Appendix Laplace Transforms Involving Fractional and Irrational Operations

As the cases of integer-order systems, Laplace transform and its inverse are very important. In this appendix, the definition is given first. Then some of the essential special functions are described. Finally, an inverse Laplace transform table involving fractional and irrational-order operators is given.

A.1 Laplace Transforms

For a time-domain function f(t), its Laplace transform, in s-domain, is defined as

$$\mathscr{L}[f(t)] = \int_0^\infty f(t)e^{-st}dt = F(s), \tag{A.53}$$

where $\mathcal{L}[f(t)]$ is the notation of Laplace transform.

If the Laplace transform of a signal f(t) is F(s), the inverse Laplace transform of F(s) is defined as

$$f(t) = \mathcal{L}^{-1}[F(s)] = \frac{1}{j2\pi} \int_{\sigma - j\infty}^{\sigma + j\infty} F(s) e^{st} ds, \qquad (A.54)$$

where σ is greater than the real part of all the poles of function F(s).

A.2 Special Functions for Laplace Transform

Since the evaluation for some fractional-order is difficult, special functions may be needed. Here some of the special functions are introduced and listed in Table A.1.

A.3 Laplace Transform Tables

An inverse Laplace transform table involving fractional and irrational operators is collected in Table A.2 [86, 300].

392 Appendix

 ${\bf Table~A.1~~Some~special~functions}$

Special functions	Definition
Mittag-Leffler	$\mathscr{E}_{\alpha,\beta}^{\gamma}(z) = \sum_{k=0}^{\infty} \frac{(\gamma)_k}{\Gamma(\alpha k + \beta)} \frac{z^k}{k!}, \ \mathscr{E}_{\alpha,\beta}(z) = \mathscr{E}_{\alpha,\beta}^1(z), \ \mathscr{E}_{\alpha}(z) = \mathscr{E}_{\alpha,1}(z)$
Dawson function	$daw(t) = e^{-t^2} \int_0^t e^{\tau^2} d\tau$
erf function	$\operatorname{erf}(t) = \frac{2}{\sqrt{\pi}} \int_0^t e^{-\tau^2} d\tau$
erfc function	$\operatorname{erfc}(t) = \frac{2}{\sqrt{\pi}} \int_{t}^{\infty} e^{-\tau^{2}} d\tau = 1 - \operatorname{erf}(t)$
Hermit polynomial	$\mathscr{H}_n(t) = e^{t^2} \frac{\mathrm{d}^n}{\mathrm{d}t^n} e^{-t^2}$
Bessel function	$\mathscr{J}_{\nu}(t)$ is the solution to $t^2\ddot{y}+t\dot{y}+(t^2-\nu^2)y=0$
Extended Bessel function	$\mathscr{I}_{\nu}(t) = \mathrm{j}^{-\nu} \mathscr{I}_{\nu}(\mathrm{j}t)$

