**Subject: Results for Lab3**

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**PART B: Modelling the Plant**

1. Include the output of **wheel\_match.m** below, showing your model matches the measured output for a step of 50 radians/sec.



1. Include the output of **wheel\_match.m** below, showing your model matches the measured output for a step of 75 radians/sec.



**PART D: Openloop Control**

1. Include your open loop control results (figure from **DT\_Openloop\_driver.m**) here.



**PART E: Limiting Slew Rate**

1. Include your open loop control results (figure from **DT\_Openloop\_driver.m**) here.



**PART F: Proportional Control**

1. Include your results for your proportional controller here (the output of **DT\_PID\_driver.m**) here. The steady state values should match the reference signal.



1. Include your graph with the input coming from the pot here. Be sure to have three (3) or more plateaus.



**PART G: Model Matching**

1. Include your results for the model matching (output of **DT\_model\_matching\_driver.m**) here.



1. What did you assume the desired closed loop response Go (z) was? Write it down here.

9) What was the order of your controller? 11