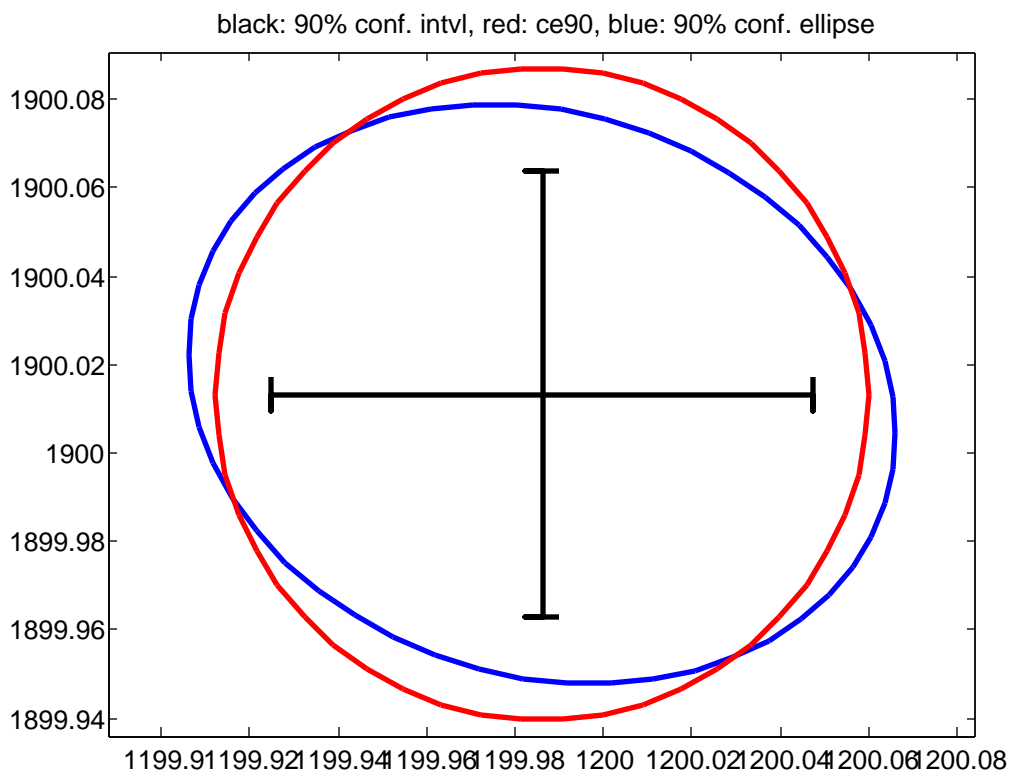


```

hw4
n = 5
n0 = 2
r = 2
u = 3
del = 2
del = -9.8368251307025
      10.0482504354788
del = -0.177097051401564
      -0.0349143872193216
del = 1.87388068704826e-005
      -1.92792887907436e-005
del = -6.13288526961868e-010
      1.85485433542491e-010
ans =
      300
      1100
      1600
      1199.98609655609
      900
      1200
      600
      1900.01331676916
s02 = 1
v = -0.0369977920770414
      0.037998044653633
      -0.016132399637412
      -1.64328321596962e-005
      -2.43082499424549e-007
vsec = -0.0369977920770414
      0.037998044653633
      -0.016132399637412
      -3.38951494151079
      -0.0501393646458645
chi test = 1.34409018860078
cv1 = 0.215795282623898
cv2 = 9.34840360449614
Sdd = 0.00139000651118658
      -0.000160938786719665
      -0.000160938786719665
      0.000936322745366826
we pass 2-sided global test @ alpha=.05
Z = 1.64485362695147
x_half_width = 0.0613247341412164
y_half_width = 0.0503315196934075
x confidence interval
xci = 1199.92477182195
      1200.04742129023
y confidence interval
yci = 1899.96298524946
      1900.06364828885
lambda1 = 0.00144129864797386
lambda2 = 0.000885030608579551
V1 & length
ans = -0.95278140585244
      0.303657031306454
maj_length = 0.0814703968491265
V2 & length
ans = -0.303657031306454
      -0.95278140585244
min_length = 0.0638413390548588
ce90 = 0.0738199263509244
theta = 2.83306406597378
diary off

