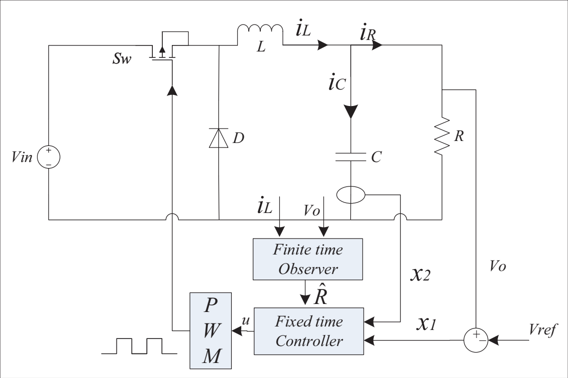
Sw
L
i_L
i_R
i_C
D
Vin
C
R
i_L
Vo
Finite time Observer
x_2
Vo
$\hat{R}$
P
W
M
u
Fixed time Controller
x_1
Vref