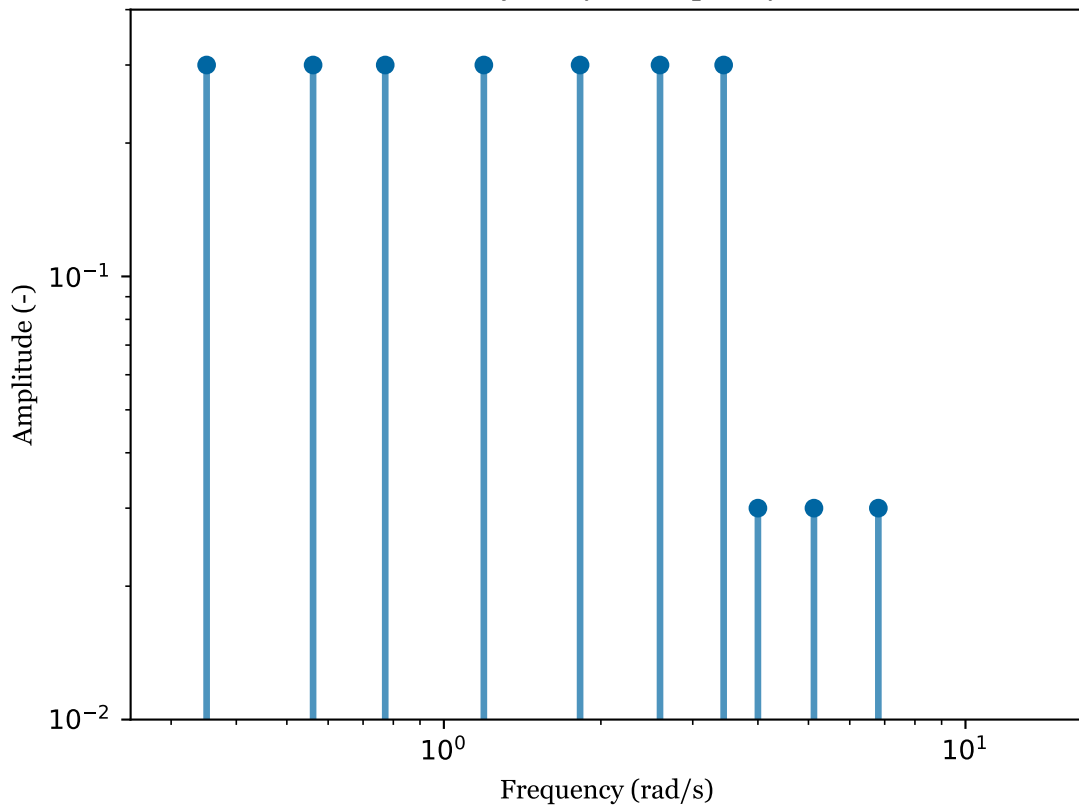
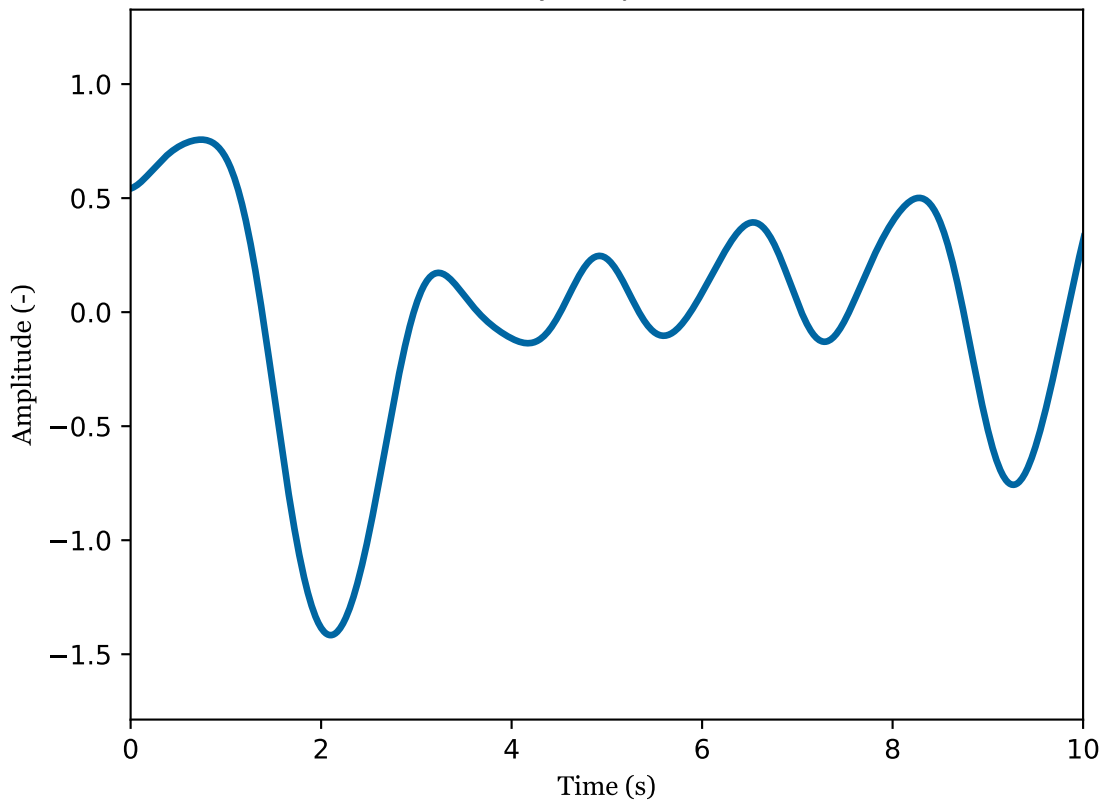


