

1. The choice of an initial guess is crucial to the quality of a solution in convex optimization.
 - (a) true
 - (b) false
2. The choice of an initial guess is crucial to the quality of a solution in nonconvex optimization.
 - (a) true
 - (b) false
3. The linearized friction cone as shown in lecture conservatively approximates the friction force available for a given normal force.
 - (a) true
 - (b) false
4. Iterative Learning Control (ILC) requires an exact dynamics model.
 - (a) true
 - (b) false
5. Iterative Learning Control (ILC) only works on systems with open loop policies.
 - (a) true
 - (b) false
6. Any linear system with discrete dynamics $x_{k+1} = Ax_k + Bu_k$, and a control policy $u_k = -Kx_k$, can be expressed as $x_{k+1} = \tilde{A}x_k$ with some constant matrix \tilde{A} .
 - (a) true
 - (b) false