

Lecture 1

September 9, 2021 12:11 PM

No textbook needed

↳ B.A. Francis Textbook (optional)

First deliverable Sept. 29th

Homework Assignments

↳ Two components

↳ Solution

↳ Full marks for clear, legible solution

↳ even if solutions are wrong

} 10% of global mark
(independent on correctness)

↳ Self-assessment

↳ go over solutions and evaluate assignment

↳ highlight own mistakes in red and write commentary

} 6% of global mark

Labs

↳ Groups of 3

↳ independent of lab section

TA's do not answer questions via email

Submit on Quercus

Grade Breakdown

↳ MATLAB code 40%

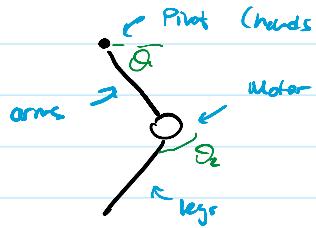
↳ Work presentation

↳ Lab report

Intro to Control Systems

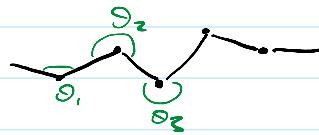
Robot Gymnast

Snek



2DOF

1 Actuator



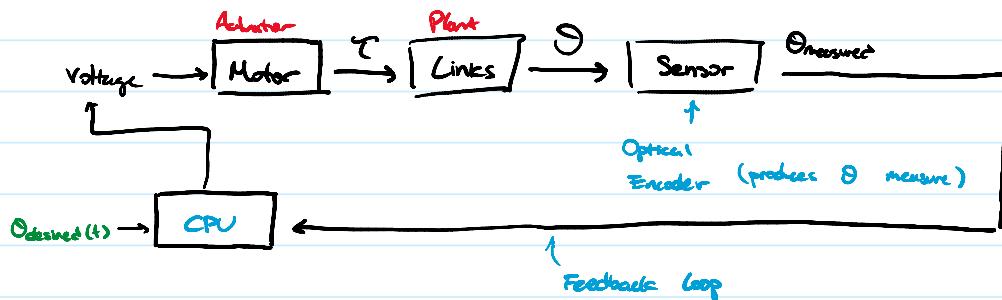
Many DOF

Core problem:

- Control actuators s.t. the angle of a linkage converges to a desired angle

$$\theta(t) \rightarrow \theta_{\text{desired}}(t)$$

In gymnast case:



LTI systems