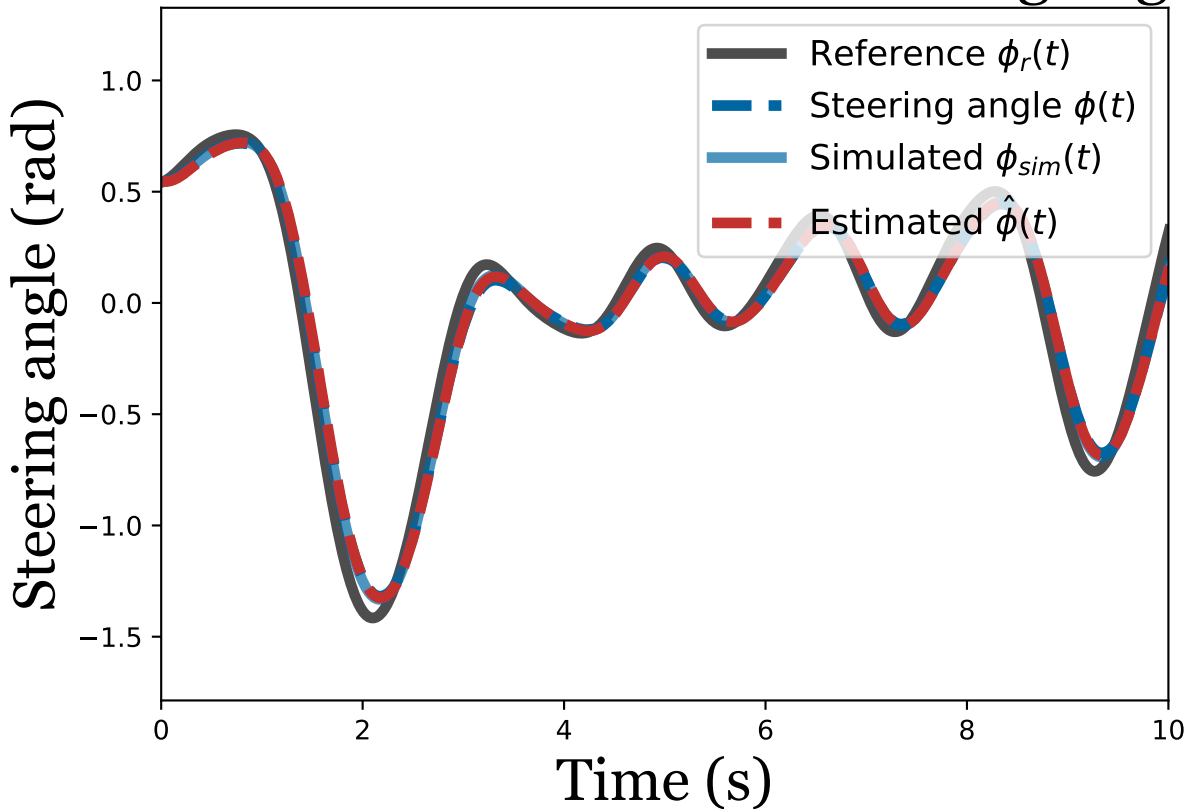
Reference trajectory in frequency domain



