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"Smack my pitch up"

The Prodigy, (1997)

1 Optimal control of pitch/travel with no feedback

1.1 State space form

We want to write the model in equation 1.1.1 in continuous time state space form with $x = [\lambda \ r \ p \ \dot{p}]^T$ and $u = p_c$

$$\dot{x} = A_c x + B_c u \tag{1.1.1}$$

*"I've got 99 problems, but a
pitch ain't one"*

Ice-T, (1993)

2 Optimal control of pitch/travel with LQ control

3 Optimal control of pitch/travel and elevation with and without feedback