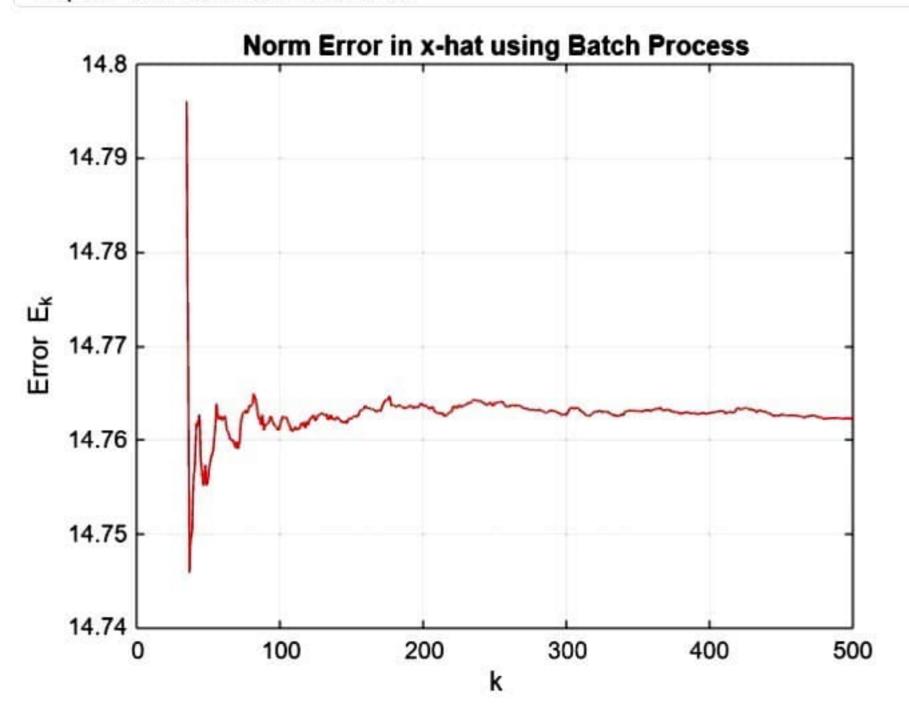


This shows that T(5) is linearly inalpendent 14 basis of Line

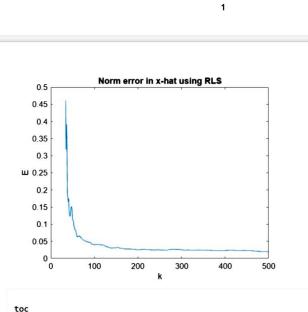
With the same of 70 Summarize, we have k, a bosin for KUT. 9 to (5) a bosis for Anti) Finally we can state their: of my real ? " X Penk (+) + Nulling (+) = dim limit + dim knot = |T(5) | + |K| = n-k + K = n = dimV - Me I would k with (n-1) lenearly independent CAR EL MITT $V = \begin{cases} -0.5000 \\ -0.5000 \end{cases}$ $V = \begin{cases} -0.5858 \\ -0.5001 \end{cases}$ $V = \begin{cases} -0.5000 \\ -0.5000 \end{cases}$ $V = \begin{cases} -0.5000 \\ -0.5000 \end{cases}$ Span (160 = 1/1 when) = spant (3) 0.7071 \\ \2 = 2.000 V 2= S 031(m) = CM $\sqrt{3} = .$ 0.5000 $\sqrt{3} = 3.4142$ -0.5000 $\sqrt{3} = 3.4142$ A 2 y unds. track the program part & corp and supple and

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The smallest n such that A_k has at least 100 independent columns is: 34



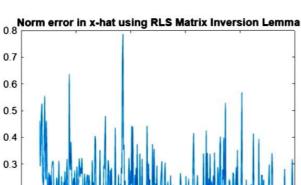
```
%HW 7 Q4c
close all
clear
clc
load("DataHW07_Prob4.mat")
S = eye(3);
temp = cell2mat(C(1));
temp_1 = size(temp);
n = ceil(temp_1(2)/temp_1(1));
for i = 1:n
    if (i == 1)
         Qk = cell2mat(C(1))'*eye(3)*cell2mat(C(1));
Tk = cell2mat(C(1))'*eye(3)*cell2mat(y(1));
    else
         Qk = Qk + cell2mat(C(i))'*eye(3)*cell2mat(C(i));
Tk = Tk + cell2mat(C(i))'*eye(3)*cell2mat(y(i));
    end
end
xk = inv(Qk)*Tk;
for k = n:N-1
    Q1 = Qk + cell2mat(C(k+1))'*eye(3)*cell2mat(C(k+1));
    Qk = Q1;
    K_k_1 = inv(Q1) * cell2mat(C(k+1))' * eye(3);
    temp = K_k_1*(cell2mat(y(k+1)) - (cell2mat(C(k+1))*xk));
    x_k_k = xk + temp(:,1);
xk = x_k_k;
    Ek\_temp = x_k_k - cell2mat(x_actual(k));
    Ek_temp1 = Ek_temp.^2;
     if (k == n)
    Ek = sum(Ek_temp1)^0.5;
    else
    Ek = [Ek;(sum(Ek_temp1))^0.5];
    end
end
plot(n:N-1,Ek)
title('Norm error in x-hat using RLS')
xlabel('k')
ylabel('E')
```



