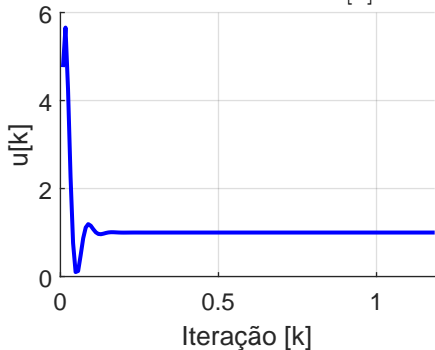
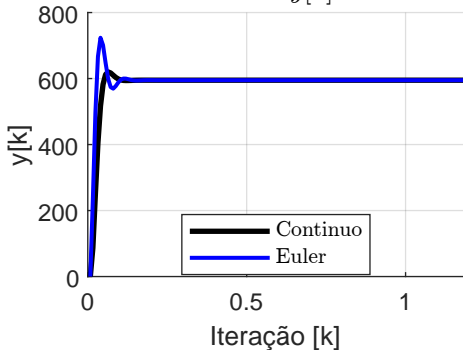


# Análise do controlador ( $Q = 1, R = 1$ )

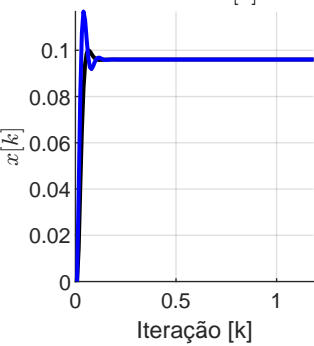
Sinal de Controle  $u[k]$



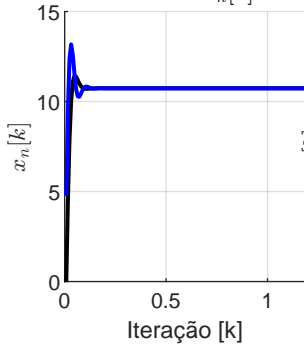
Saida  $y[k]$



Estado:  $x[k]$



Estado:  $x_n[k]$



Erro  $e[k]$

