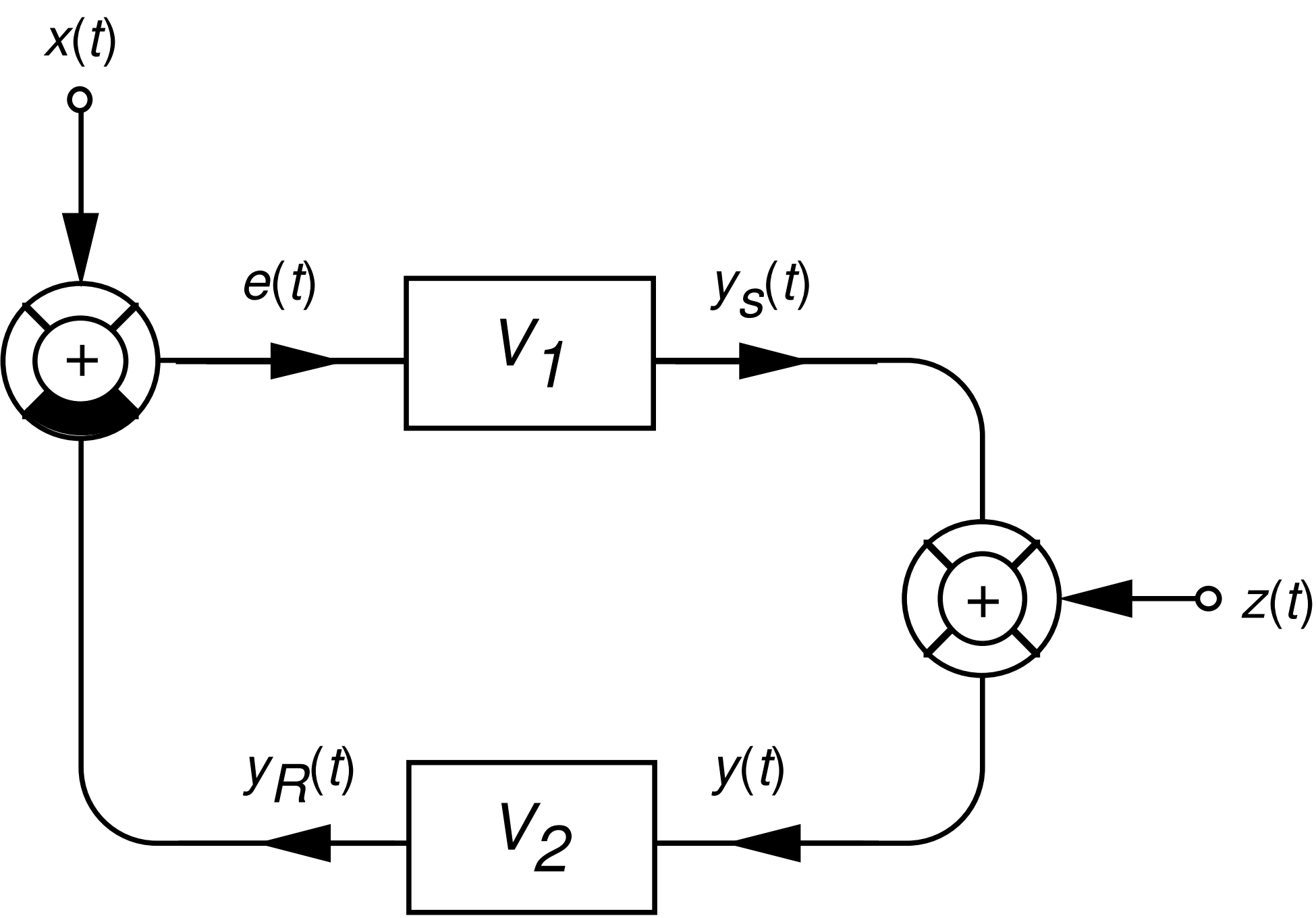
x(t)
e(t)
V1
ys(t)
+
+
z(t)
yR(t)
V2
y(t)