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 Control Full-state Feedback ...X State Step 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: $U=Nbar$ $R-Kx$ $U=Nbar$
 $R-Kx$ Figure 3: Response To Step Input With The N^- Correction. Gives The Desired
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 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 Δ
 That Can Be Made As Small As Physically Mean-ingful (e.g., The Control Period For A
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