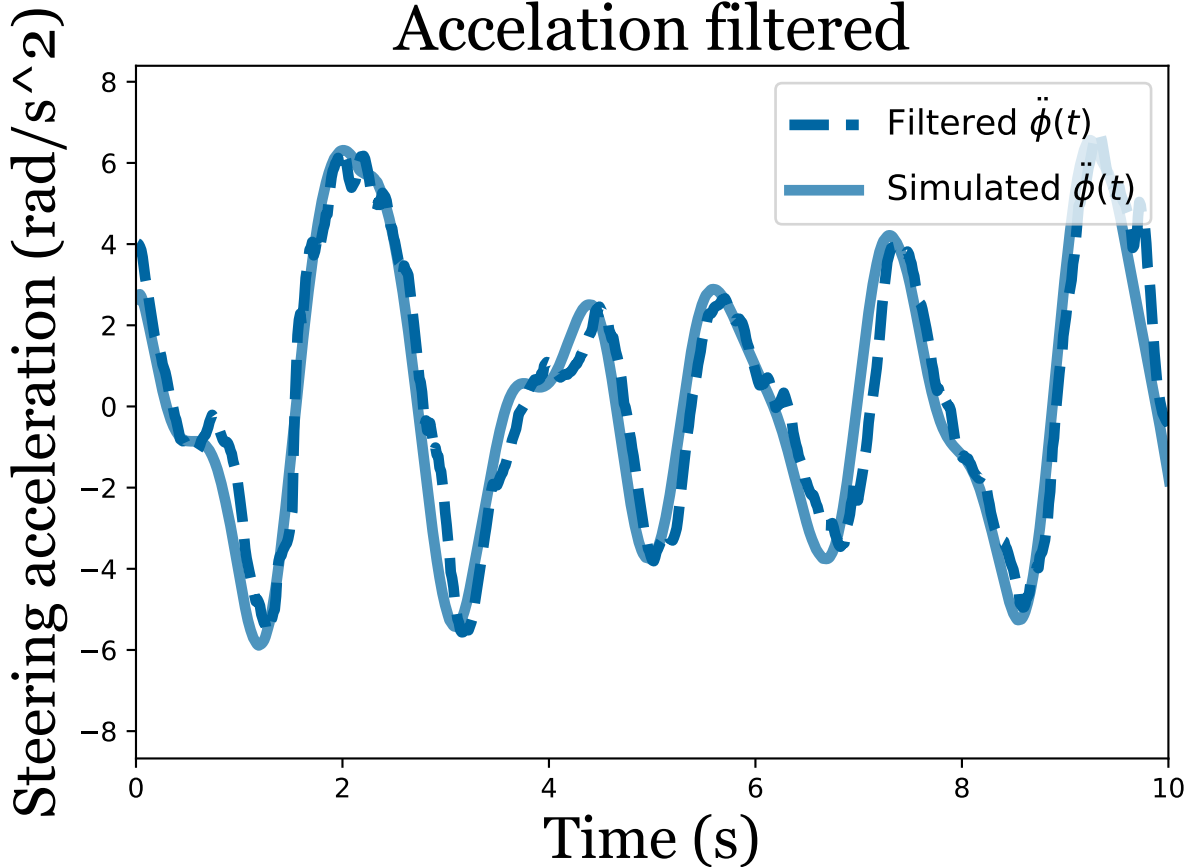
Reference trajectory in time domain



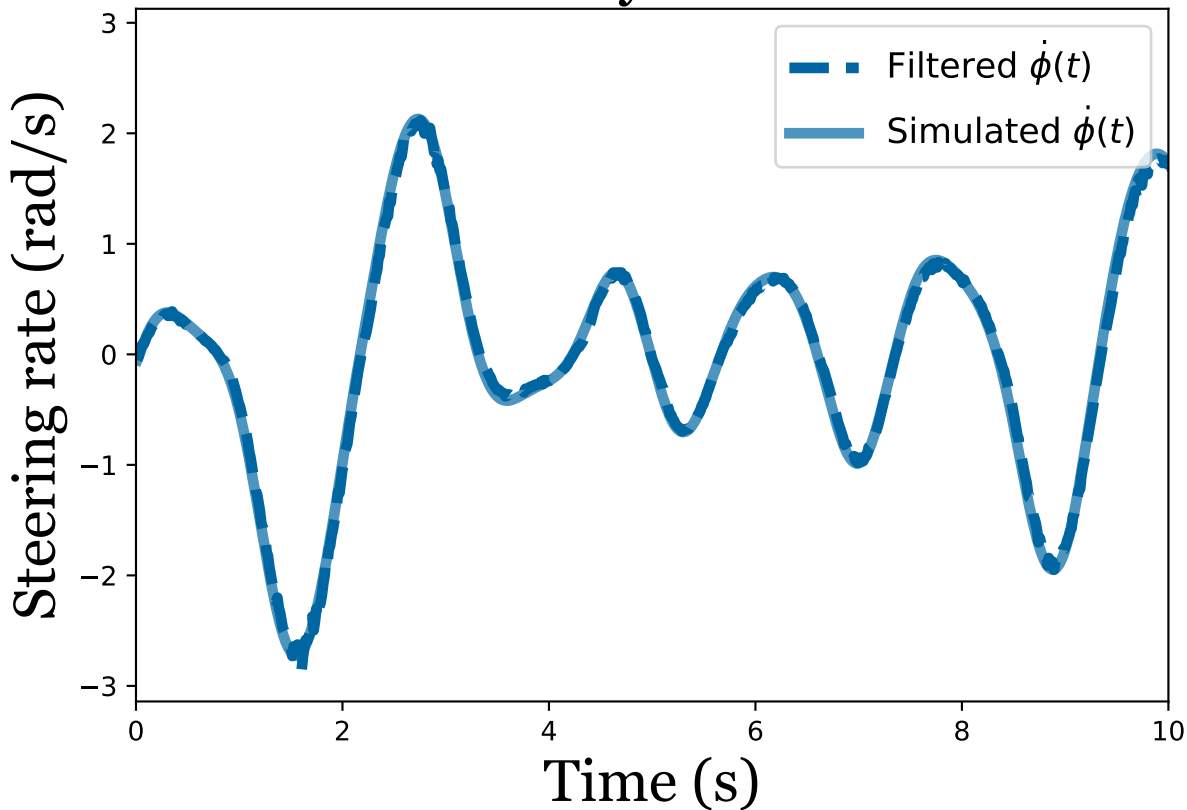
