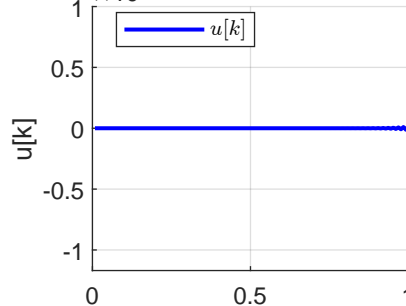
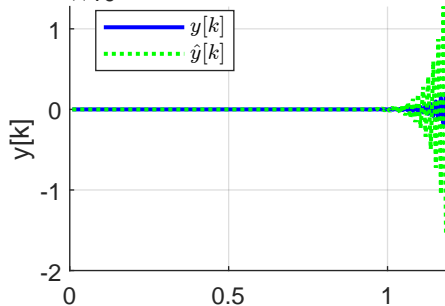


Análise do Observador (Kalman): ( $L_k = 0.043$ ,  $Q_k = 0.1$ ,  $R_k = 50$ )

Sinal de Controle  $u[k]$

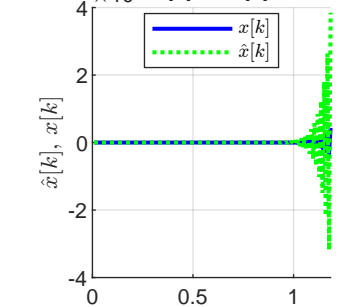


Saída  $y[k]$



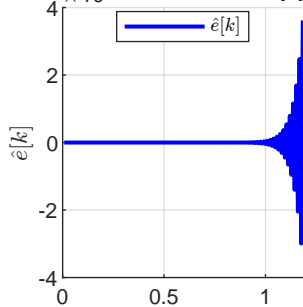
Iteração  $[k]$

$\times 10^9$   $\hat{x}[k]$  vs  $x[k]$



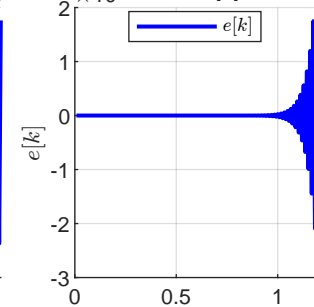
Iteração  $[k]$

Erro de estimativa:  $\hat{e}[k]$



Iteração  $[k]$

Erro  $e[k]$



Iteração  $[k]$