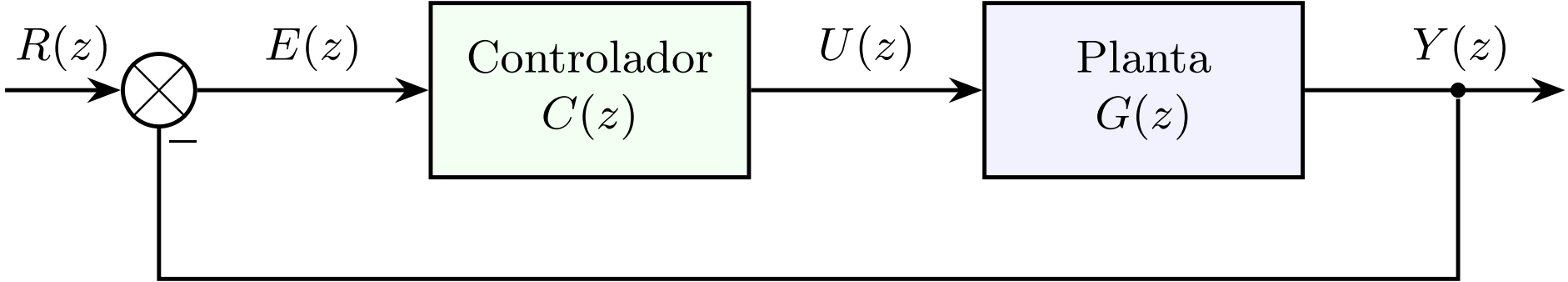
$R(z)$
$E(z)$
Controlador
$C(z)$
$U(z)$
Planta
$G(z)$
$Y(z)$
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