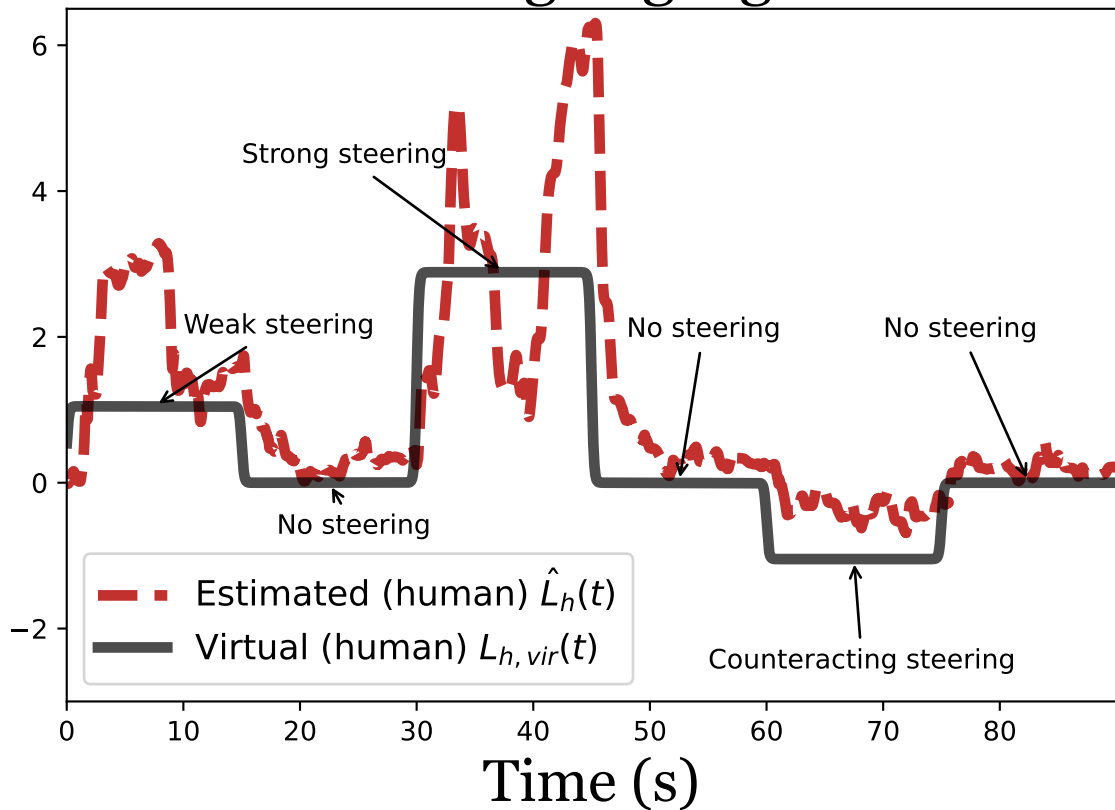


# Steering rate error weight

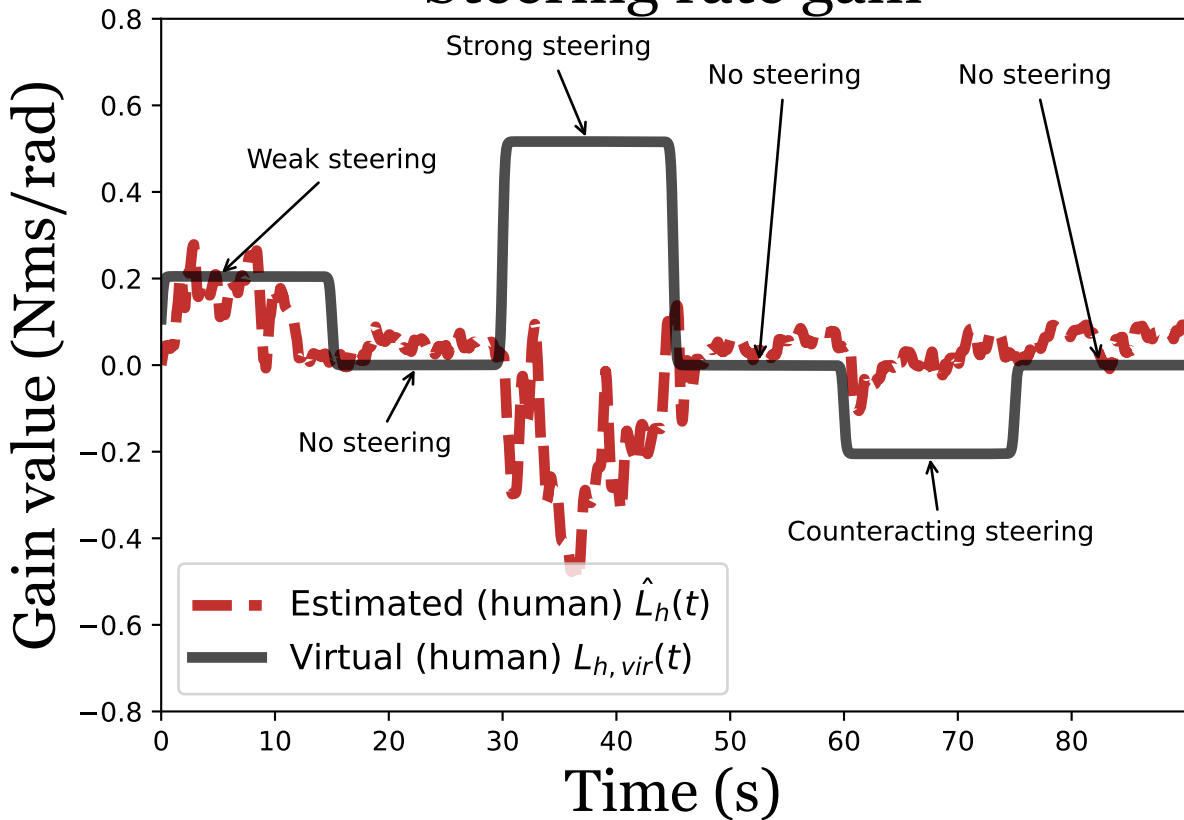


# Steering angle gain

