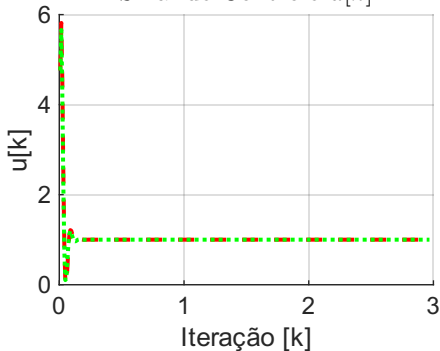
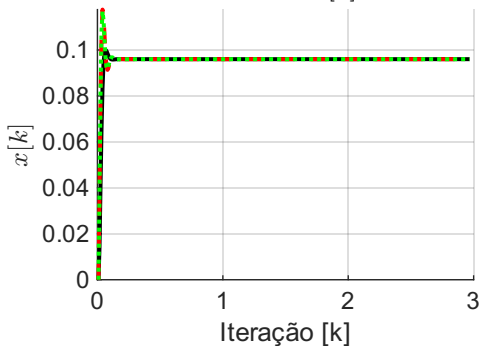


Análise do controlador (sem observador)

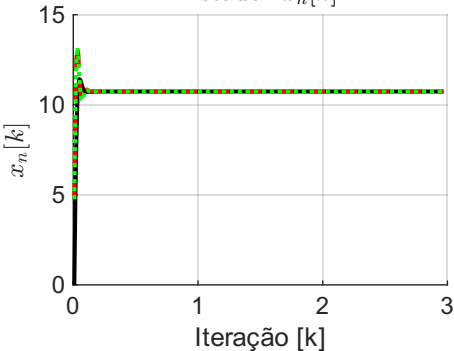
Sinal de Controle $u[k]$



Estado: $x[k]$



Estado: $x_n[k]$



Saida $y[k]$

