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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 first 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 $k_i; i = 1, \dots, n$ 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

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For Theorem 3, $P_i (\forall i \in \mathcal{J})$ is the positive definite symmetry solution of the following discrete time algebraic Riccati 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) $u_i(t) = - (B_i^T P_i B_i + R)^{-1} B_i^T P_i A_i x_i(t)$ and for Theorem 4, $P_i (\forall i \in \mathcal{J})$ is the positive definite symmetry solution of the following discrete time algebraic Riccati equation (42) $A_i^T P_i A_i - P_i + Q_i \dots$

Optimal control of discrete-time switched linear systems

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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 $x_k = \sin(\omega kT)$, the output signal is also a discrete approximation of a sinusoid.