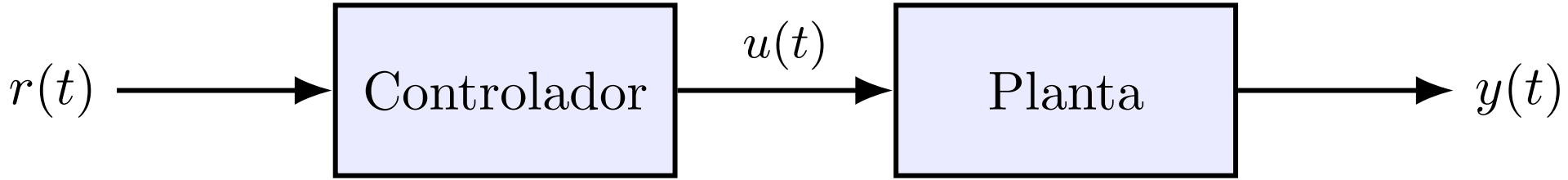
$r(t)$
Controlador
$u(t)$
Planta
$y(t)$