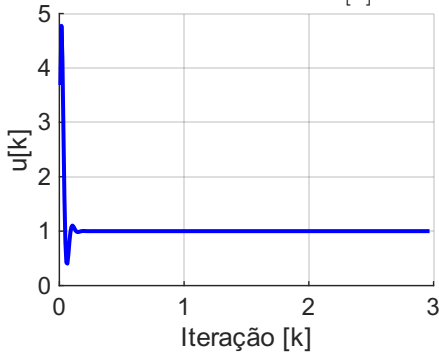
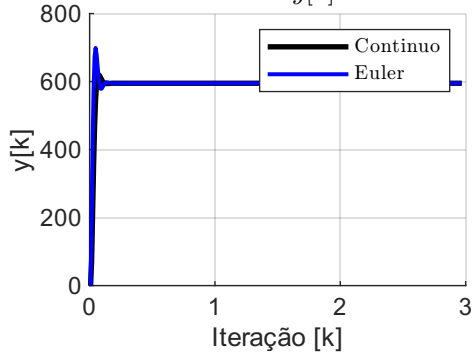


Análise do controlador ($Q = 1.2, R = 2$)

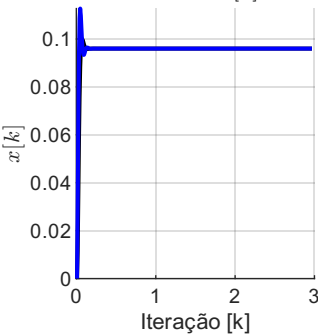
Sinal de Controle $u[k]$



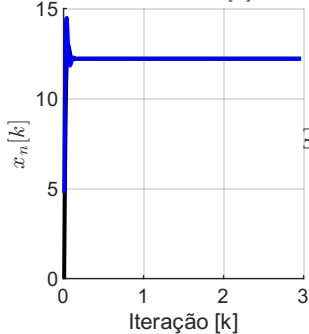
Saida $y[k]$



Estado: $x[k]$



Estado: $x_n[k]$



Erro $e[k]$

