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Methods of Nonlinear Analysis

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Methods Of Nonlinear Analysis 2vol

Krzysztof R. Kozlowski



Methods Of Nonlinear Analysis 2vol:

Topological Methods in Nonlinear Analysis, 2002 *Approximate and Noisy Realization of Discrete-Time Dynamical Systems* Yasumichi Hasegawa, 2008-06-02 This monograph deals with approximation and noise cancellation of dynamical systems which include linear and nonlinear input output relations It will be of special interest to researchers engineers and graduate students who have specialized in ltering theory and system theory From noisy or noiseless data reduction will be made A new method which reduces noise or model information will be proposed Using this method will allow model description to be treated as noise reduction or model reduction As proof of the e cacy this monograph provides new results and their extensions which can also be applied to nonlinear dynamical systems To present the e ectiveness of our method many actual examples of noise and model information reduction will also be provided Using the analysis of state space approach the model reduction problem may have become a major theme of technology after 1966 for emphasizing e ciency in the elds of control economy numerical analysis and others Noise reduction problems in the analysis of noisy dynamical systems may have become a major theme of technology after 1974 for emphasizing e ciency in control However the subjects of these researches have been mainly concentrated in linear systems In common model reduction of linear systems in use today a singular value decomposition of a Hankel matrix is used to nd a reduced order model However the existence of the conditions of the reduced order model are derived without evaluation of the resultant model In the common typical noise reduction of linear systems in use today the order and parameters of the systems are determined by minimizing information criterion Approximate and noisy realization problems for input output relations can be roughly stated as follows A The approximate realization problem For any input output map nd one mathematical model such that it is similar to the input output map and has a lower dimension than the given minimal state space of a dynamical system which has the same behavior to the input output map B The noisy realization problem

Model

Abstraction in Dynamical Systems: Application to Mobile Robot Control Patricia Mellodge, Pushkin Kachroo, 2008-09-02 The subject of this book is model abstraction of dynamical systems The primary goal of the work embodied in this book is to design a controller for the mobile robotic car using abstraction Abstraction provides a means to represent the dynamics of a system using a simpler model while retaining important characteristics of the original system A second goal of this work is to study the propagation of uncertain initial conditions in the framework of abstraction The summation of this work is presented in this book It includes the following An overview of the history and current research in mobile robotic control design A mathematical review that provides the tools used in this research area The development of the robotic car model and both controllers used in the new control design A review of abstraction and an extension of these ideas into new system relationship characterizations called traceability and traceability A framework for designing controllers based on abstraction An open loop control design with simulation results An investigation of system abstraction

with uncertain initial conditions

Artificial Neural Networks for the Modelling and Fault Diagnosis of Technical Processes Krzysztof Patan, 2008-06-11 An unappealing characteristic of all real world systems is the fact that they are vulnerable to faults malfunctions and more generally unexpected modes of haviour This explains why there is a continuous need for reliable and universal monitoring systems based on suitable and effective fault diagnosis strategies This is especially true for engineering systems whose complexity is permanently growing due to the inevitable development of modern industry as well as the information and communication technology revolution Indeed the design and operation of engineering systems require an increased attention with respect to availability reliability safety and fault tolerance Thus it is natural that fault diagnosis plays a fundamental role in modern control theory and practice This is reflected in plenty of papers on fault diagnosis in many control oriented conferences and journals Indeed a large amount of knowledge on model based fault diagnosis has been accumulated through scientific literature since the beginning of the 1970s As a result a wide spectrum of fault diagnosis techniques have been developed A major category of fault diagnosis techniques is the model based one where an analytical model of the plant to be monitored is assumed to be available

Analysis and Synthesis of Dynamical Systems with Time-Delays Yuanqing Xia, Mengyin Fu, Peng Shi, 2009-09-07 Time delay occurs in many dynamical systems such as biological systems chemical systems metallurgical processing systems nuclear reactor long transmission lines in pneumatic hydraulic systems and electrical networks Especially in recent years time delay which exists in networked control systems has brought more complex problems into a new research area Frequently it is a source of the generation of oscillation instability and poor performance Considerable effort has been applied to different aspects of linear time delay systems during recent years Because the introduction of the delay factor renders the system analysis more complicated in addition to the difficulties caused by the perturbation or uncertainties in the control of time delay systems the problems of robust stability and robust stabilization are of great importance This book presents some basic theories of stability and stabilization of systems with time delay which are related to the main results in this book More attention will be paid on synthesis of systems with time delay That is sliding mode control of systems with time delay networked control systems with time delay networked data fusion with random delay