```



```

% hw4. m 4-nov-09
% solve data hw#4

X=[300; 1100; 1600; 1210];
Y=[900; 1200; 600; 1890];
d1=1345. 40;
d2=707. 08;
d3=1360. 18;
th1d=33+51/60+30. 6/3600;
th2d=25+13/60+55. 1/3600;
degrad=180/pi ;
th1=th1d/degrad;
th2=th2d/degrad;
sa=(10/3600)/degrad;
l=[d1; d2; d3; th1; th2];
n=5
n0=2
r=3
u=n0
B=zeros(n, u);
f=zeros(n, 1);

w=[1/(0. 05^2);
    1/(0. 05^2);
    1/(0. 05^2);
    1/(sa^2);
    1/(sa^2)];
W=diag(w);
i ter=1;
keep_goi ng=1;
whi l e((keep_goi ng==1) && (i ter<10))
    res=di stance2d(d1, 4, 1, X, Y);
    B(1, :)=res(1, 3: 4);
    f(1)=-res(2);
    res=di stance2d(d2, 4, 2, X, Y);
    B(2, :)=res(1, 3: 4);
    f(2)=-res(2);
    res=di stance2d(d3, 4, 3, X, Y);
    B(3, :)=res(1, 3: 4);
    f(3)=-res(2);
    res=angl e2d(th1, 4, 2, 1, X, Y);
    B(4, :)=res(1, 3: 4);
    f(4)=-res(2);
    res=angl e2d(th2, 4, 3, 2, X, Y);
    B(5, :)=res(1, 3: 4);
    f(5)=-res(2);
    N=B' *W*B;
    t=B' *W*f;
    del =i nv(N) *t;
    X(4)=X(4)+del (1);
    Y(4)=Y(4)+del (2);
    i ter=i ter+1;
    i f(al l(abs(del) < 1. 0e-08))
        keep_goi ng=0;
    end
end

[X Y]

% post adj ustment stati stics

s02=1. 0
v=F-B*del
vsec=v;
vsec(4)=v(4) *degrad*3600;
vsec(5)=v(5) *degrad*3600;
vsec
chi test=v' *W*v/s02
cv1=chi 2i nv(0. 025, 3)
cv2=chi 2i nv(0. 975, 3)
Sdd=i nv(N)

% 90% c. i. x, y; 90% conf. ell. x, y; 90% conf. circ.

i f((chi test > cv1) && (chi test < cv2))
    disp('we pass 2-si ded gl obal test @ al pha=. 05' );
    % do the error prop (P=0. 90, al pha=0. 10)
    % c. i. x-hat +/- z*si gma
    P=0. 9;
    al pha=0. 10;
    z=normi nv(1-al pha/2, 0, 1)
    x_hal f_wi dth=z*sqrt(Sdd(1, 1))
    y_hal f_wi dth=z*sqrt(Sdd(2, 2))

```

```

disp('x conf interval');
xci=[X(4)-x_half_width X(4)+x_half_width]
disp('y conf interval');
yci=[Y(4)-y_half_width Y(4)+y_half_width]
% now the conf ellipse
[V,D]=eig(Sdd);
if(D(2,2) > D(1,1))
    D=[D(2,2) 0; 0 D(1,1)];
    V=[V(:,2) V(:,1)];
end
lambda1=D(1,1)
lambda2=D(2,2)
disp('V1 & length');
V(:,1)
scale=chi2inv(P,2);
maj_length=sqrt(lambda1*scale)
disp('V2 & length');
V(:,2)
min_length=sqrt(lambda2*scale)
% now confidence
ce90=cep2(P,Sdd)
% ok now pictures
theta=atan2(V(2,1),V(1,1))
draw_ellipse(X(4),Y(4),maj_length,min_length,theta,'b-',2);
draw_circle(X(4),Y(4),ce90,50,'r-',2);
axis equal
d=0.05*ce90;
xc=X(4);
yc=Y(4);
xh=x_half_width;
yh=y_half_width;
px=[xc-xh; xc-xh; xc-xh; xc+xh; xc+xh; xc+xh];
py=[yc+d; yc-d; yc; yc; yc-d; yc+d];
plot(px,py,'k-','linewidth',2);
py=[yc-yh; yc-yh; yc-yh; yc+yh; yc+yh; yc+yh];
px=[xc+d; xc-d; xc; xc; xc-d; xc+d];
plot(px,py,'k-','linewidth',2);
shrink5;
title('black: 90% conf. intvl, red: ce90, blue: 90% conf. ellipse');
else
disp('we do not pass the 2-sided global test @ alpha=.05');
end

```

```

distance2d.m
% distance2d.m 30-oct-08
% compute distance condition equation
% returned vector is [dc Fd dFdx dFdy dFdxj dFdyj]
function result=distance2d(d,i,j,X,Y)
xi=X(i);
yi=Y(i);
xj=X(j);
yj=Y(j);
Dij=sqrt((xj-xi)^2 + (yj-yi)^2);
dFdx=(xj-xi)/Dij;
dFdy=(yj-yi)/Dij;
dFdxj=-dFdx;
dFdyj=-dFdy;
F=d - Dij;
result=[Dij F dFdx dFdy dFdxj dFdyj];

```

note that the returned array has an extra element at the beginning, different from that specified in the instructions - it was added to return the value of the observation as computed from the current coordinates - this is useful for simulation and generation of synthetic data.

angl e2d. m

```
% angl e2d. m 3-nov-08
function resul t = angl e2d(a, i, j, k, X, Y)
xi=X(i);
yi=Y(i);
xj=X(j);
yj=Y(j);
xk=X(k);
yk=Y(k);
Dij_sq=(xj-xi)^2 + (yj-yi)^2;
Dik_sq=(xk-xi)^2 + (yk-yi)^2;
dFdx_i = (yk-yi)/Dik_sq - (yj-yi)/Dij_sq;
dFdy_i = -(xk-xi)/Dik_sq + (xj-xi)/Dij_sq;
dFdx_j = (yj-yi)/Dij_sq;
dFdy_j = -(xj-xi)/Dij_sq;
dFdx_k = -(yk-yi)/Dik_sq;
dFdy_k = (xk-xi)/Dik_sq;
ac=atan2(xk-xi, yk-yi) - atan2(xj-xi, yj-yi);
if(ac < 0)
    ac=ac + 2*pi;
end

% ac
% degrad=180/pi;
% ac*degrad

Fa=a - ac;
resul t=[ac Fa dFdx_i dFdy_i dFdx_j dFdy_j dFdx_k dFdy_k];
```

see comments about distance2d.m - same comments apply here.