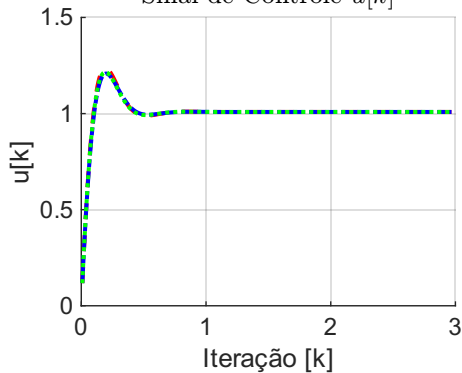
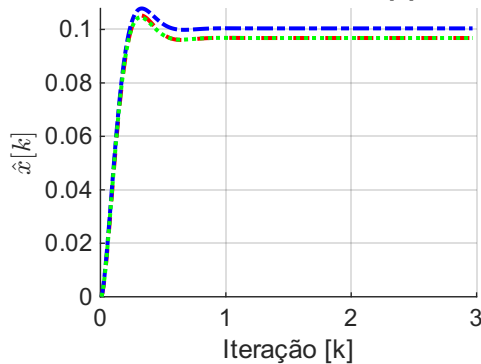
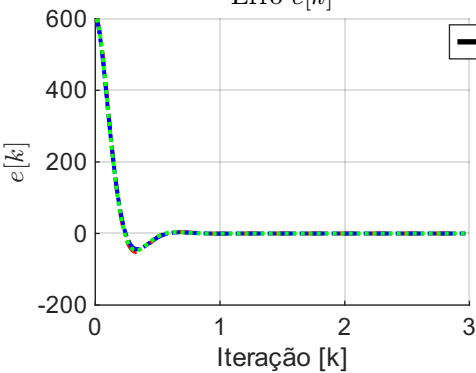


Sinal de Controle  $u[k]$ Estado observado  $\hat{x}[k]$ Erro  $e[k]$ Saída  $y[k]$ 