Safe Adaptive Control Margareta Stefanovic, Michael G. Safonov, 2011-02-10 Safe Adaptive Control gives a formal and complete algorithm for assuring the stability of a switched control system when at least one of the available candidate controllers is stabilizing The possibility of having an unstable switched system even in the presence of a stabilizing candidate controller is demonstrated by referring to several well known adaptive control approaches where the system goes unstable when a large mismatch between the unknown plant and the available models exists plant model mismatch instability Sufficient conditions for this possibility to be avoided are formulated and a recipe to be followed by the control system designer to guarantee stability and desired performance is provided The problem is placed in a standard optimization setting Unlike the finite controller sets considered elsewhere the candidate controller set is allowed to be

continuously parametrized so that it can deal with plants with a very large range of uncertainties

PID Control for Multivariable Processes Qing-Guo Wang, Zhen Ye, Wen-Jian Cai, Chang-Chieh Hang, 2008-03-19 There are rich theories and designs for general control systems but usually they will not lead to PID controllers. Noting that the PID controller has been the most popular one in industry for over fifty years we will continue our discussion here to PID control only. PID control has been an important research topic since 1950s and causes remarkable activities for the last two decades. Most of the existing works have been on the single variable PID control and its theory and design are well established, understood and practically applied. However, most industrial processes are of multivariable nature. It is not rare that the overall multivariable PID control system could fail although each PID loop may work well. Thus demand for addressing multivariable interactions is high for successful application of PID control in multivariable processes and it is evident from major leading control companies who all ranked the couplings of multivariable systems as the principal common problem in industry. There have been studies on PID control for multivariable processes and they provide some useful design tools for certain cases. But it is noted that the existing works are mainly for decentralized form of PID control and based on ad hoc methodologies. Obvious multivariable PID control is much less understood and developed in comparison with the single variable case and actual need for industrial applications. Better theory and design have to be established for multivariable PID control to reach the same maturity and popularity as the single variable case. The present monograph puts together in a single volume a fairly comprehensive up to date and detailed treatment of PID control for multivariable processes from pairing gain and phase margins to various design methods and applications.

Fault Tolerant Flight Control Christopher Edwards, Thomas Lombaerts, Hafid Smaili, 2010-04-18 Written by leading experts in the field this book provides the state of the art in terms of fault tolerant control applicable to civil aircraft. The book consists of five parts and includes online material.

Optimization and Cooperative Control Strategies Michael Hirsch, Clayton W. Commander, Panos M. Pardalos, Robert Murphey, 2009-01-17 Cooperative collaborating autonomous systems are at the forefront of research efforts in numerous disciplines across the applied sciences. There is constant progress in solution techniques for these systems. However, despite this progress, cooperating systems have continued to be extremely difficult to model, analyze and solve. Theoretical results are very difficult to come by. Each year the International Conference on Cooperative Control and Optimization (CCO) brings together top researchers from around the world to present new cutting edge ideas, theories, applications and advances in the fields of autonomous agents, cooperative systems, control theory, information flow and optimization. The works in this volume are a result of invited papers and selected presentations at the Eighth Annual International Conference on Cooperative Control and Optimization held in Gainesville, Florida, January 30 - February 1, 2008.

Networked Control Systems Alberto Bemporad, Maurice Heemels, Mikael Johansson, 2010-10-15 This book finds its origin in the WIDE PhD School on Networked Control Systems which we organized in

July 2009 in Siena Italy Having gathered experts on all the aspects of networked control systems it was a small step to go from the summer school to the book certainly given the enthusiasm of the lecturers at the school We felt that a book collecting overviewson the important developmentsand open pr lems in the eld of networked control systems could stimulate and support future research in this appealing area Given the tremendoucurrentinterests in distributed control exploiting wired and wireless communication networks the time seemed to be right for the book that lies now in front of you The goal of the book is to set out the core techniques and tools that are ava able for the modeling analysis and design of networked control systems Roughly speaking the book consists of three parts The rst part presents architectures for distributed control systems and models of wired and wireless communication n works In particular in the rst chapter important technological and architectural aspects on distributed control systems are discussed The second chapter provides insight in the behavior of communication channels in terms of delays packet loss and information constraints leading to suitable modeling paradigms for commu cation networks