# Measured and estimated steering angle

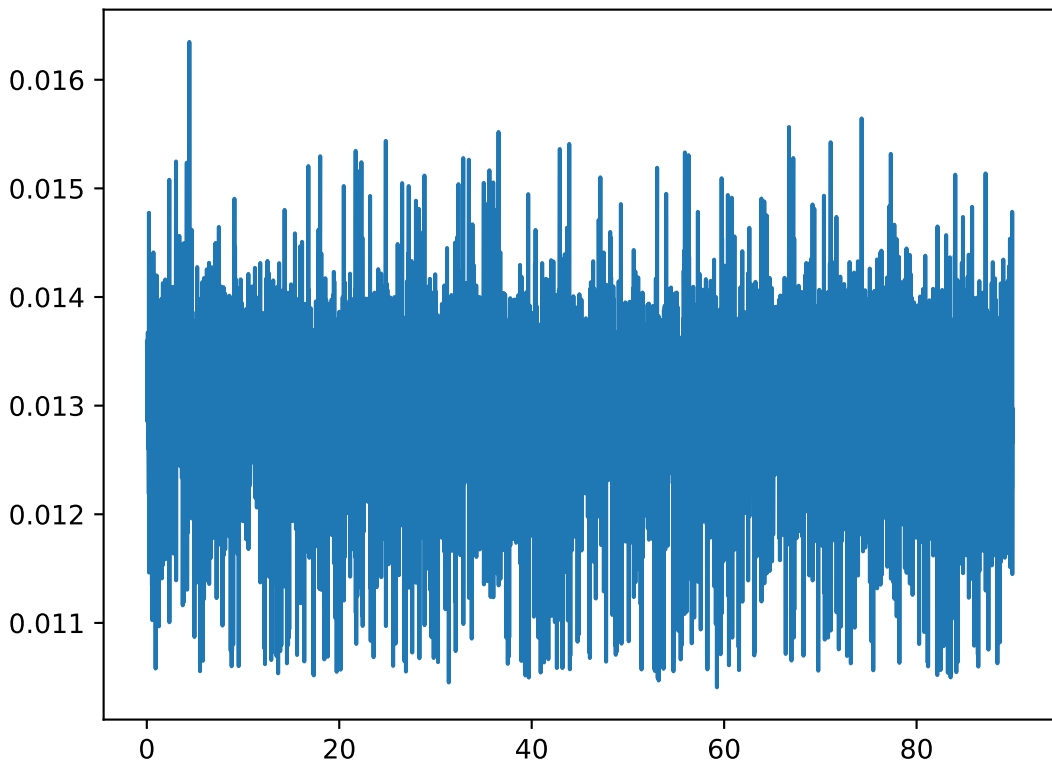


# Acceleration filtered



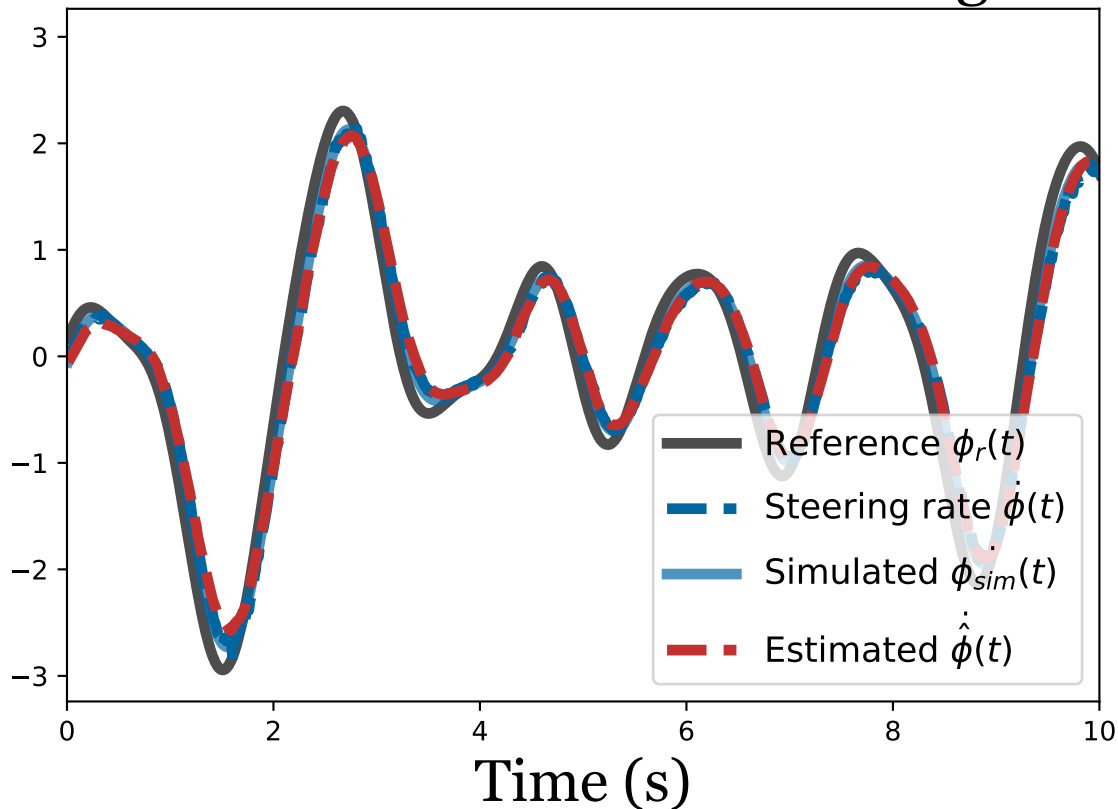
