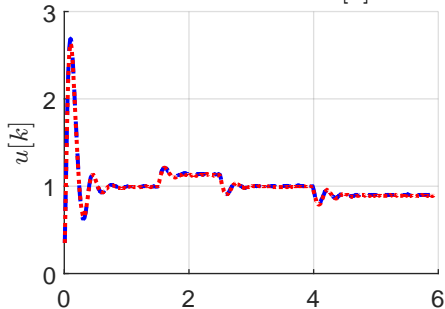
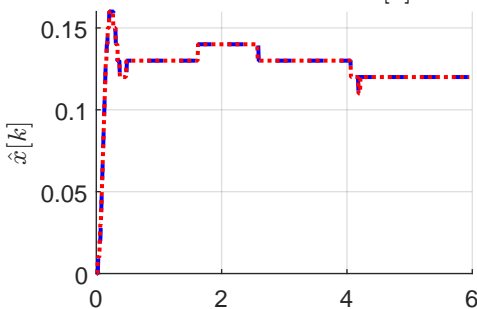


Análise do controlador ($Q_c = 0.1$, $R_c = 20$, $L_k = 0.208$)

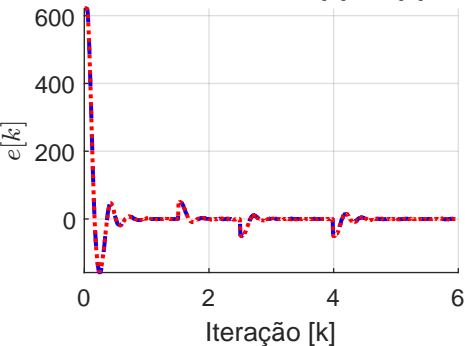
Saída estimada: $u[k]$



Estado estimado: $\hat{x}[k]$



Erro de rastreamento: $e[k] = r[k] - y[k]$



Saída: $y[k]$

