

EXPERIMENTS

Exp 1.

Reference (Step)
Noise
Initial conditions
System variation

Exp 2.

Reference (Sin)
Noise
Initial conditions
System variation

Exp 3.

Reference
Noise
Initial conditions
System variation

ENVIRONMENT

Benchmark configuration

Sample time (Δt), Model Callbacks, Coder

Controller Plugin:

- PID
- MPC
- DeePC
- LQR

System Plugin:

- Otter USV
- Quadcopter
- Cart-pole
- Three tank

Noise Plugin:

- Gaussian
- White noise

Estimator Plugin:

- EKF
- UKF
- Particle filter
- Luenberger

