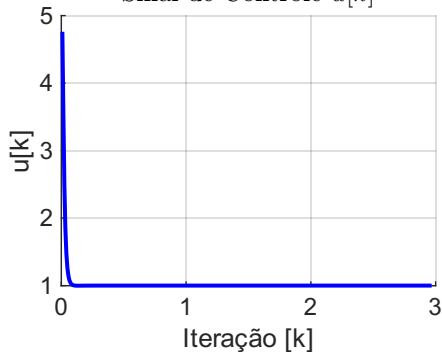
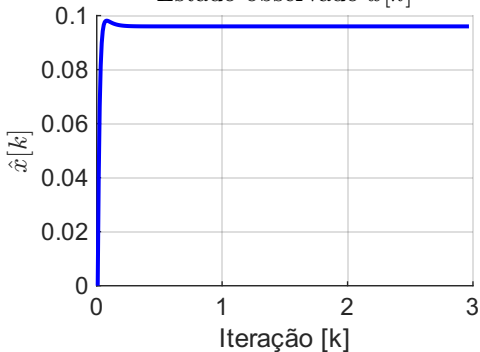


Análise do controlador

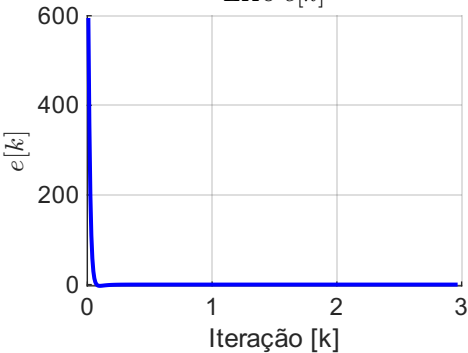
Sinal de Controle $u[k]$



Estado observado $\hat{x}[k]$



Erro $e[k]$



Saída $y[k]$

