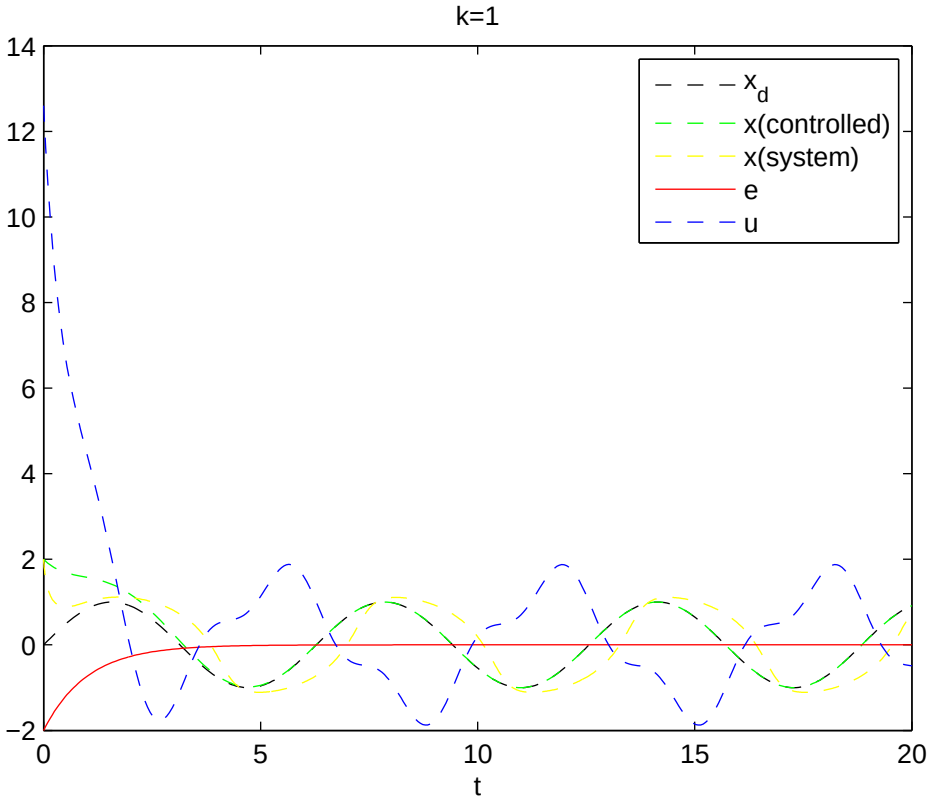
k=1
14
12
10
8
6
4
2
0
−2
0
5
10
15
20
t
x_d
x(controlled)
x(system)
e
u