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Such a discrete-time control system consists of four major parts: 1 The Plant which is a continuous-time dynamic system. 2 The Analog-to-Digital Converter (ADC). 3 The Controller (μP), a microprocessor with a “real-time” OS. 4 The Digital-to-Analog Converter (DAC). 3 + ? $r(t)$ $e(t)$ ADC μP DAC $u(t)$ Plant ? ? $y(t)$ 4

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$d[n]=a[n]?3a[n ? 1]+3a[n ? 2]?a[n ? 3]$ is equivalent to this set of equations: $d[n]=c[n]?c[n ? 1]$ $c[n]=b[n]?b[n ? 1]$ $b[n]=a[n]?a[n ? 1]$. As the r st step, use the last equation to eliminate $b[n]$ and $b[n ? 1]$ from the $c[n]$ equation: $c[n]=(a[n]?a[n ? 1])?(a[n ? 1]?a[n ? 2]) = a[n]?2a[n?1]+a[n?2]$.

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TU Berlin Discrete-Time Control Systems 4 Solution for the last system: $x-[k] = kx-[0]$ If it is possible to diagonalize then the solution is a combination of k i terms, where k i; $i = 1;:::;n$ are the eigenvalues of . If it is not possible to diagonalize then the solution is a linear combination of the terms p i(k) k i where p

Analysis of Discrete-Time Systems

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For Theorem 3, P i (? i ? ?) is the positive definite symmetry solution of the following discrete time algebraic Rccati equation (40) A i T P i A i ? P i + Q ? A i T P i B i (B i T P i B i + R) ? 1 B i T P i A i = 0 and the optimal control input (41) u (t) = ? 1 2 (B i T P i B i + R) ? 1 B i T P i A i x (t) and for Theorem 4, P i (? i ? ?) is the positive definite symmetry solution of the following discrete time algebraic Rccati equation (42) A i T P i A i ? P i + Q i ...

Optimal control of discrete-time switched linear systems ...

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Ogata K. Discrete-Time Control Systems 2nd ed. (PH, 1995)(0133286428)

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Both time-discrete feedback controls and digital filters are described by their z-transform transfer functions. If a time-discrete system with the transfer function $H(z)$ receives a sinusoidal input sequence $x_k = \sin(?kT)$, the output signal is also a discrete approximation of a sinusoid.