Table A.2 Inverse Laplace transforms with fractional and irrational operators

F(s)	$f(t) = \mathcal{L}^{-1}[F(s)]$	F(s)	$f(t) = \mathcal{L}^{-1}[F(s)]$
$\frac{s^{\alpha\gamma-\beta}}{(s^{\alpha}+a)^{\gamma}}$	$t^{\beta-1}\mathscr{E}_{\alpha,\beta}^{\gamma}\left(-at^{\alpha}\right)$	$\frac{1}{s^n \sqrt{s}}, n = 1, 2, \cdots$	$\frac{2^n t^{n-\frac{1}{2}}}{1 \cdot 3 \cdot 5 \cdots (2n-1)\sqrt{\pi}}$
$\frac{k}{s^2 + k^2} \coth\left(\frac{\pi s}{2k}\right)$	$ \sin kt $	$\arctan \frac{k}{s}$	$\frac{1}{t}\sin kt$
$\log \frac{s^2 - a^2}{s^2}$	$\frac{2}{t}(1-\cosh at)$	$\frac{1}{s\sqrt{s}}e^{-k\sqrt{s}}$	$2\sqrt{\frac{t}{\pi}}e^{-\frac{1}{4t}k^2} - k \operatorname{erfc}\left(\frac{k}{2\sqrt{t}}\right)$
$\log \frac{s^2 + a^2}{s^2}$	$\frac{2}{t}(1-\cos at)$	$\frac{e^{-k\sqrt{s}}}{\sqrt{s}(a+\sqrt{s})}$	$e^{ak}e^{a^2t}\operatorname{erfc}\left(a\sqrt{t}+\frac{k}{2\sqrt{t}}\right)$
$\frac{(1-s)^n}{s^{n+\frac{1}{2}}}$	$\left \frac{n!}{(2n)!\sqrt{\pi t}} \mathscr{H}_{2n}\left(\sqrt{t}\right) \right $	$\frac{1}{\sqrt{s+b}(s+a)}$	$\frac{1}{\sqrt{b-a}} e^{-at} \operatorname{erf}\left(\sqrt{(b-a)t}\right)$
$\frac{1}{\sqrt{s^2 + a^2}}$	$\mathcal{J}_0(at)$	$\frac{(1-s)^n}{s^{n+\frac{3}{2}}}$	$-\frac{n!}{(2n+1)!\sqrt{\pi}}\mathscr{H}_{2n+1}\left(\sqrt{t}\right)$
$\frac{1}{\sqrt{s^2 - a^2}}$	$\mathscr{I}_0(at)$	$\frac{(a-b)^k}{(\sqrt{s+a}+\sqrt{s+b})^{2k}}$	$\frac{k}{t}\mathrm{e}^{-\frac{1}{2}(a\!+\!b)t}\mathscr{I}_k\left(\frac{a\!-\!b}{2}t\right),\ k\!>\!0$
$\frac{\sqrt{s+2a} - \sqrt{s}}{\sqrt{s+2a} + \sqrt{s}}$	$\frac{1}{t}e^{-at}\mathscr{I}_1(at)$	$\frac{\sqrt{s+2a} - \sqrt{s}}{\sqrt{s+2a} + \sqrt{s}}$	$\frac{1}{t}e^{-at}\mathscr{I}_1(at)$
$\frac{(\sqrt{s^2 + a^2} - s)^{\nu}}{\sqrt{s^2 + a^2}}$	$a^{\nu} \mathcal{J}_{\nu}(at), \nu > -1$	$\frac{1}{(s^2 - a^2)^k}$	$\frac{\sqrt{\pi}}{\Gamma(k)} \left(\frac{t}{2a}\right)^{k-\frac{1}{2}} \mathscr{I}_{k-\frac{1}{2}}(at)$
$\frac{(\sqrt{s^2 - a^2} + s)^{\nu}}{\sqrt{s^2 - a^2}}$	$a^{\nu} \mathscr{I}_{\nu}(at), \ \nu > -1$	$\frac{1}{(\sqrt{s^2 + a^2})^k}$	$\frac{\sqrt{\pi}}{\Gamma(k)} \left(\frac{t}{2a}\right)^{k-\frac{1}{2}} \mathscr{I}_{k-\frac{1}{2}}(at)$ $\frac{\sqrt{\pi}}{\Gamma(k)} \left(\frac{t}{2a}\right)^{k-\frac{1}{2}} \mathscr{J}_{k-\frac{1}{2}}(at)$
$(\sqrt{s^2+a^2}-s)^k$	$\frac{ka^k}{t}\mathcal{J}_k(at), k>0$	$\log \frac{s-a}{s-b}$	$\frac{1}{t} \left(e^{bt} - e^{at} \right)$
$\frac{1}{s + \sqrt{s^2 + a^2}}$	$rac{\mathscr{J}_1(at)}{at}$	$\frac{1}{\sqrt{s+a}\sqrt{s+b}}$	$e^{-\frac{1}{2}(a+b)t}\mathscr{I}_0\left(\frac{a-b}{2}t\right)$

Appendix 393

Table A.2 (continued)

