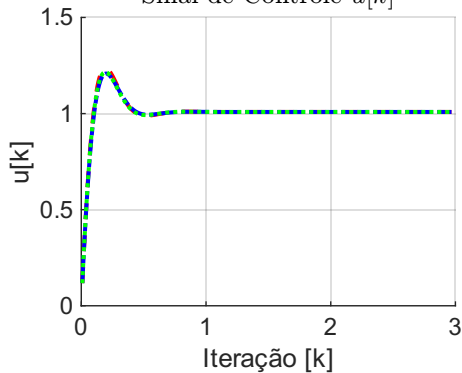
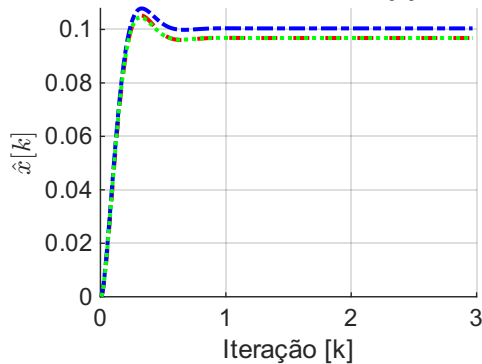
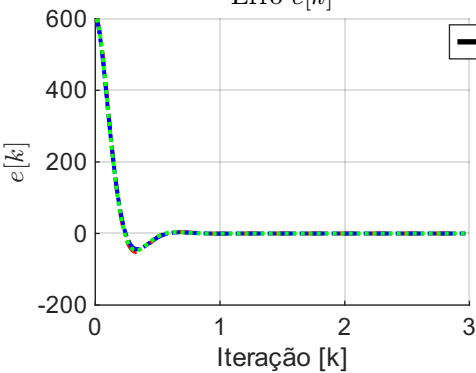


Sinal de Controle $u[k]$ Estado observado $\hat{x}[k]$ Erro $e[k]$ Saída $y[k]$ 