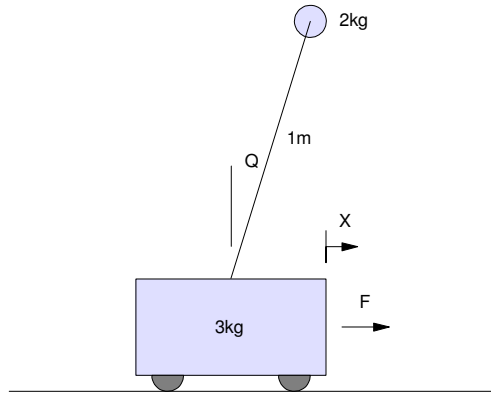


ECE 463/663 - Final Exam

Open book, open notes, internet & matlab permitted - just not other people.

Due Monday, May 11th

No Aid Given Received, or Observer (i.e. you did not get help from someone else) _____



Expand homework set #10 to include

- Two sensors (position and angle)
- Noise on both sensors, and
- A constant disturbance on the angle measurement (the angle it reports is slightly off)

$$s \begin{bmatrix} \dot{x} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & -6.533 & 0 & 0 \\ 0 & 16.333 & 0 & 0 \end{bmatrix} \begin{bmatrix} x \\ \theta \\ \dot{x} \\ \dot{\theta} \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0.333 \\ -0.333 \end{bmatrix} (F + n_u)$$

$$y_x = x + n_x \quad \text{position is measured with noise}$$

$$y_\theta = \theta + n_\theta + d \quad \text{angle is also measured, with a constant disturbance}$$

where there is Gaussian noise at the input and output

$$n_u \sim \mathcal{N}(0, 0.02^2) \quad \text{mean zero, standard deviation } 0.02$$

$$n_x \sim \mathcal{N}(0, 0.01^2) \quad \text{mean zero, standard deviation } 0.01$$

$$n_\theta \sim \mathcal{N}(0, 0.03^2) \quad \text{mean zero, standard deviation } 0.03$$

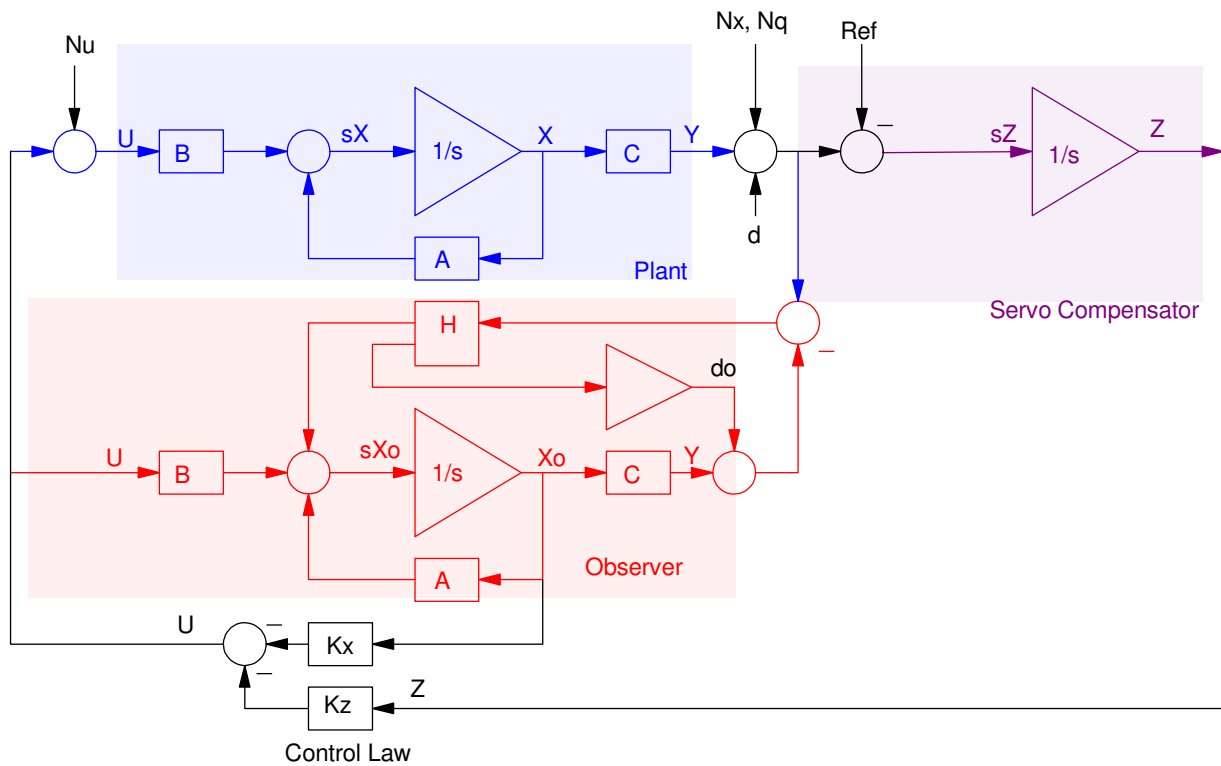
$$d \quad \text{constant disturbance (offset) on the measured angle}$$

- 1) Design a feedback control law so that the step response to position (x) has
 - No error for a step input,
 - A 2% settling time of 4 seconds
 - The overshoot for a step input is 5% or less

- 2) Design a Kalman filter to estimate the states and the constant disturbance using both position and angle

- 3) Simulate the step response of the linear system with $d = 0.1$ radian and
 - Without any noise, and
 - With noise

- 4) Simulate the step response of the nonlinear system with
 - the Kalman filter (full-order observer), and
 - A disturbance: $d = 0.1$ radian.



Bonus! (Over)