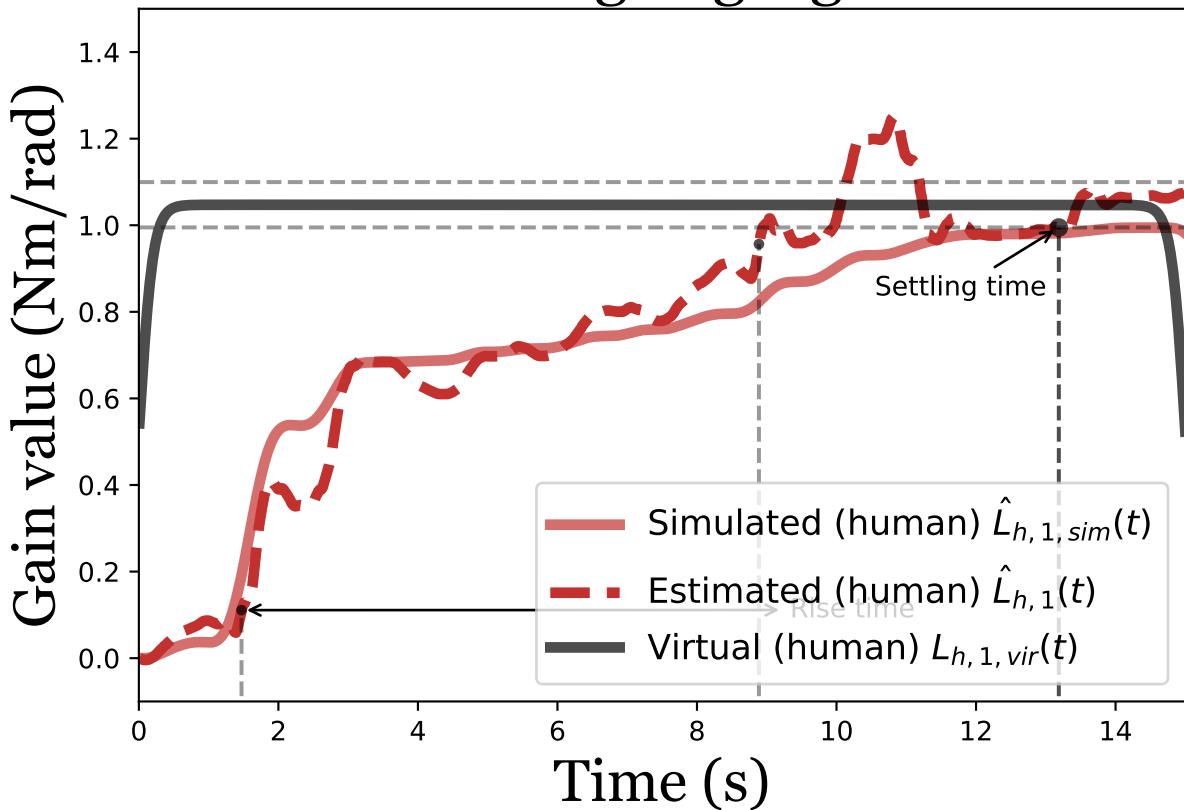
Gain value (Nm/rad)



# Steering rate gain



# Steering angle gain



# Steering rate gain

Gain value (Nms/rad)

