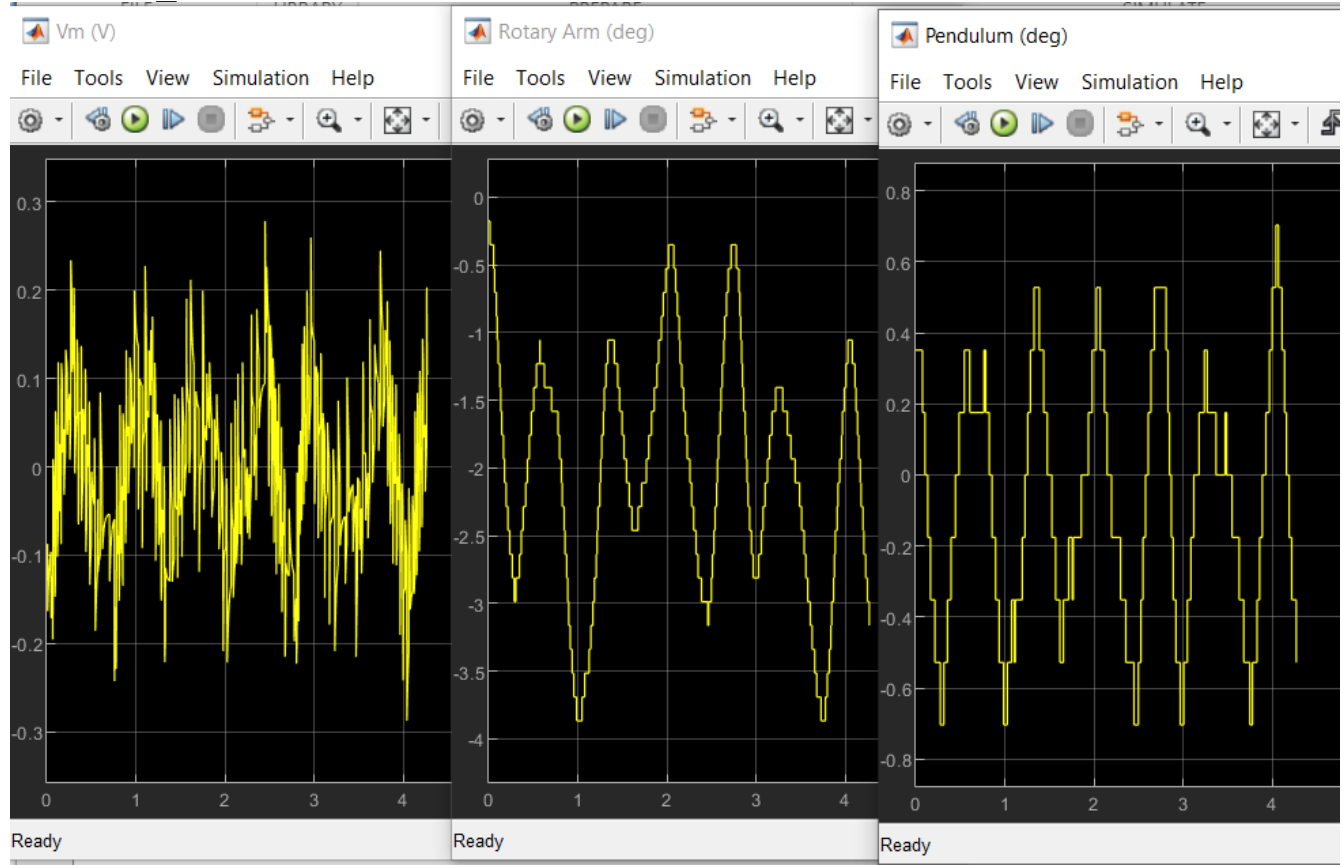


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SF:

