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book opens a view to the largely unexplored area of nonlinear systems with uncertainties. The focus is on adaptive nonlinear control results introduced with the new recursive design methodology--adaptive backstepping. Describes basic tools for nonadaptive backstepping design with state and output feedbacks.

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Differential geometric techniques are used to identify classes of nonlinear systems considered and to design feedback algorithms. Adaptive versions of these controls are developed in the presence of unknown parameters while robust versions are designed in the presence of time-varying disturbances.

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1.1.1 Emergence of adaptive control 1.1.2 Achievements of adaptive linear control 1.1.3 Adaptive control as dynamic nonlinear feedback 1.1.4 Lyapunov-based design 1.1.5 Estimation-based design Adaptive Nonlinear Control 1.2.1 A nonlinear challenge 1.2.2 A structural obstacle 1.2.3 Early results Preview of the Main Topics 1.3.1 Classes of ...

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The focus is on adaptive nonlinear control results introduced with the new recursive design methodology--adaptive backstepping. Describes basic tools for nonadaptive backstepping design with state and output feedbacks. Nonlinear And Adaptive Control Of Complex Systems Author : A.L. Fradkov

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Communicative and accessible at a level not usually present in research texts, "Nonlinear and Adaptive Control Design" can be used as either a stand-alone or a supplemental text in courses on nonlinear or adaptive control, as well as in control research and applications.

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Nonlinear and Adaptive Control Design, (1995)

The adaptive control problem for general nonlinear systems can be formulated as follows. Consider a nonlinear system described by equations of the form. $\dot{x} = F(x, u, \theta), \quad \quad \quad y = H(x, \theta), \quad (1)$ where $x(t) \in \{\mathbb{R}\}^n$ denotes the state of the system, $u(t) \in \{\mathbb{R}\}^m$ denotes the input of the system, $\theta \in \{\mathbb{R}\}^q$ denotes the constant unknown parameter, $y(t) \in \{\mathbb{R}\}^p$ denotes the measured output, and $F : \{\mathbb{R}\}^n$

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Nonlinear control design: geometric, adaptive and robust . 1996.

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Abstract. No abstract available. Cited By. Tzafestas S (2018) Mobile Robot Control and Navigation, Journal of Intelligent and Robotic Systems, 91:1, (35-58), Online publication date: 1-Jul-2018.

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Adaptive control of nonlinear processes; Concurrent learning adaptive control, which relaxes the condition on persistent excitation for parameter convergence for a class of systems ; Adaptive control has even been merged with intelligent techniques such as fuzzy and neural networks and the new terms like fuzzy adaptive control has been generated.

Adaptive control - Wikipedia

Adaptive Nonlinear Control – A Tutorial Miroslav Krstić «c
University of California, San Diego – Backstepping – Tuning F
unctions Design – Modular Design – Output Feedback –

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Adaptive Nonlinear ControlÑA T uto r ial Miroslav Krsti «C

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Nonlinear and Adaptive Control with Applications provides a detailed treatment of the design of robust adaptive controllers for nonlinear systems with uncertainties. The authors employ a new tool based on the ideas of system immersion and manifold

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invariance.

Nonlinear and Adaptive Control with Applications ...

The same nonlinear Six-DOF model is used in this paper to develop a state-constrained adaptive control design for hypersonic cruise flight. The controller ensures that the vehicle attitude, body rates, and velocity remain bounded within the prescribed limits.

Nonlinear robust neuro-adaptive flight control for ...

Official Description. Design of nonlinear control systems based on stability considerations; Lyapunov and hyperstability approaches to analysis and design of model reference adaptive systems; identifiers, observers, and controllers for unknown plants. Course Information: Prerequisite: ECE 515.

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Using a pedagogical style along with detailed proofs and illustrative examples, this book opens a view to the largely unexplored area of nonlinear systems with uncertainties. The focus is on adaptive nonlinear control results introduced with the new recursive design methodology--adaptive backstepping.

Nonlinear and Adaptive Control Design by Miroslav Krstić

A discontinuous projection based desired compensation adaptive robust controller (ARC) is constructed. In particular, based on the special structures of various periodic nonlinear forces, design models consisting of known basis functions with unknown weights are used to approximate those unknown nonlinear forces.

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