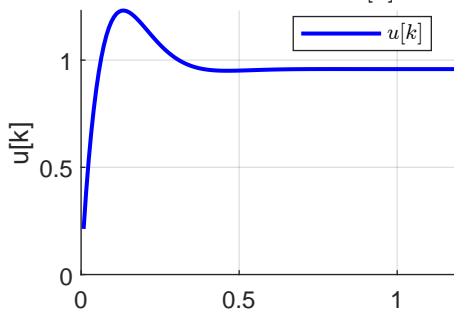
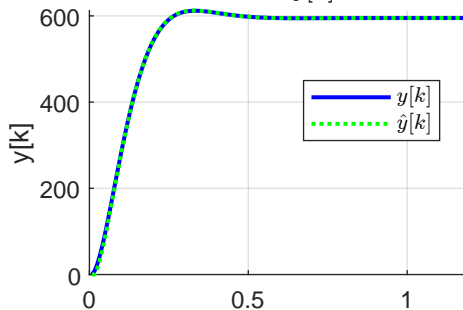


Análise do Observador (Kalman): ($L_k = 0.013$, $Q_k = 0.1$, $R_k = 500$)

Sinal de Controle $u[k]$



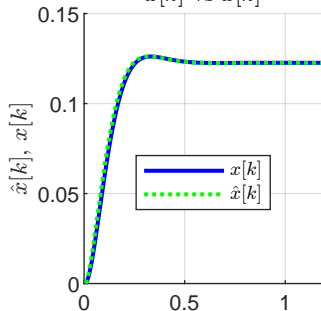
Saída $y[k]$



Iteração [k]

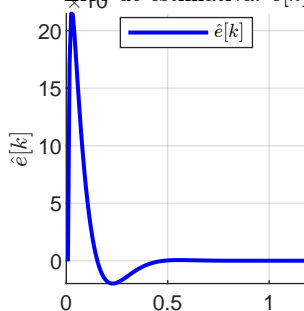
Iteração [k]

$\hat{x}[k]$ vs $x[k]$



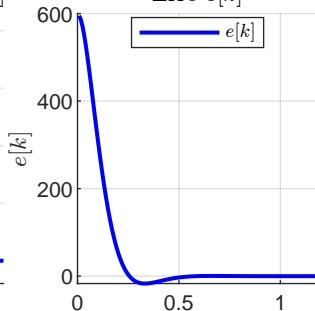
Iteração [k]

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



Iteração [k]

Erro $e[k]$



Iteração [k]