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5.6 Problems
6 Robust Control of Nonlinear Systems; 6.1 Introduction; 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 Approach; 7.1 Introduction; 7.2 Preliminary Theorems; 7.3 Kharitonov Theorem; 7.4 Control Design Using Kharitonov Theorem; 7.5 Notes and References; 7.6 Problems; 8 H and H_2 Control; 8.1 Introduction; 8.2 Function Space; 8.3 Computation of H_2 and H Norms; 8.4 Robust Control Problem as H_2 and H Control Problem; 8.5 H_2/H_∞ Control Synthesis; 8.6 Notes and References; 8.7 Problems; 9 Robust Active Damping; 9.1 Introduction; 9.2 Problem Formulation; 9.3 Robust 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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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