# velocity filtered



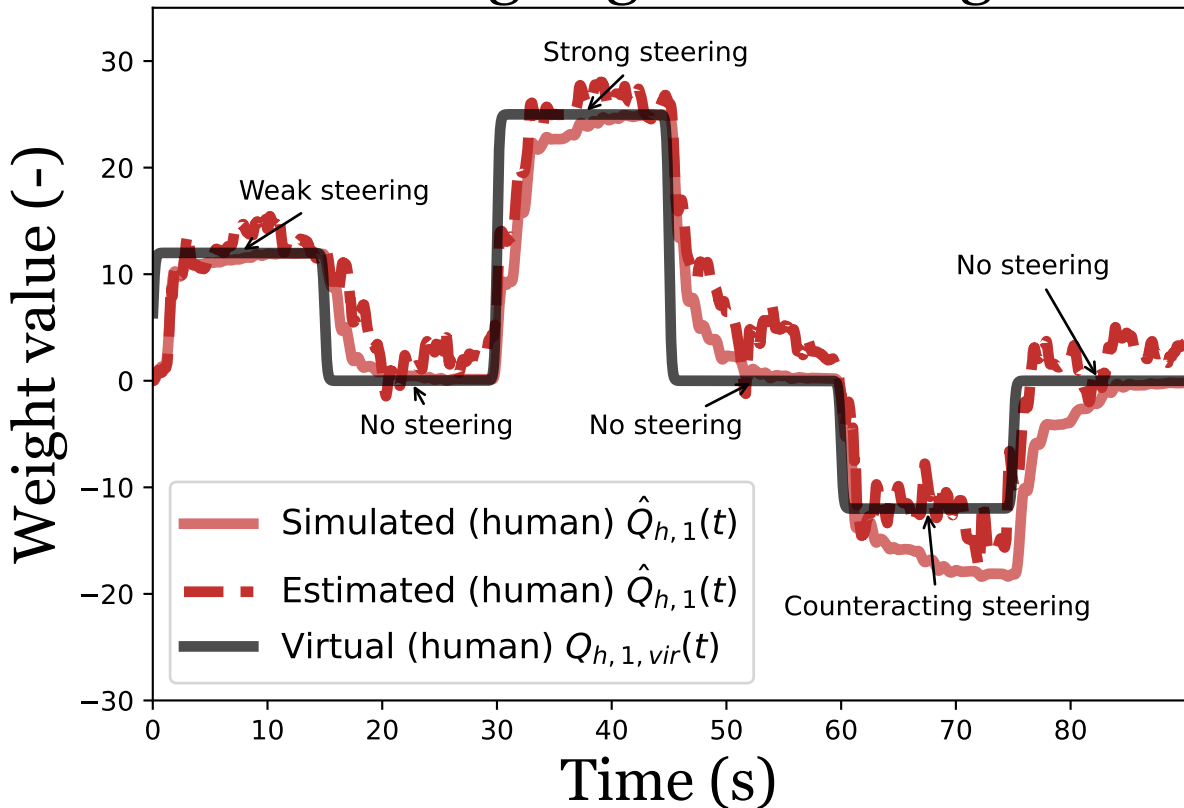


# Measured and estimated steering rate

Steering angle (rad)

