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Gene F. Franklin 1991 Solutions Manual To Accompany Design Of Feedback Control  
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Response X 1 X 2 0 0.5 1 1.5 2 2.5 3 3.5 4 -15 -10 -5 0 5 Time (sec) U Control  
Step Response:  $U = N_{bar} R - Kx$   $U = N_{bar} R - Kx$  Figure 3: Response To Step Input With

The  $N^-$  Correction. Gives The Desired Steady- 2th, 2024Dynamic Programming Techniques For Feedback ControlOne Of The Main Appeals Of The Dynamic Programming Approach Resides In The Fact That The Optimal Control Can Be Determined In State Feedback Form  $F(x) = A^*(0)$  For A Horizon  $\Delta$  That Can Be Made As Small As Physically Mean-ingful (e.g., The Control Period For A Computer Controlled 3th, 2024.

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