20000

Elapsed time is 0.606846 seconds.

```
%HW 7 Q4d
tic
close all
clear
clc
load("DataHW07_Prob4.mat")
temp = cell2mat(C(1));
temp_1 = size(temp);
n = ceil(temp_1(2)/temp_1(1));
S = eye(3);
for i = 1:n
    if (i == 1)
        Qk = cell2mat(C(1))'*eye(3)*cell2mat(C(1));
        Tk = cell2mat(C(1))'*eye(3)*cell2mat(y(1));
    else
        Qk = Qk + cell2mat(C(i))'*eye(3)*cell2mat(C(i));
        Tk = Tk + cell2mat(C(i))'*eye(3)*cell2mat(y(i));
    end
end
Pk = inv(Qk);
x_k_h = Pk*Tk;
for k = n:N-1
    Pk1 = Pk - Pk*cell2mat(C(k+1))'*inv(inv(S)...
        + cell2mat(C(k+1))*Pk*cell2mat(C(k+1))')*cell2mat(C(k+1))*Pk;
    Kk1 = Pk1 * cell2mat(C(k+1))' * S;
    Xk1 = x_k_hat + Kk1*(cell2mat(y(k+1))-cell2mat(C(k+1))*x_k_hat);
    x_k_h = Xk1;
    Ek_temp = x_k_hat - cell2mat(x_actual(k));
    Ek_temp1 = Ek_temp.^2;
    if(k == n)
    Ek = sum(Ek\_temp1)^0.5;
    else
    Ek = [Ek;(sum(Ek_temp1))^0.5];
    end
end
plot(n:N-1,Ek)
title('Norm error in x-hat using RLS Matrix Inversion Lemma')
xlabel('k')
```



ylabel('E')

0.7

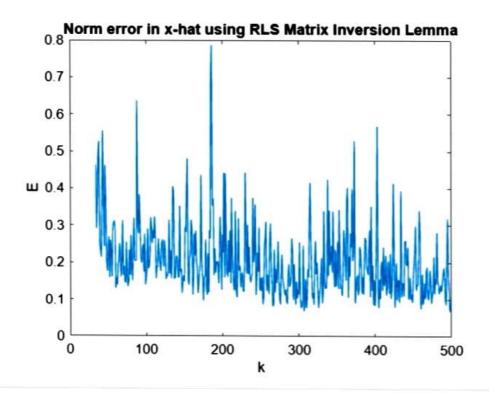
0.6 0.5

ш 0.4

0.3

0.2

0.1

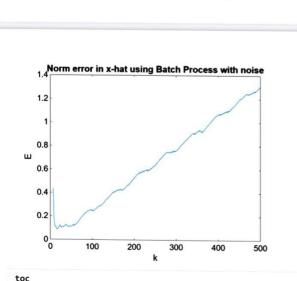


toc

Elapsed time is 0.392118 seconds.

```
%HW 7 Q5a
tic
close all
clear
clc
load("DataHW07_Prob5.mat")
temp = cell2mat(C(1));
temp_1 = size(temp);
n = ceil(temp_1(2)/temp_1(1));
for i = 1:n-1
    if (i == 1)
    Ak = cell2mat(C(i));
        Yk = cell2mat(y(i));
    else
        Ak = [Ak;cell2mat(C(i))];
Yk = [Yk;cell2mat(y(i))];
    end
end
for k = n:N
    Ak = [Ak;cell2mat(C(k))];
    Yk = [Yk;cell2mat(y(k))];
    Rk = eye(3*k);
    xk_hat = inv(Ak'*Rk*Ak) * (Ak'*Rk*Yk);
    Ek_temp = xk_hat - cell2mat(x_actual(k));
    Ek_temp1 = Ek_temp.^2;
    if (k == n)
    Ek = sum(Ek_temp1)^0.5;
    else
    Ek = [Ek;(sum(Ek_temp1))^0.5];
    end
end
plot(n:N,Ek)
title('Norm error in x-hat using Batch Process with noise')
xlabel('k')
ylabel('E')
```

1



Elapsed time is 1.094195 seconds.

