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ing Control System Is Implemented Using An Analog Loop Around The Motor Velocity And A Digital Loop Around The Load Position. Defining The Output Of The System As $Y\{t\} = X,\{t\}$ (2.2) And Utilizing An Analog Feedback Control Around The Motor Velocity, $F\{t\}=Kv\{u(.t)-v,,,\{t\}\}$ (2.3) Where U Jan 6th, 2024

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What Does Discrete Mean? What Is Discrete Mathematics?

Computation And A Discrete Worldview Go Hand-in-hand. Computer Data Is Discrete (all Stored As Bits No Matter What The Data Is). Time On A Computer Occurs In Discrete Steps (clock Ticks), Etc. Because We Work Almost Solely With Discrete Values, It Makes Since That Jan 5th, 2024

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Data Points X_j . The Procedure For Deriving Coefficients Of Spline Interpolations Uses Information From All Data Points, I.e. Nonlocal Information To Guarantee Global Smoothness In The Interpolated Function Up To Some Order Of Derivatives. 33 Equations The Interpolated Function On May 2th, 2024

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Discrete -Time Fourier Transform • The DTFT Can Also Be Defined For A Certain Class Of Sequences Which Are Neither Absolutely Summable nor Square Summable • Examples Of Such Sequences Are The Unit Step Sequence $\mu[n]$, The Sinusoidal Sequence And The Feb 2th, 2024

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Input-Output (I/O) Stability -Stability Of A System

Note That If $G(s)$ Is Stable, Then By Parseval's Theorem, $\int_{-\infty}^{\infty} |G(j\omega)|^2 d\omega = \int_{-\infty}^{\infty} |g(t)|^2 dt$ (I.27) Theorem I.2 Assume That $G(s)$ Is Stable And Strictly Proper. Then, Its Typical Feb 7th, 2024

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