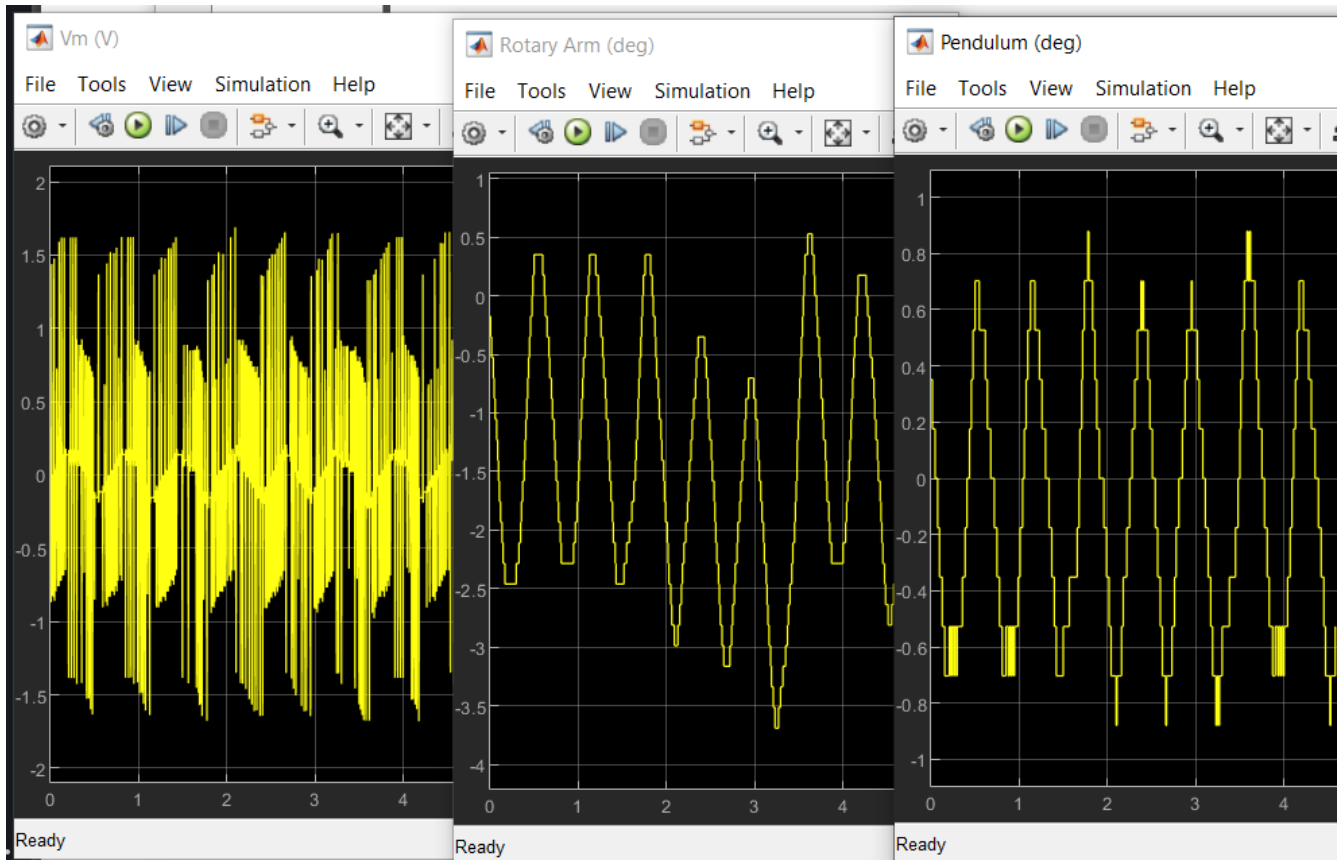
```
polevec K = [-20 -40 -1.5-.1500j -1.500+.1500j];
```



SF with observer:

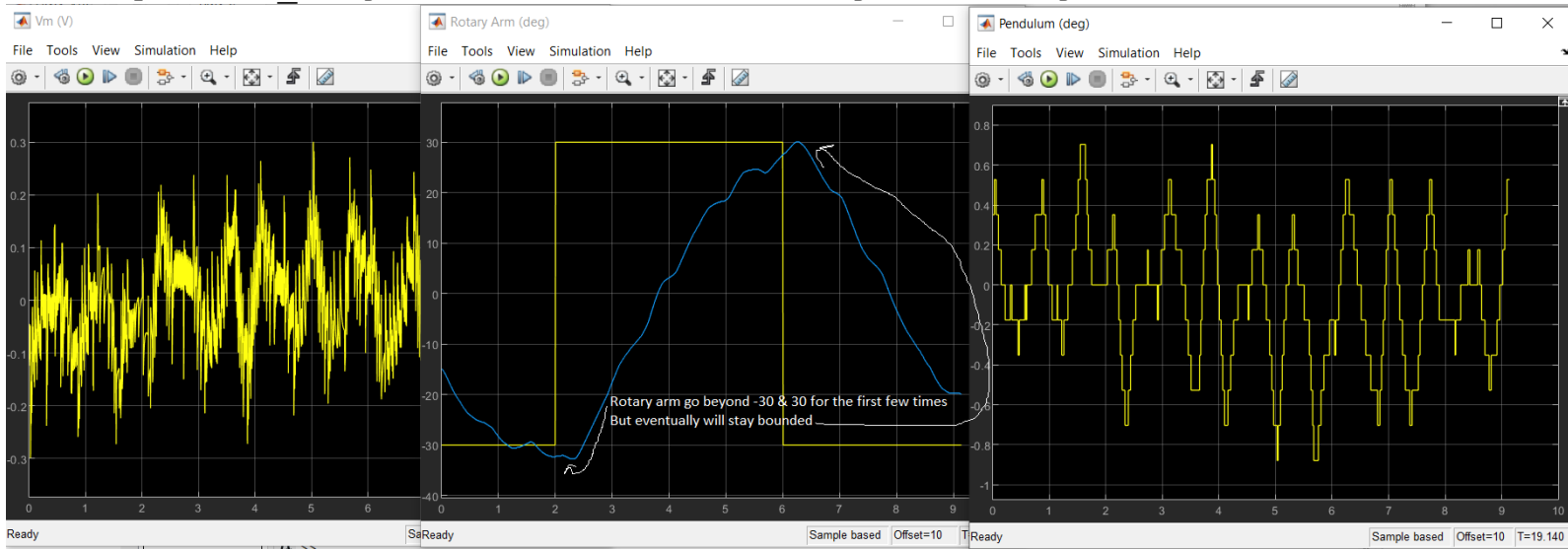
```
polevec_K = [-20 -40 -1.5-.1500j -1.500+.1500j];
```

```
polevec_L = [-500 -501 -502 -503];
```



Servo:

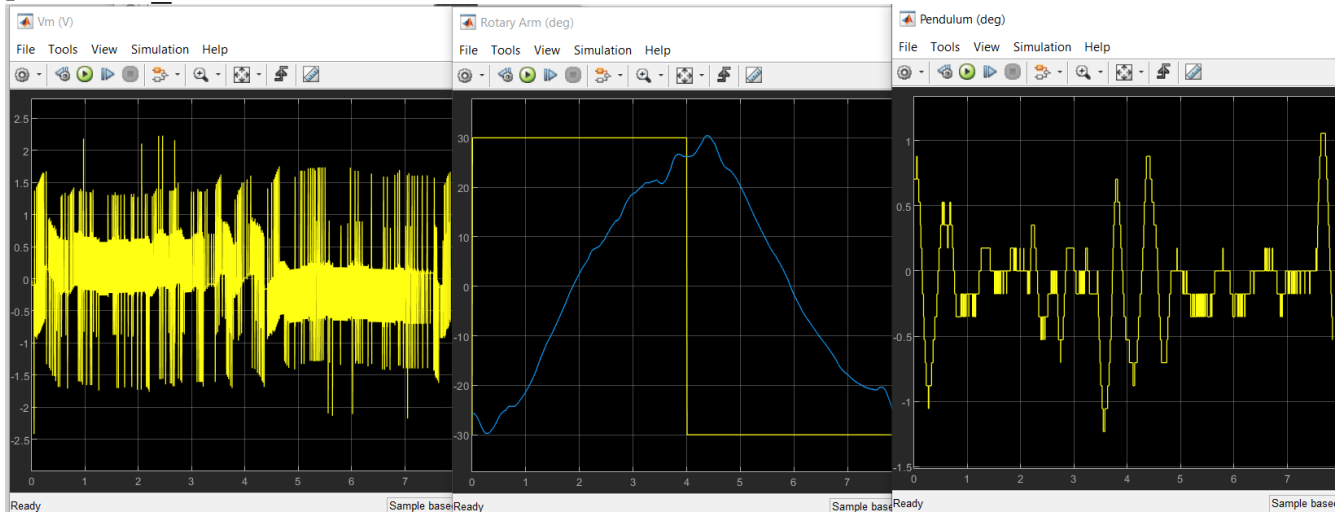
```
polevec_Kaug = [-15 -10 -5 -1.5-.15j -1.5+.15j];
```



Servo with observer:

```
polevec_Kaug = [-15 -10 -5 -1.5-.15j -1.5+.15j];
```

```
polevec_L = [-500 -501 -502 -503];
```



Similar with previous answer, where rotary arm starts out going beyond 30 & -30 deg limit, but eventually stays bounded.