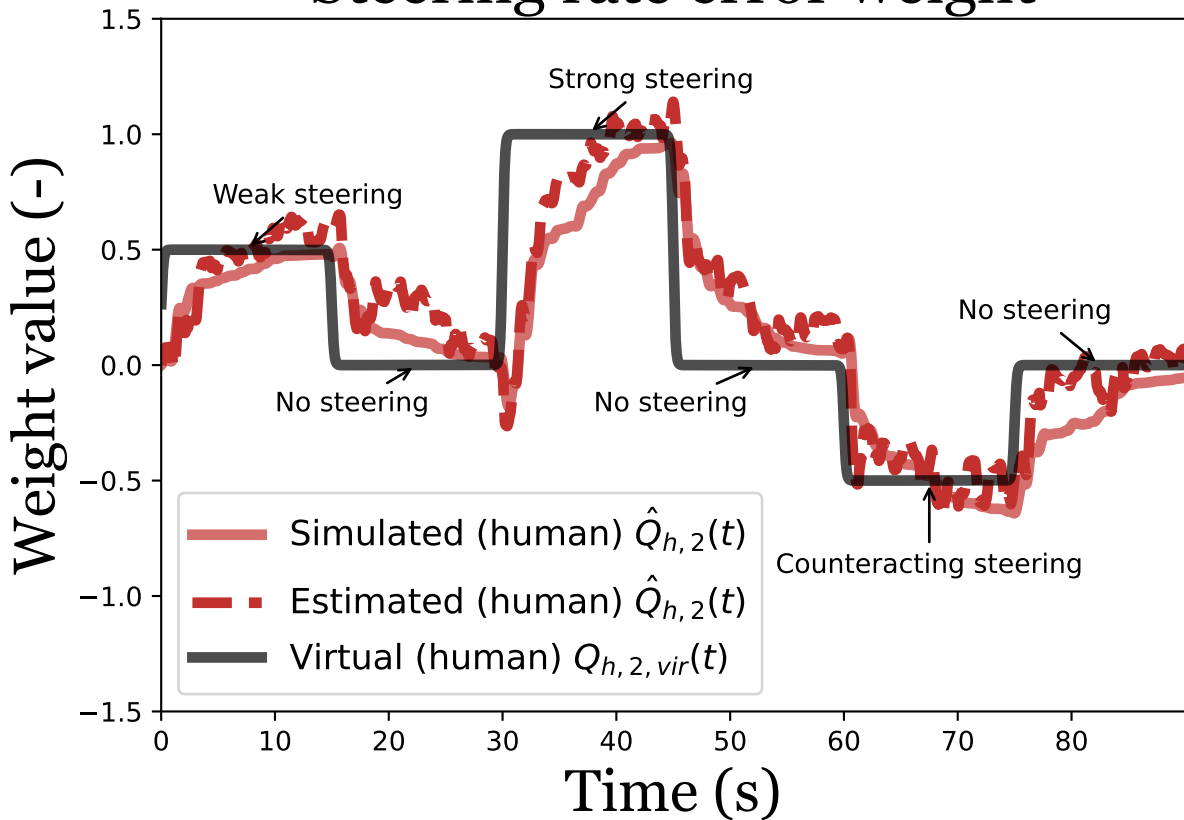


# Steering angle error weight

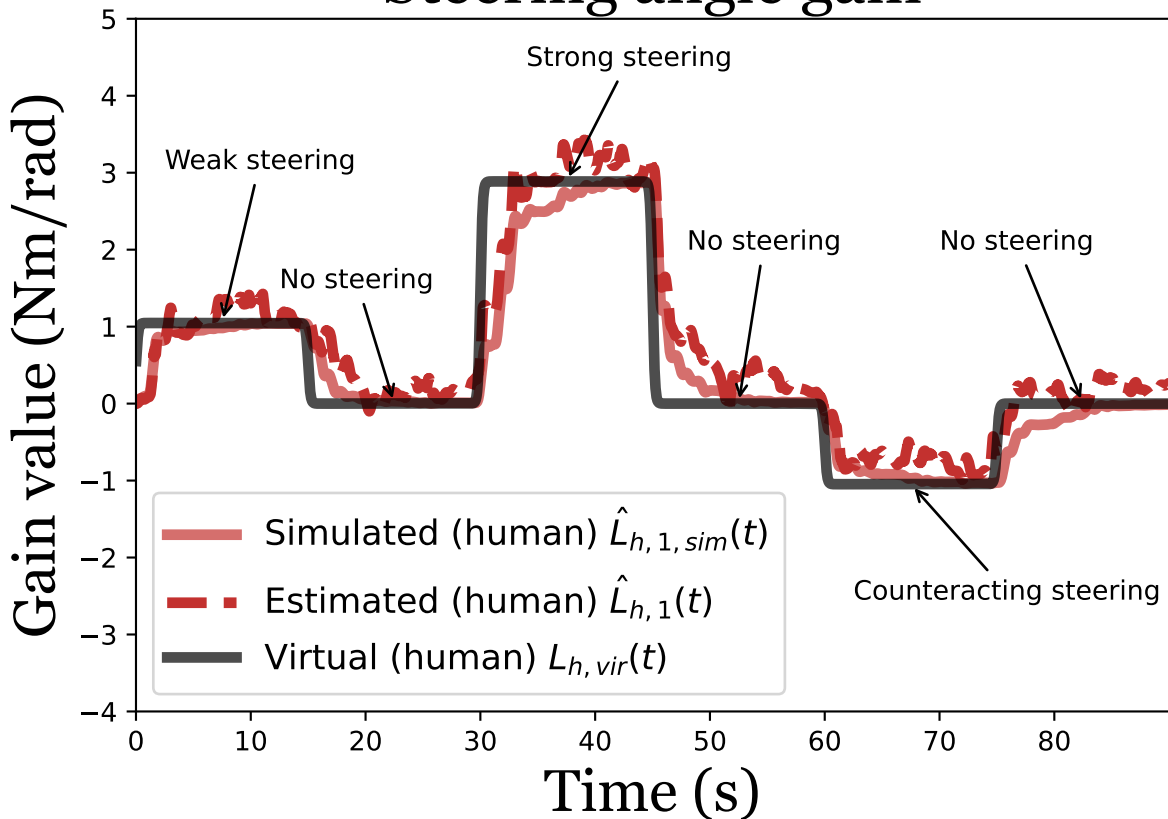




# Steering rate error weight

