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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 (µ P), a microprocessor with a " real-time " OS. 4 The Digital-to-Analog Converter (DAC). 3 + − r(t) e(t) ADC µ P 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 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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For Theorem 3, P i ($\forall$ i $\in$) 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 ($\forall$ i $\in$) 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 ...

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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(ω kT), the output signal is also a discrete approximation of a sinusoid.