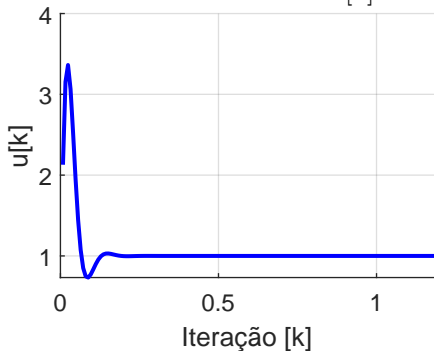
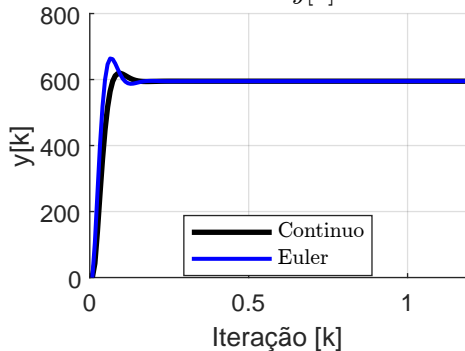


# Análise do controlador ( $Q = 0.1, R = 0.5$ )

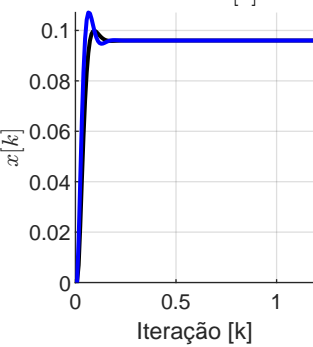
Sinal de Controle  $u[k]$



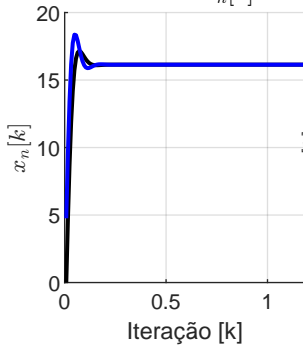
Saida  $y[k]$



Estado:  $x[k]$



Estado:  $x_n[k]$



Erro  $e[k]$

