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deviation of the vehicle the linearized model is a controller that includes Apply a sinusoidal signa x-axis with time. Plot t [AM09] K. J. Astrom a Princeton University Pr	from the x-axis and the angle only the first state. Construct a an observer. The dynamics are all as the reference trajectory the he output (lateral deviation of the R. M. Murray. Feedback S.	between the vehicle axis and the x-axis. The output of Simulink model for the vehicle steering system with its envailable in Example 6.4 and Example 7.3 in [AM09] at specifies the desired deviation of the vehicle from the the vehicle from the x-axis) with time. Systems: An Introduction for Scientists and Engineers of Am08-complete_22Feb09.pdf.
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