Automotive Model Predictive Control Luigi Del Re, Frank Allgöwer, Luigi Glielmo, Carlos Guardiola, Ilya Kolmanovsky, 2010-03-11 Automotive control has developed over the decades from an auxiliary te nology to a key element without which the actual performances emission safety and consumption targets could not be met Accordingly automotive control has been increasing its authority and responsibility at the price of complexity and di cult tuning The progressive evolution has been mainly ledby speci c applicationsandshorttermtargets withthe consequencethat automotive control is to a very large extent more heuristic than systematic Product requirements are still increasing and new challenges are coming from potentially huge markets like India and China and against this ba ground there is wide consensus both in the industry and academia that the current state is not satisfactory Model based control could be an approach to improve performance while reducing development and tuning times and possibly costs Model predictive control is a kind of model based control design approach which has experienced a growing success since the middle of the 1980s for slow complex plants in particular of the chemical and process industry In the last decades severaldevelopments haveallowedusing these methods also for fast systemsandthis hassupporteda growinginterestinitsusealsofor automotive applications with several promising results reported Still there is no consensus on whether model predictive control with its high requi ements on model quality and on computational power is a sensible choice for automotive control

Perspectives in Mathematical System Theory, Control, and Signal Processing Jan C. Willems, Shinji Hara, Yoshito Ohta, Hisaya Fujioka, 2010-02-28 This Festschrift published on the occasion of the sixtieth birthday of Yutaka mamoto YY as he is occasionally casually referred to contains a collection of articles by friends colleagues and former Ph D students of YY They are a tribute to his friendship and his scienti c vision and oeuvre which has been a source of inspiration to the authors Yutaka Yamamoto was born in Kyoto Japan on March 29 1950 He studied applied mathematics and general engineering science at the Department of Applied Mathematics and Physics of Kyoto University obtaining the B S and M Sc degrees in 1972 and 1974 His M Sc work was done

under the supervision of Professor Yoshikazu Sawaragi In 1974 he went to the Center for Mathematical System Theory of the University of Florida in Gainesville He obtained the M Sc and Ph D degrees both in Mathematics in 1976 and 1978 under the direction of Professor Rudolf Kalman

Time-Varying Sliding Modes for Second and Third Order Systems Andrzej Bartoszewicz,Aleksandra Nowacka-Leverton,2009-04-03 A principal objective of control engineering is to design control systems which are robust with respect to external disturbances and modelling uncertainty This objective may be well achieved using the sliding mode technique which is the main subject of this monograph More precisely Time Varying Sliding Modes for Second and Third Order Systems focuses on only one but very important aspect of the sliding mode system design i e the problem of the sliding plane selection In this self contained monograph the main notions and concepts used in the field of variable structure systems and sliding mode control are presented before in the main part the issue of the switching surface design is discussed This is done by considering two standard plants which are very often encountered in the control engineering practice the second and the third order nonlinear and possibly time varying systems

The Joint Spectral Radius Raphaël Jungers,2009-05-19 This monograph is based on the Ph D Thesis of the author 58 Its goal is twofold First it presents most researchwork that has been done during his Ph D or at least the part of the work that is related with the joint spectral radius This work was concerned with theoretical developments part I as well as the study of some applications part II As a second goal it was the author s feeling that a survey on the state of the art on the joint spectral radius was really missing in the literature so that the first two chapters of part I present such a survey The other chapters mainly report personal research except Chapter 5 which presents an important application of the joint spectral radius the continuity of wavelet functions The first part of this monograph is dedicated to theoretical results The first two chapters present the above mentioned survey on the joint spectral radius Its minimum growth counterpart the joint spectral subradius is also considered The next two chapters point out two specific theoretical topics that are important in practical applications the particular case of nonnegative matrices and the Finiteness Property The second part considers applications involving the joint spectral radius

Modern Sliding Mode Control Theory Giorgio Bartolini,Leonid Fridman,Alessandro Pisano,Elio Usai,2008-04-05 This concise book covers modern sliding mode control theory The authors identify key contributions defining the theoretical and applicative state of the art of the sliding mode control theory and the most promising trends of the ongoing research activities

