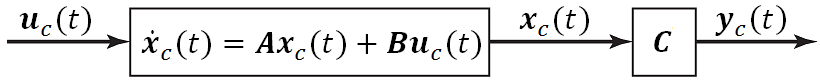
***Contents***

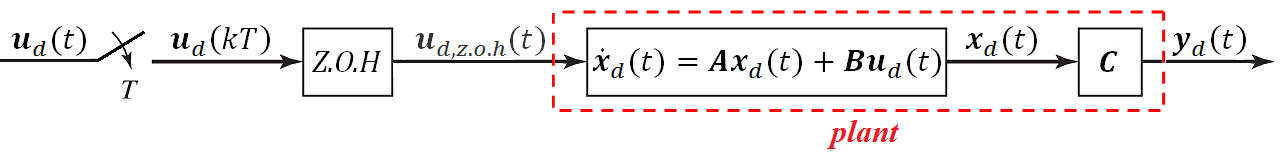
*Use* ***for-loop*** *to write a reference function*

***Open-loop system***

1. *Continuous-time system simulation*

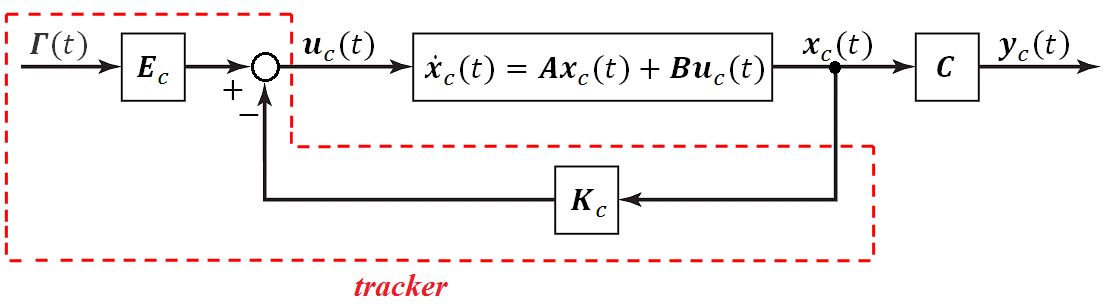
**

1. *Discrete-time system simulation*

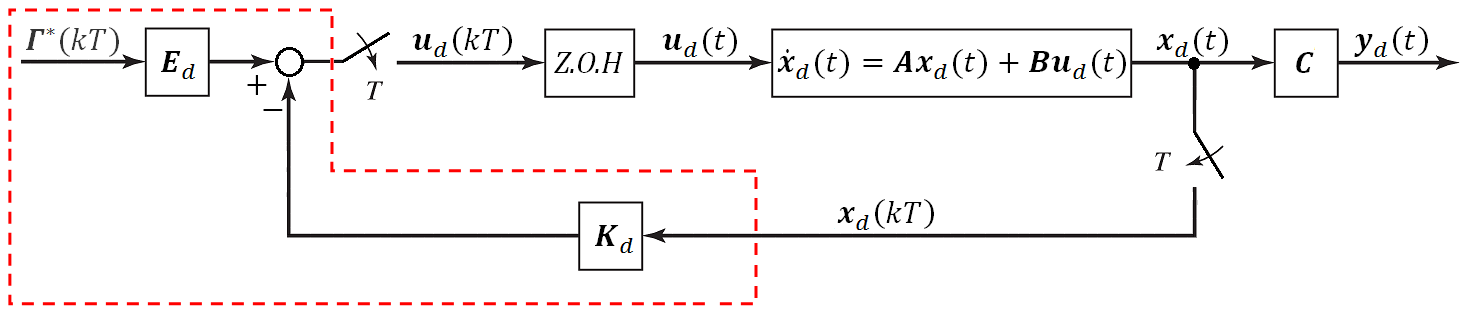
**

***Closed-loop system***

1. *Continuous-time system plus* ***controller*** *simulation*

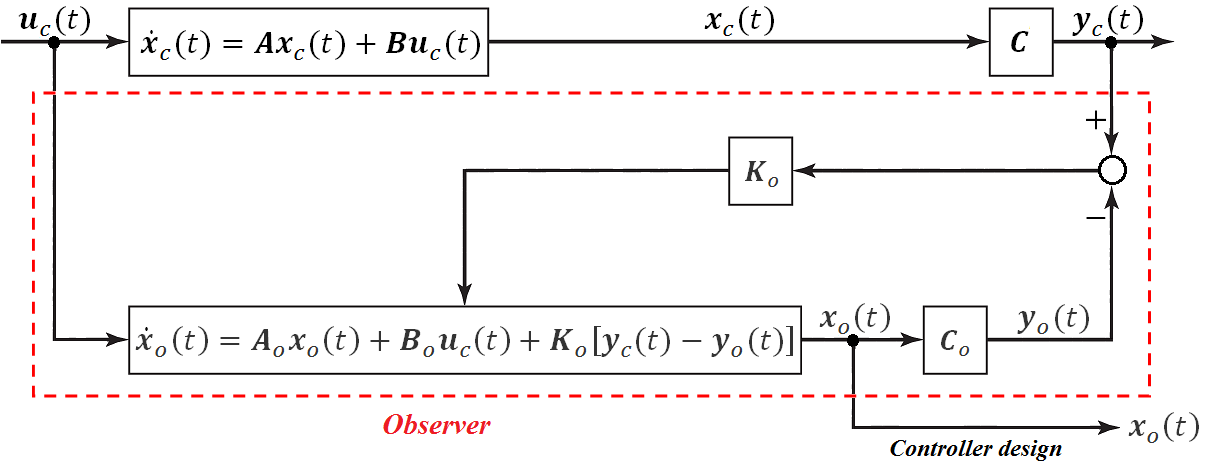
**

1. *Discrete-time system plus* ***controller*** *simulation*

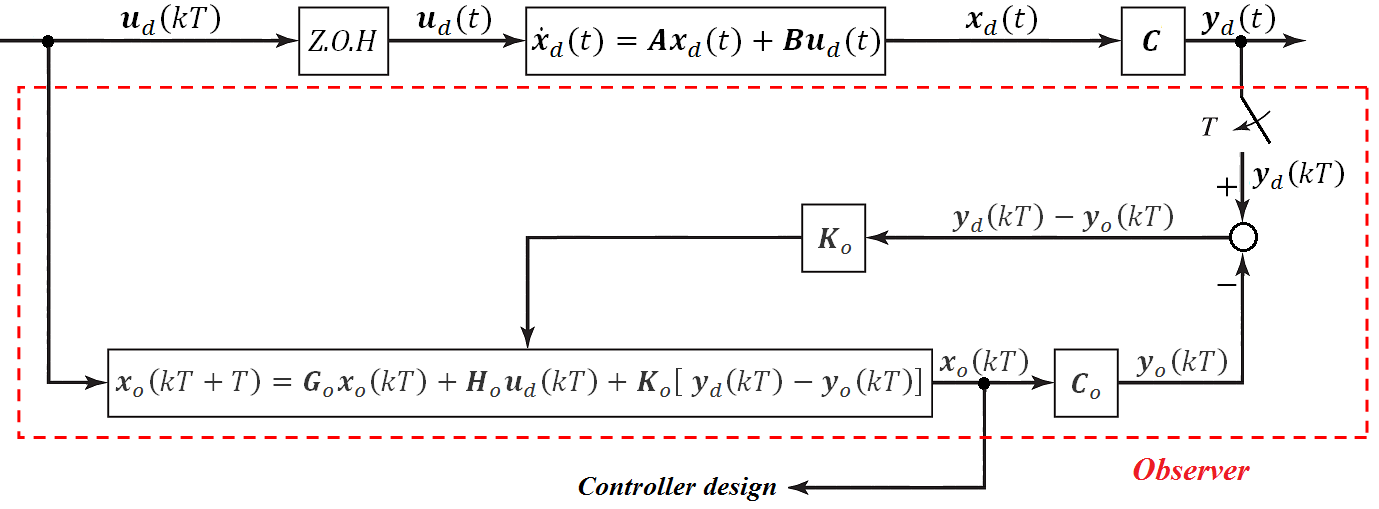
**

***Open-loop system***

1. *Continuous-time system plus* ***observer*** *simulation*

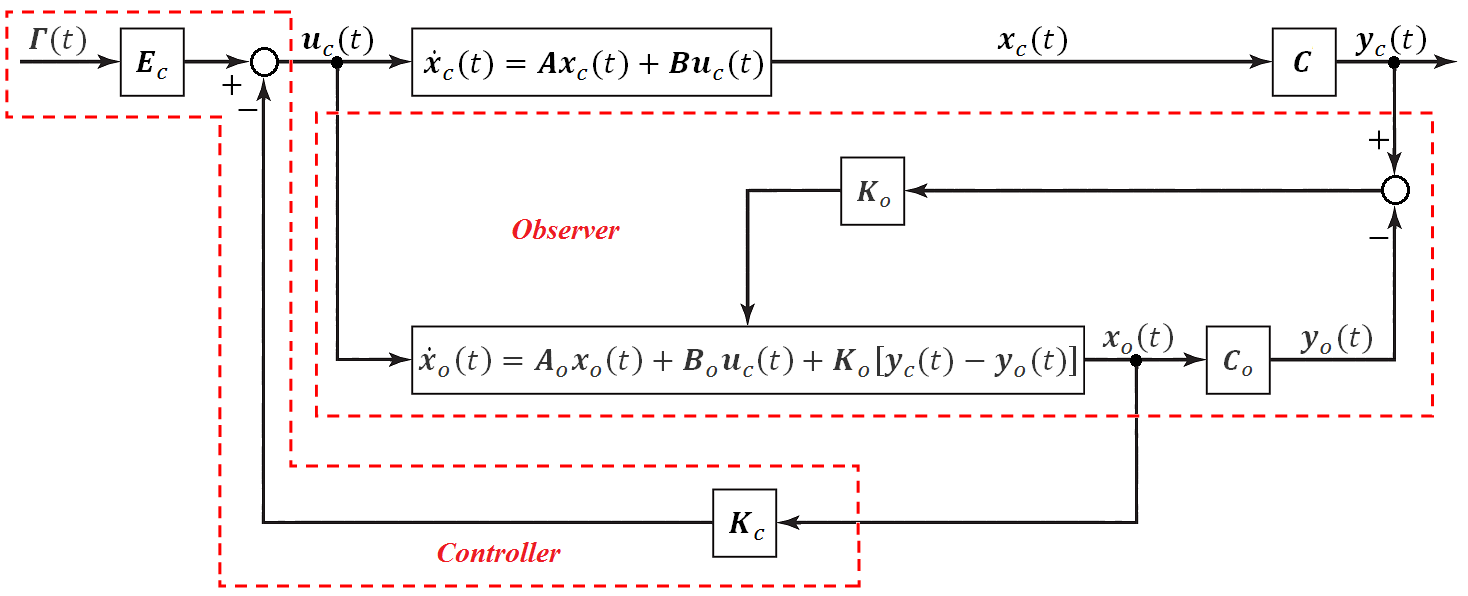
**

1. *Discrete-time system plus* ***observer*** *simulation*

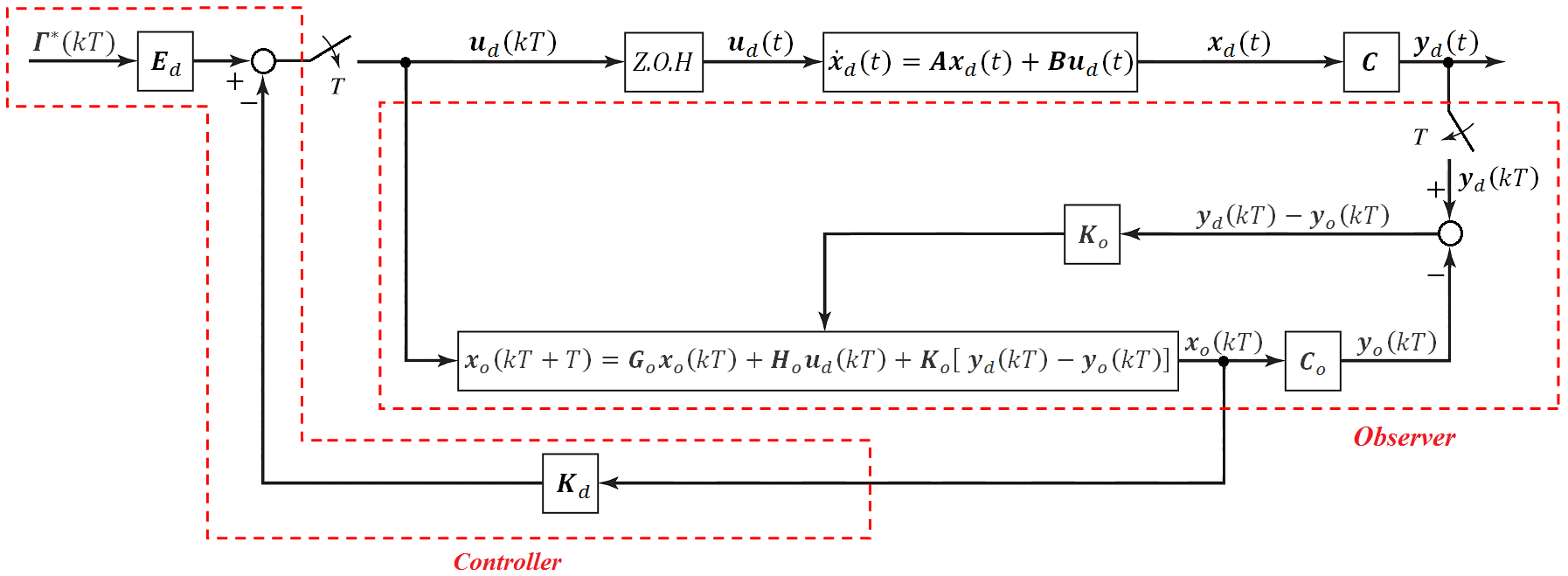
**

***Closed-loop system***

1. *Continuous-time system plus* ***observer*** *and* ***controller*** *simulation*

**

1. *Discrete-time system plus* ***observer*** *and* ***controller*** *simulation*

**

***Open-loop system***

1. *Continuous-time system plus* ***OKID*** *simulation*
2. *Discrete-time system plus* ***OKID*** *simulation*

***Closed-loop system***

1. *Continuous-time system plus* ***OKID*** *and* ***controller*** *simulation*
2. *Discrete-time system plus* ***OKID*** *and* ***controller*** *simulation*

***Twelve types* :**

***Design procedure* :**

*Step 1* : Optimal Linearization

*Step 2* : State Estimator

*Step 3* : Analog Linear Quadratic Tracker

*Step 4* : Digital Redesign

*Step 5* : Perform Simulation