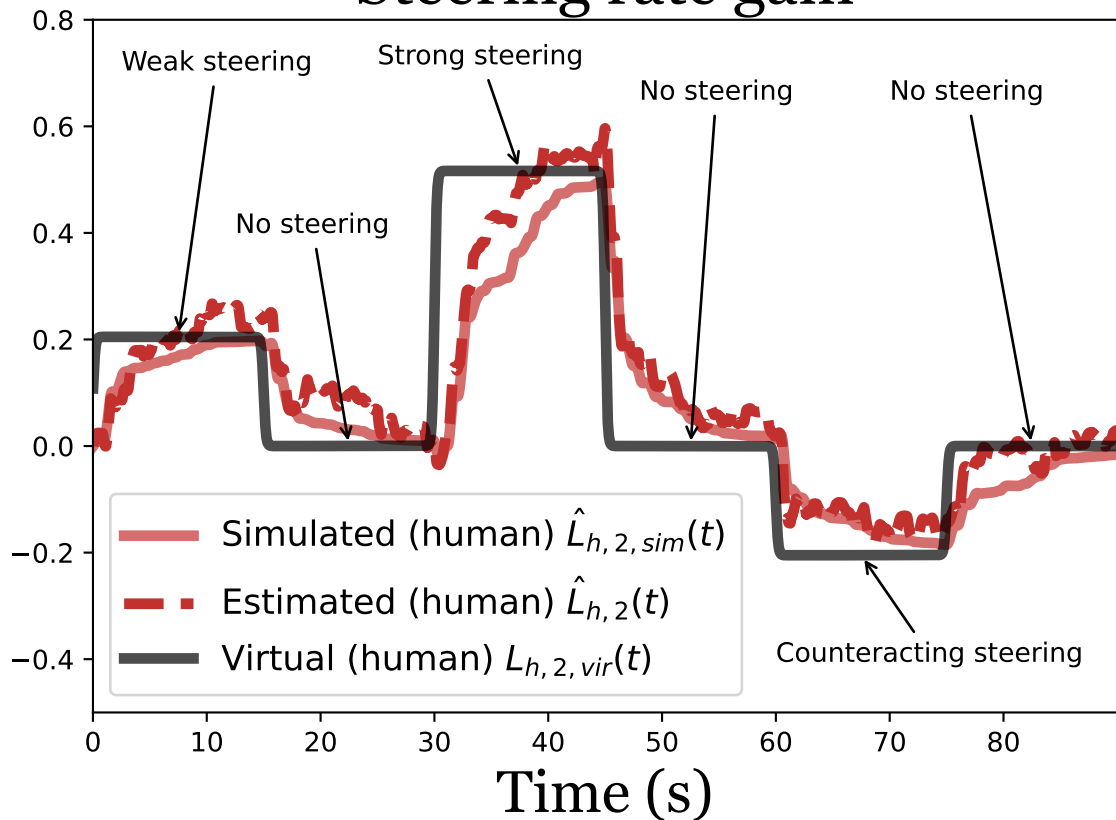


# Steering angle gain

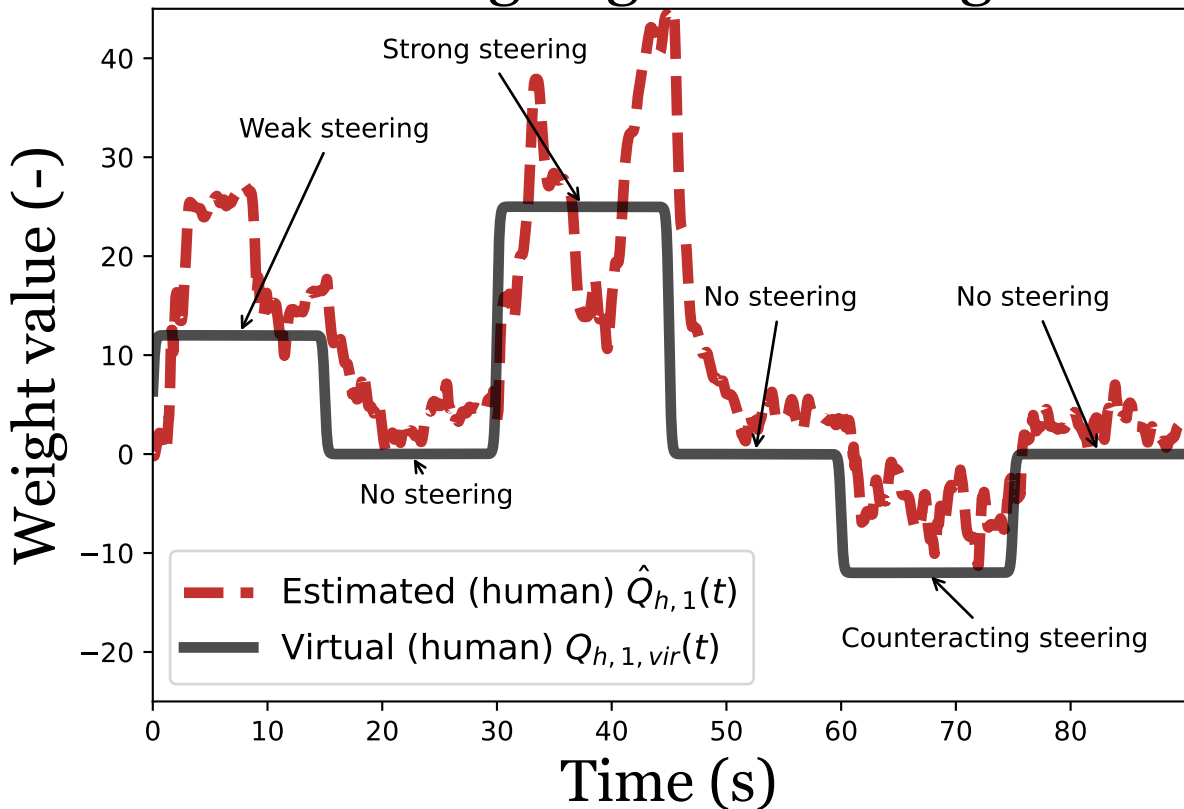


# Steering rate gain

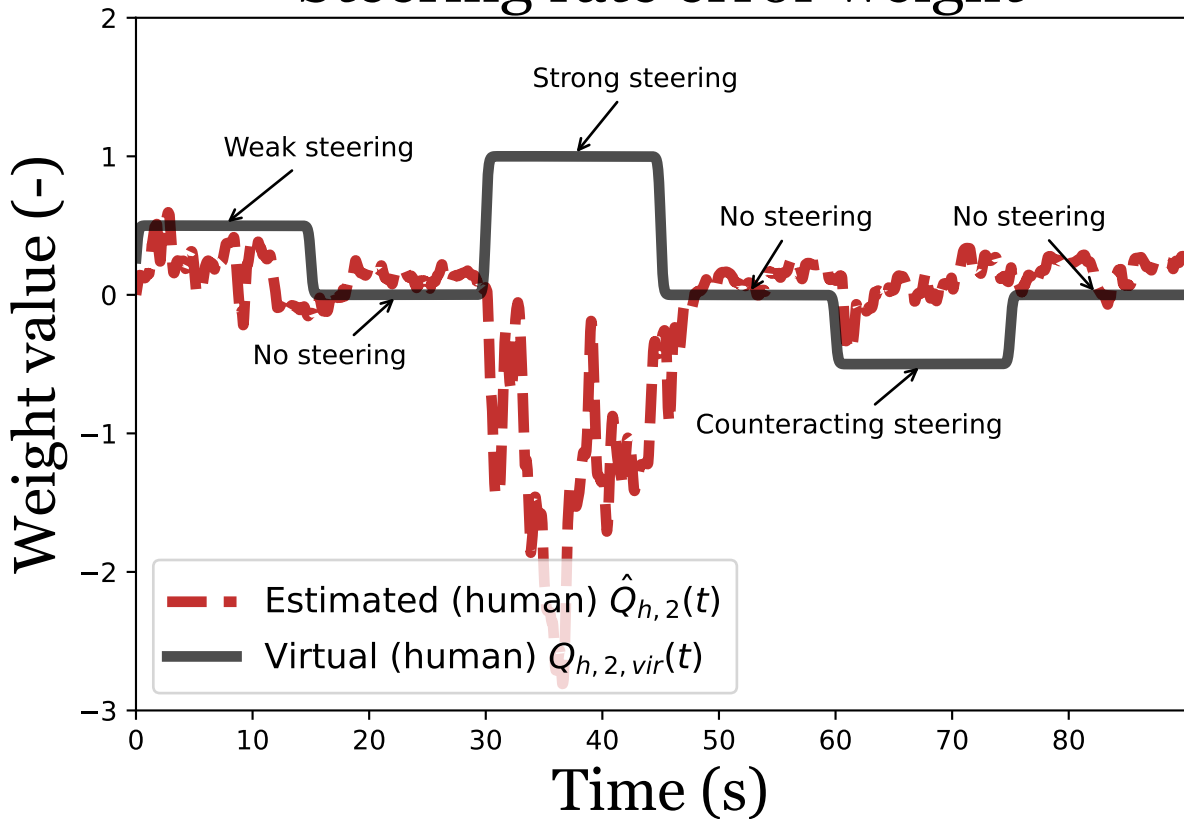
