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Autore	Lin Feng
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5.6 Problems  
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6.2 Matched Uncertainty; 6.3 Unmatched Uncertainty; 6.4 Uncertainty in  
the Input Matrix; 6.5 Notes and References; 6.6 Problems; 7 Kharitonov  
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Theorem; 7.4 Control Design Using Kharitonov Theorem; 7.5 Notes and  
References; 7.6 Problems; 8 H and H<sub>2</sub> Control; 8.1 Introduction; 8.2  
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Control Problem as H<sub>2</sub> and H Control Problem; 8.5 H<sub>2</sub>/H $\infty$   
> Control Synthesis  
8.6 Notes and References; 8.7 Problems; 9 Robust  
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Active Damping Design; 9.4 Active Vehicle Suspension System; 9.5  
Discussion; 9.6 Notes and References; 10 Robust Control of  
Manipulators; 10.1 Robot Dynamics; 10.2 Problem Formulation; 10.3  
Robust Control Design; 10.4 Simulations; 10.5 Notes and References;  
11 Aircraft Hovering Control; 11.1 Modelling and Problem Formulation;  
11.2 Control Design for Jet-borne Hovering; 11.3 Simulation; 11.4  
Notes and References  
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References and Bibliography; Index

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Sommario/riassunto

Comprehensive and accessible guide to the three main approaches to robust control design and its applications. Optimal control is a mathematical field that is concerned with control policies that can be deduced using optimization algorithms. The optimal control approach to robust control design differs from conventional direct approaches to robust control that are more commonly discussed by firstly translating the robust control problem into its optimal control counterpart, and then solving the optimal control problem. Robust Control Design: An Optimal Control Approach offers

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2. Record Nr.	UNISALENTO991001436259707536
Autore	Gleick, James
Titolo	Faster : the acceleration of just about everything / James Gleick
Pubbl/distr/stampa	New York : Vintage Book, 2000
ISBN	9780679775485
Descrizione fisica	x, 311 p. , 21 cm
Disciplina	303.48
Soggetti	Progresso tecnico - Aspetti sociali Tempo - Sociologia
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia