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d[n]=a[n]3a[n Æ 1]+3a[n Æ 2]a[n Æ 3] is equivalent to this set of equations: d[n]=c[n]c[n Æ 1] c[n]=b[n]b[n Æ 1] b[n]=a[n]a[n Æ 1]. As the Ærst step, use the last equation to eliminate b[n] and b[n Æ 1] from the c[n] equation: c[n]=(a[n]a[n Æ 1])Æ(a[n Æ 1]a[n Æ 2]) = a[n]Æ2a[nÆ 1]+a[nÆ 2].

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

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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 xk = sin(ÆkT), the output signal is also a discrete approximation of a sinusoid.