

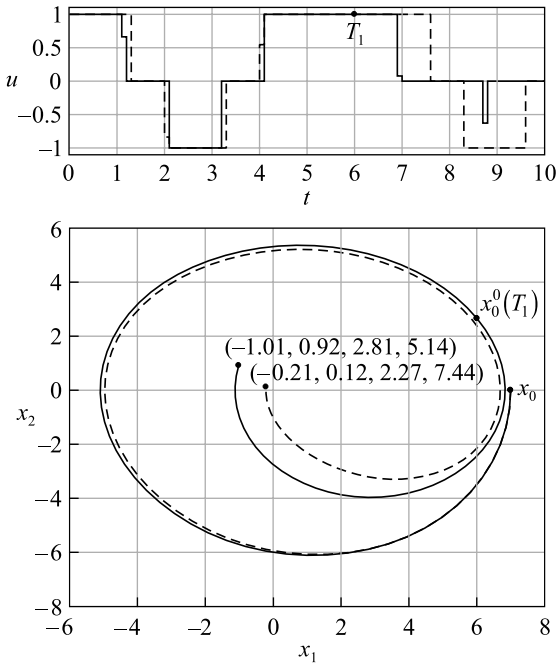


Fig. 4. Optimal control and trajectories in example 2 under the worst-case disturbance $w^*(\cdot)$