

Assignment 5 TTK4190

Marine Control Systems:  
**Analysis and Design**

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## **Abstract**

Abstract goes here. Remember to make it good.



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# Abbreviations

Abbrev.	Abbreviation
Etc.	Etcetera
E.g.	For example (Lat. <i>exempli gratia</i> )
I.e.	That is to say (Lat. <i>id est</i> )
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 T<sub>E</sub>X 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 an 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.

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#### Task 1.1.1

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More text in the task. The next task is Task 1.1.2.

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#### 1.1.1 A Subsection

##### Task 1.1.2

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

(1.1)

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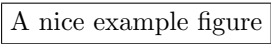


Figure 1.1: An example figure.

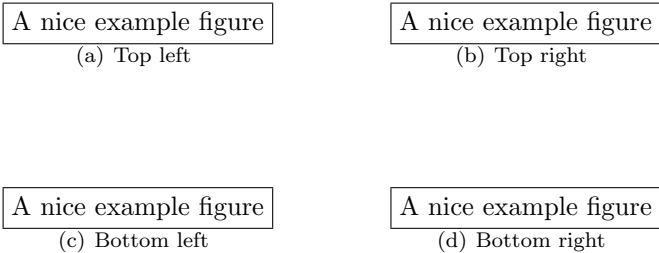


Figure 1.2: Another example figure with too long caption for the List of Figures, also showing how to make subfigures.

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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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