ROB-SOI Assignment-10

18/11/2024.

$$\frac{\partial f(\alpha_1, \alpha_2, \alpha_3)}{\partial f(\alpha_1)} = \frac{3}{3} \alpha_1 \left[\frac{\partial \alpha_2}{\partial \alpha_1} - (\alpha_3)^3 \right] + \frac{(\alpha_2)^4}{3}$$

$$\frac{\partial f(\alpha_1)}{\partial \alpha_2} := \left[\frac{\partial f(\alpha_1)}{\partial \alpha_1}, \frac{\partial f(\alpha_1)}{\partial \alpha_2}, \frac{\partial f(\alpha_1)}{\partial \alpha_3} \right].$$

DE(N) = 622 - 3/4 (23)3

 $\frac{\partial f}{\partial n_2} = 6n_1 + \frac{4}{3}n_2$ $\frac{\partial f}{\partial n_3} = -9n_1 n_3$

 $\frac{1}{2}$

 $\partial F(N) = (1, 3, -1)^{7} = (3(6+1), 6 + \frac{1}{3}(43)^{3}, -9)$

= [21, U2, -g]

$$\frac{\partial F(\mathbf{x}^{N})}{\partial N_{1}} = F(\mathbf{x}^{N} + S_{1}) - F(\mathbf{x}^{*} - S_{7}) - - - 0$$

$$x^{N} + S_{1} = \begin{bmatrix} 1.001 \\ 3 \\ -1 \end{bmatrix} = \begin{bmatrix} N_{1} \\ N_{2} \\ N_{3} \end{bmatrix}$$

$$f(x) = f(x_1, x_2, x_3) = 3x_1 \left(2x_2 - (x_3)^3\right) + \frac{x_2}{3}$$

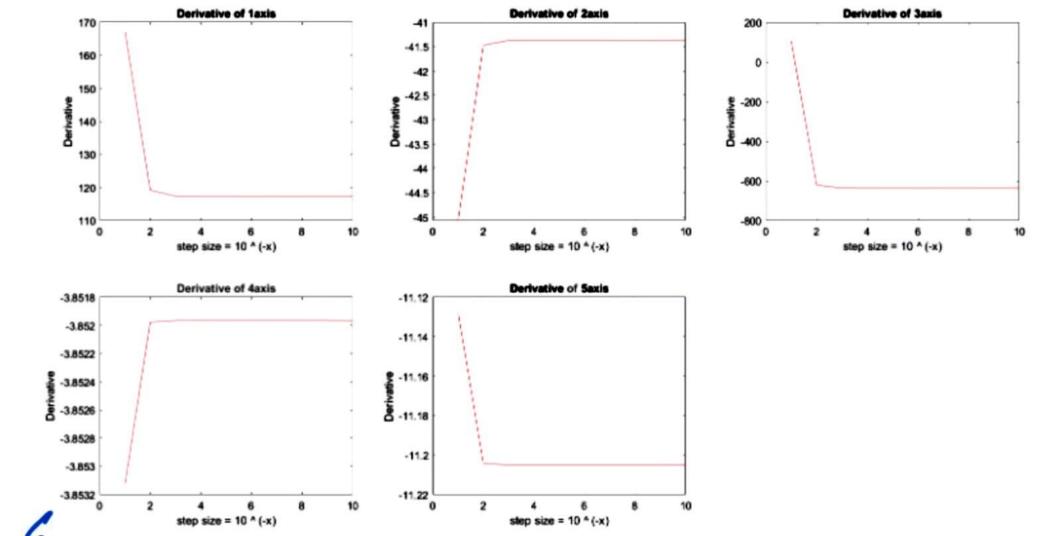
$$\int_{1}^{1} dx \quad S_{2} = \begin{bmatrix} 0 & 0.001 \\ 0 & 0.001 \end{bmatrix}$$

$$\frac{\partial C(n^{N})}{\partial n^{2}} = \frac{f(x^{N} + \delta_{2}) - f(x^{N} - \delta_{2})}{\partial \delta_{2}} = \frac{48.0420 - 47.958}{0.002}$$

$$dv \, \mathcal{E}_3 = \begin{bmatrix} 0 & 0 \\ 0 & 001 \end{bmatrix}$$

$$\frac{\partial f(w^{n})}{\partial x_{3}} = \frac{f(w^{n} + 6x) - f(w^{n} - 6x)}{28x} = 47.9910 - 48.0090$$

$$= -9.0000$$



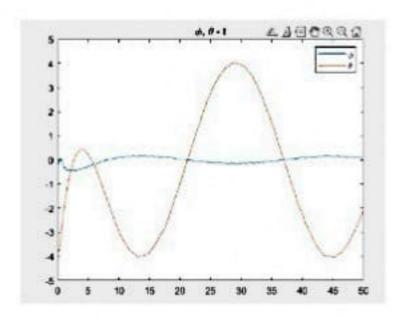
10 Jacobian &
$$= [1,1,1,1,1]$$

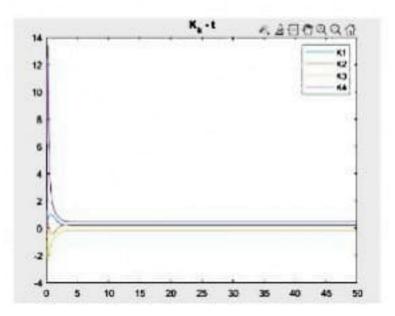
= $[14.3523, -41.3685, -636.6021, -3.8520, -11.2049]$