New Trends in Optimal Filtering and Control for Polynomial and Time-Delay Systems Michael Basin,2008-09-18 0 1 Introduction Although the general optimal solution of the filtering problem for nonlinear state and observation equations confused with white Gaussian noises is given by the Kushner equation for the conditional density of an unobserved state with respect to observations see 48 or 41 Theorem 6 5 formula 6 79 or 70 Subsection 5 10 5 formula 5 10 23 there are a very few known examples of nonlinear systems where the Kushner equation can be reduced to a finite dimensional closed system of filtering equations for a certain number of lower conditional moments The most famous result the Kalman Bucy

Iter 42 is related to the case of linear state and observation equations where only two moments the estimate itself and its variance form a closed system of ltering equations However the optimal nonlinear nite dimensional lter can be tained in some other cases if for example the state vector can take only a nite number of admissible states 91 or if the observation equation is linear and the drift term in the 2 2 state equation satis es the Riccati equation $df dx f x$ see 15 The complete classi cation of the general situation cases this means that there are no special sumptions on the structure of state and observation equations and the initial conditions where the optimal nonlinear nite dimensional lter exists is given in 95

Robot Motion and Control 2009 Krzysztof R. Kozlowski, 2009-12-15 Robot Motion Control 2009 presents very recent results in robot motion and control Forty short papers have been chosen from those presented at the sixth International Workshop on Robot Motion and Control held in Poland in June 2009 The authors of these papers have been carefully selected and represent leading institutions in this field The following recent developments are discussed design of trajectory planning schemes for holonomic and nonholonomic systems with optimization of energy torque limitations and other factors new control algorithms for industrial robots nonholonomic systems and legged robots different applications of robotic systems in industry and everyday life like medicine education entertainment and others multiagent systems consisting of mobile and flying robots with their applications The book is suitable for graduate students of automation and robotics informatics and management mechatronics electronics and production engineering systems as well as scientists and researchers working in these fields

Advances in the Theory of Control, Signals and Systems with Physical Modeling Jean Levine, Philippe Müllhaupt, 2010-09-30 In the 60 s control signals and systems had a common linear algebraic background and according to their evolution their respective backgrounds have now dramatically differed Recovering such a common background especially in the nonlinear context is currently a fully open question The role played by physical models finite or infinite dimensional in this hypothetical convergence is extensively discussed in this book The discussion does not only take place on a theoretical basis but also in the light of two wide classes of applications among the most active in the current industrially oriented researches Electrical and Mechatronical systems Chemical Processes and systems appearing in Life Sciences In this perspective this book is a contribution to the enhancement of the dialogue between theoretical laboratories and more practically oriented ones and industries This book is a collection of articles that have been presented by leading international experts at a series of three workshops of a Bernoulli program entitled Advances in the Theory of Control Signals and Systems with Physical Modeling hosted by the Bernoulli Centre of EPFL during the first semester of 2009 It provides researchers engineers and graduate students with an unprecedented collection of topics and internationally acknowledged top quality works and surveys

Reconfigurable Control of Nonlinear Dynamical Systems Jan H. Richter, 2011-02-02 This research monograph summarizes solutions to reconfigurable fault tolerant control problems for nonlinear dynamical systems that are based on the fault hiding principle It emphasizes but is not limited to complete actuator and sensor failures In the first part

the monograph starts with a broad introduction of the control reconfiguration problems and objectives as well as summaries and explanations of solutions for linear dynamical systems The solution is always a reconfiguration block which consists of linear virtual actuators in the case of actuator faults and linear virtual sensors in the case of sensor faults The main advantage of the fault hiding concept is the reusability of the nominal controller which remains in the loop as an active system while the virtual actuator and sensor adapt the control input and the measured output to the fault scenario The second and third parts extend virtual actuators and virtual sensors towards the classes of Hammerstein Wiener systems and piecewise affine systems The main analyses concern stability recovery setpoint tracking recovery and performance recovery as reconfiguration objectives The fourth part concludes the monograph with descriptions of practical implementations and case studies The book is primarily intended for active researchers and practicing engineers in the field of fault tolerant control Due to many running examples it is also suitable for interested graduate students

Adaptive Backstepping Control of Uncertain Systems Jing Zhou, Changyun Wen, 2008-01-08 This book employs the powerful and popular adaptive backstepping control technology to design controllers for dynamic uncertain systems with non smooth nonlinearities Various cases including systems with time varying parameters multi inputs and multi outputs backlash dead zone hysteresis and saturation are considered in design and analysis For multi inputs and multi outputs systems both centralized and decentralized controls are addressed This book not only presents recent research results including theoretical success and practical development such as the proof of system stability and

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