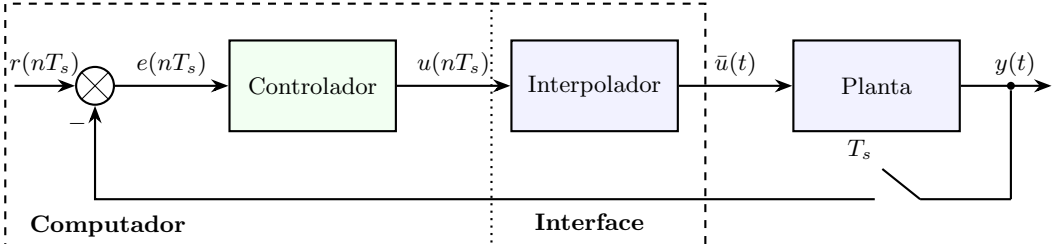
$r(nT_s)$
$e(nT_s)$
Controlador
$u(nT_s)$
Interpolador
$\bar{u}(t)$
Planta
$y(t)$
$-$
T_s
Computador
Interface