Gain value (Nms/rad)



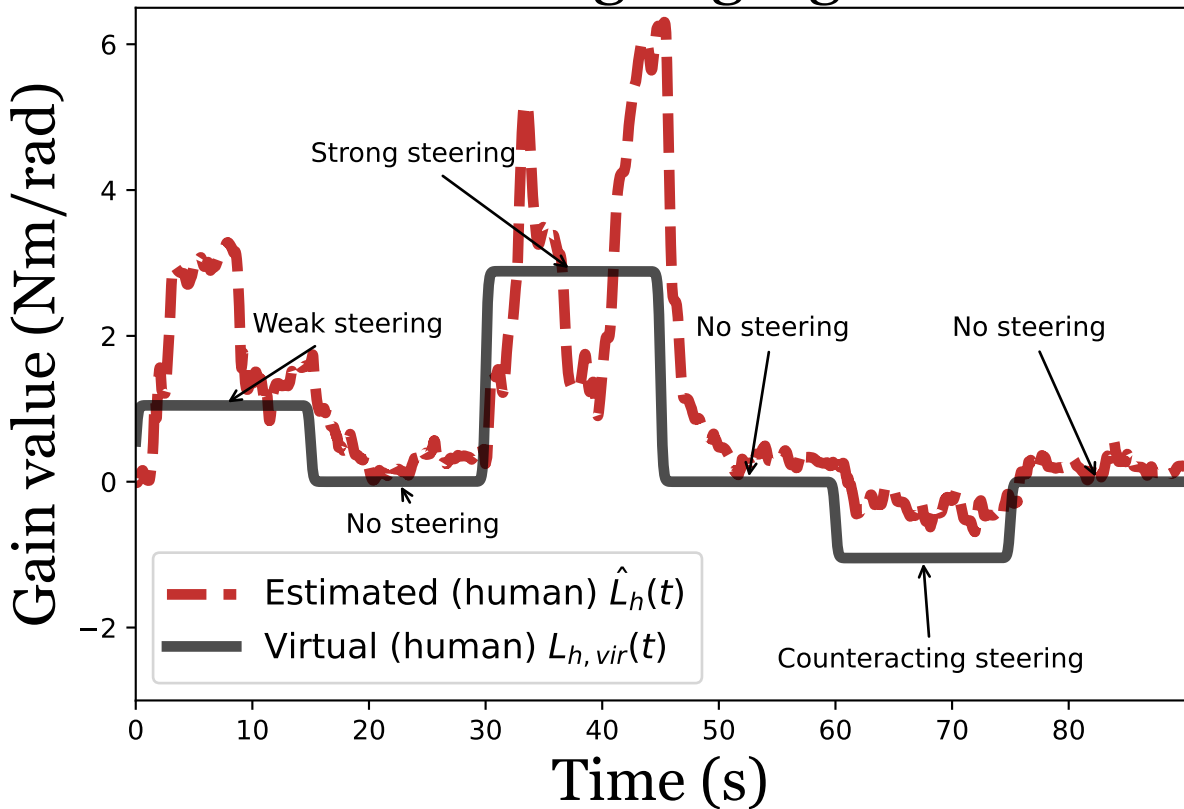
# Steering angle error weight



# Steering rate error weight



# Steering angle gain



# Steering rate gain

