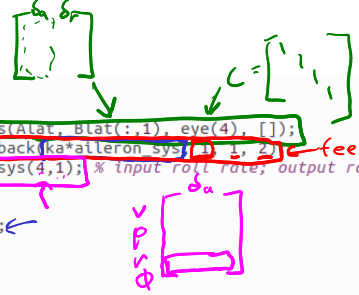
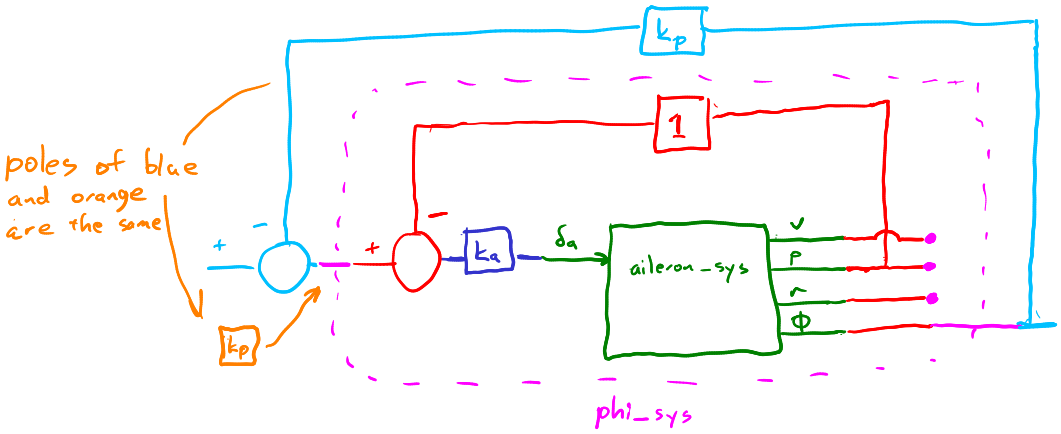



```
%% Task 3

aileron_sys = ss(Alat, Blat(:,1), eye(4), []);
p_fb_sys = feedback(ka*aileron_sys, 1, 1, 2);
phi_sys = p_fb_sys(4,1); % input roll rate, output roll angle

figure(1); clf;
rlocus(phi_sys);

figure(2); clf;
kp = nan
step(phi_sys); % Modify this to get the step response of the feedback system

```

feedin, feed out