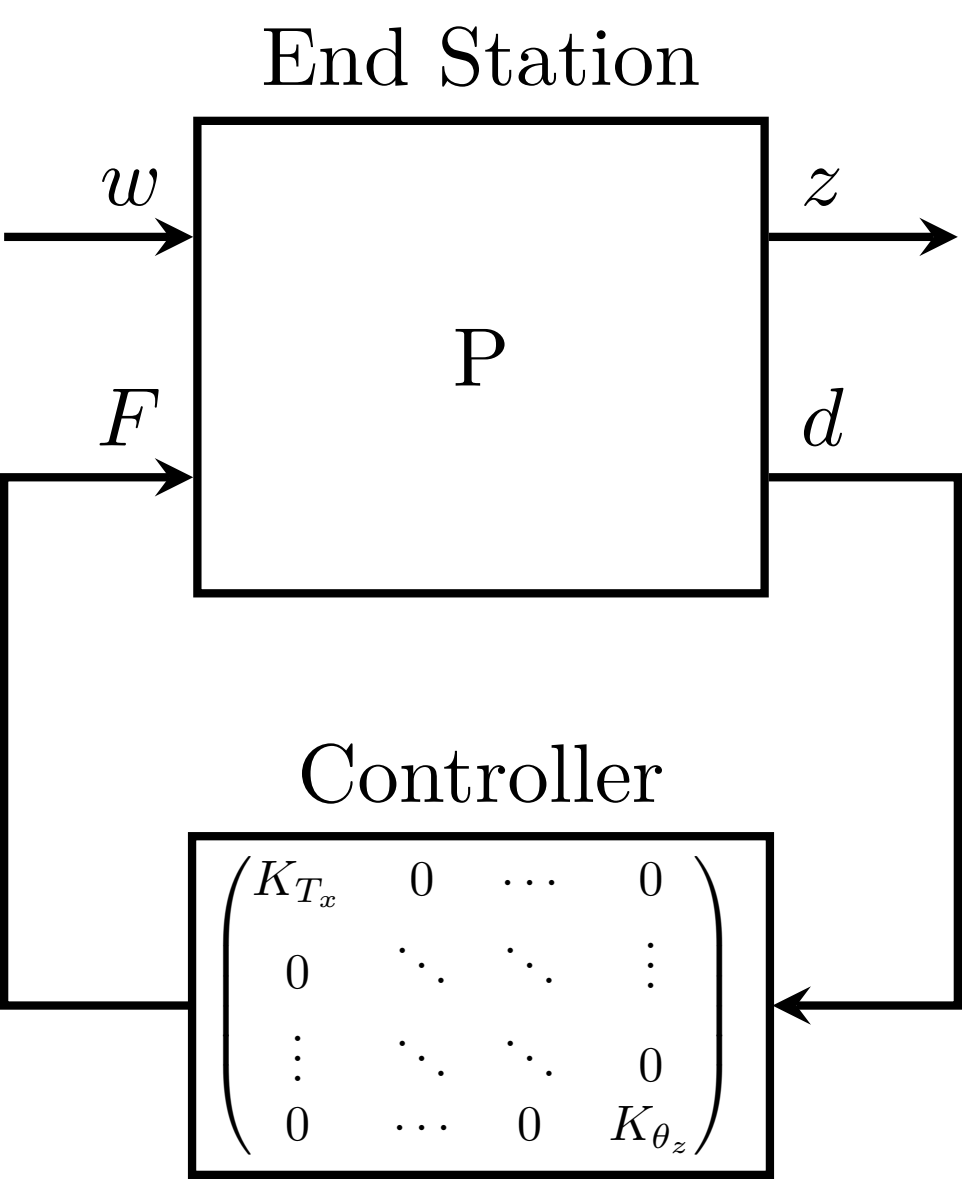
End Station
w
z
P
F
d
Controller
$\begin{pmatrix} K_{T_x} & 0 & \cdots & 0 \\ 0 & \ddots & \ddots & \vdots \\ \vdots & \ddots & \ddots & 0 \\ 0 & \cdots & 0 & K_{\theta_z} \end{pmatrix}$