Assignment 5 TTK4190

Marine Control Systems:
Analysis and Design

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Abstract

Abstract goes here. Remember to make it good.

@memwarnUnknown toclevel for chapter

Contents

List of Figures

List of Tables

Abbreviations

Abbrev.	Abbreviation
Abbrev.	Abbreviation
Etc.	Etcetera
E.g.	For example (Lat. *exempli gratia*)
I.e.	That is to say (Lat. *id est*)
GC	Guidance and Control
TA	Teaching Assistant

Introduction

Using the Template

To use this template, you need memoir. You can find it at CTAN (The Comprehensive TeX Archive Network).

The memoir manual is very good, both at explaining how to use the memoir class, and general rules of typography.

Not Using the Template

You do not have to use the template. If you are not using it, use this document as en example of how the final report *can* (but not *must*) look.

You are also free to modify the template as you see fit.

Assignment 1

Historical Development of Marine Control Systems

This chapter contains dummy text, and also shows what to do if the chapter name is a bit too long. In additions, it contains example figures, example tables and example citations.

1.1 A Section

The following is a quotation. Writing it like this is sometimes useful. For longer stuff you can use \quotation environment for longer, multi-paragraph quotes.

> Cuius rei demonstrationem mirabilem sane detexi. Hanc marginis exiguitas non caperet.[MS93]

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Task 1.1.1
This is a task text for Task 1.1.1.
More text in the task. The next task is Task 1.1.2.

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A Subsection

Task 1.1.2
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$$M\ddot{\xi} = \sum_{\alpha=1}^{N} f_\alpha \tag{1.1}$$

$$\mathbf{M}\ddot{\boldsymbol{\xi}} = \sum_{\alpha=1}^{N} \boldsymbol{f}_\alpha$$

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A nice example figure

Figure 1.1: An example figure.

A nice example figure	A nice example figure
(a) Top left	(b) Top right
A nice example figure	A nice example figure
(c) Bottom left	(d) Bottom right

Figure 1.2: Another example figure with too long caption for the List of Figures, also showing how to make subfigures.

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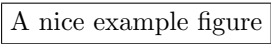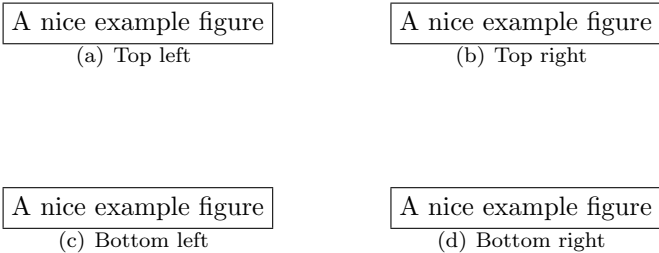
Alpha	Beta	Gamma
Delta	Epsilon	Zeta
Eta	Theta	Iota

Table 1.1: Table of Greek

Alef	Bet	Gimel
Dalet	He	Vav
Zayin	Het	Tet

Table 1.2: Table of Hebrew

Assignment 2

Marine Vessel Modeling

Assignment 3

Autopilots and Path Following

Assignment 4

Dynamic Positioning Systems

5 Conclusions

5.1 A Section

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References

[Bro83]   R. W. Brockett. *Asymptotic stability and feedback stabilization*, pages 181–191. Birkhäuser, 1983.

[Maz03]   F. Mazenc. Strict lyapunov functions for time-varying systems. *Automatica*, 39:349–353, 2003.

[MS93]   R. M. Murray and S. S. Sastry. Nonholonomic motion planning: steering using sinusoids. *IEEE Transactions on Automatic Control*, 38:700–716, 1993.

Appendices

Appendix A

Moderately Important Stuff

A.1 About Appendices

If you have many appendices, do it like this: A page signifying the start of the appendices saying "Appendices", then the appendices numbered A, B, C, ...

If you only have one appendix, do not have a page saying "Appendices". Have just one unnumbered chapter with title "Appendix", or "Appendix: Name of Appendix".

Appendix B

More Moderately Important Stuff

Appendix: Slightly Important Stuff

A Section

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