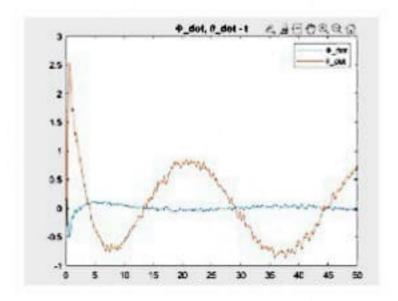
```
load SegwayData4KF.mat
phi = zeros(N, 1);
theta = zeros(N, 1);
phi dot = zeros(N, 1);
theta dot = zeros(N. 1);
K 1 = zeros(N, 1);
K 2 - zeros(N, 1);
K_3 = zeros(N, 1);
K 4 = zeros(N, 1);
x1 = x0;
P1 = P0;
tic
t=zeros(1,N);
for k -1:N
    uk = u(k);
    yk = y(k):
    K . P1 * C' / (C * P1 * C' + 0)
    x1 = A * x1 + B * uk + A * K * (yk - C * x1);
    P1 = A * (P1 - K * C * P1) * A' + G * R * G';
    x1 hat = x1;
    P1 hat = P1;
    phi(k)=[1 0 0 0] * x1_hat;
    theta(k)=[0 1 0 0] * x1 hat;
    phi dot(k) = [0 0 1 0] * x1 hat;
    theta_dot(k) = [0 0 0 1] * x1 hat;
    K_1(k) = K(1);
    K_2(k) = K(2);
    K 3(k) = K(3);
    K \ 4(k) = K(4);
```

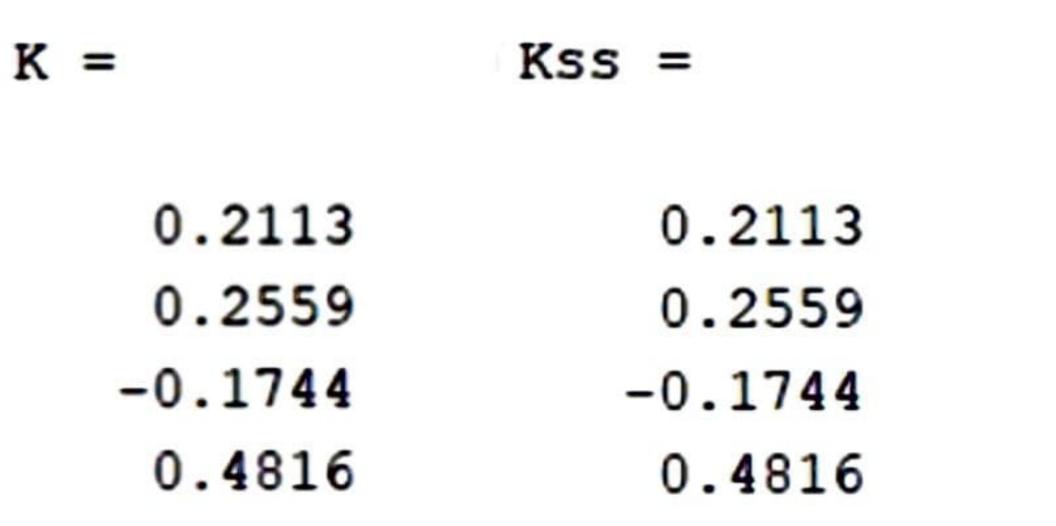
x1=x1_hat; P1 = P1_hat; end

t(k)=k*Ts;









```
u = 10;
R = 16;
c = 3 * (10 ^ 8);
C = -2 / c;
Q = 10 ^ (-18);
z 1 = 2.2 * (10 ^ (-8));
X 0 = 1;
P 0 = 0.25;
X_{hat} = A * X_{0} + B * u;
z_{hat} = 2 / c * (5 - X_{hat});
P hat = A * P 0 * A' + B * R * B';
K = P hat * C' / (C * P hat * C' + Q);
X 1 hat = X hat + K * (z_1 - z_hat)
P 1 hat = P hat - K * C * P hat
```

A = 1;

B = 0.1;

(y) & = argnin xTATAX

lus = "min NTATAN NTN=1

=) XE = GN = ATAN

of = e-value, and ATA = e-vector of to

Since we want e-values to be minimized, he pick the condition the condition of the condition. The smallest e-value is at the bottom higher cohner of Σ

>) The collesponding &-vector is the last column of v

[: columns of value eveross of ATA]

$$(3)$$
 (3) (4) (4) (4) (4) (5) (5) (5) (4) (5) (5) (5) (5) (5) (6) (5)

$$\Delta A = \begin{bmatrix} 0.0010 & -0.0010 & 0.0010 \\ -0.0024 & 0.0025 & -0.0025 \\ 0.0013 & -0.0013 & 0.0013 \end{bmatrix}$$