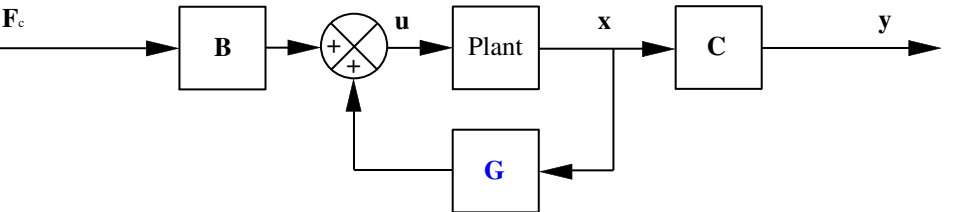


Codes:

LMIs for designing an FTS controller for the Epileptor Model

Control approach for the Epileptor model using a fourth-order Runge-Kutta integrator



x States
 \hat{x} Estimated states
 u Input vector

B Input matrix
 C Output matrix
 G Gains of the controller

F_c Input force