

Model Documentation of the 'Linear cable mass problem of order 20'

1 Nomenclature

1.1 Nomenclature for Model Equations

x	state vector
u	control input vector
w	noise vector
z	regulated output vector
y	measurement vector

2 Model Equations

State Vector and Input Vector:

$$x \in \mathbb{R}^{960} \quad u \in \mathbb{R}^1 \quad w \in \mathbb{R}^1 \quad z \in \mathbb{R}^3 \quad y \in \mathbb{R}^2$$

System Equations:

$$\dot{x}(t) = Ax(t) + B_1w(t) + Bu(t) \quad (1a)$$

$$z(t) = C_1x(t) + D_{11}w(t) + D_{12}u(t) \quad (1b)$$

$$y(t) = Cx(t) + D_{21}w(t) \quad (1c)$$

Outputs: z

2.1 Exemplary parameter values

Parameters omitted due to large matrices. See Source code.

3 Derivation and Explanation

This model is part of the "COMpleib" - library and was automatically imported into ACKREP.

The original description was:

CM6 To CM1 corresponding example of order 960.

4 Simulation

References

- [1] . A. Burns and B.B. King, "A reduced bases approach to the design of low order feedback controllers for nonlinear continuous systems", ICAM Virginia Polytechnic Institute and State University, Blacksburg