F(s)	$f(t) = \mathcal{L}^{-1}[F(s)]$	F(s)	$f(t) = \mathcal{L}^{-1}[F(s)]$
$\frac{1}{(s+\sqrt{s^2+a^2})^N}$	$\left \frac{N \mathscr{J}_N(at)}{at}, N > 0 \right $	$\frac{b^2 - a^2}{(s - a^2)(\sqrt{s} + b)}$	$e^{a^2t} \Big[b - a \operatorname{erf} \Big(a\sqrt{t} \Big) \Big] - be^{b^2t} \operatorname{erfc} \Big(b\sqrt{t} \Big)$
$\sqrt{s-a} - \sqrt{s-b}$	$\frac{1}{2\sqrt{\pi t^3}} \left(e^{bt} - e^{at} \right)$	$\frac{\sqrt{s+2a}-\sqrt{s}}{\sqrt{s}}$	$ae^{-at}\Big[\mathscr{I}_1(at)+\mathscr{I}_0(at)\Big]$
$\frac{1}{s}e^{-k/s}$	$\mathscr{J}_0\left(2\sqrt{kt} ight)$	$\frac{1}{\sqrt{s}}e^{-k/s}$	$\frac{1}{\sqrt{\pi t}}\cos 2\sqrt{kt}$
$\frac{1}{\sqrt{s}} e^{k/s}$	$\frac{1}{\sqrt{\pi t}}\cosh 2\sqrt{kt}$	$\frac{1}{s\sqrt{s}}e^{-k/s}$	$\frac{1}{\sqrt{\pi k}}\sin 2\sqrt{kt}$
$\frac{1}{s\sqrt{s}}e^{k/s}$	$\frac{1}{\sqrt{\pi k}}\sinh 2\sqrt{kt}$	$\frac{1}{s^{\nu}} e^{-k/s}$	$\frac{\sqrt{\pi k}}{\sqrt{\pi k}} \sin 2\sqrt{kt}$ $\left(\frac{t}{k}\right)^{\frac{1}{2}(\nu-1)} \mathscr{J}_{\nu-1}\left(\frac{t}{k}\right), \nu > 0$
$e^{-k\sqrt{s}}$	$\frac{k}{2\sqrt{\pi t^3}} e^{-\frac{1}{4k}k^2}$	$\frac{1}{s^{\nu}} e^{k/s}$	$\left(\frac{t}{k}\right)^{\frac{1}{2}(\nu-1)}\mathscr{I}_{\nu-1}\left(2\sqrt{kt}\right)$
$\frac{1}{s}e^{-k\sqrt{s}}$	$\operatorname{erfc}\left(\frac{k}{2\sqrt{t}}\right)$	$\frac{1}{s\sqrt{s}}e^{-\sqrt{s}}$	$2\sqrt{\frac{t}{\pi}}e^{-\frac{1}{4t}} - \operatorname{erfc}\left(\frac{1}{2\sqrt{t}}\right)$
$\frac{1}{\sqrt{s}} e^{-k\sqrt{s}}$	$\frac{1}{\sqrt{\pi t}} e^{-\frac{1}{4t}k^2}$	$\frac{e^{-\sqrt{s}}}{\sqrt{s}(\sqrt{s}+1)}$	e^{t+1} erfc $\left(\sqrt{t} + \frac{1}{2\sqrt{t}}\right)$
$\frac{1}{(s+a)^{\alpha}}$	$\frac{t^{\alpha-1}}{\Gamma(\alpha)} e^{-at}$	$\frac{1}{s^{\alpha} + a}$	$t^{\alpha-1}\mathscr{E}_{\alpha,\alpha}\left(-at^{\alpha}\right)$
$\frac{a}{s(s^{\alpha}+a)}$	$1 - \mathscr{E}_{\alpha} \left(-at^{\alpha} \right)$	$\frac{s^{\alpha}}{s(s^{\alpha}+a)}$	$\mathscr{E}_{lpha}\left(-at^{lpha} ight)$
$\frac{1}{s^{\alpha}(s-a)}$	$t^{lpha}\mathscr{E}_{1,1+lpha}(at)$	$\frac{s^{\alpha}}{s-a}$	$-t^{\alpha}\mathcal{E}_{1,1-\alpha}(at), \ 0<\alpha<1$
$\frac{1}{\sqrt{s}}$	$\frac{1}{\sqrt{\pi t}}$	$\frac{1}{s\sqrt{s}}$	$2\sqrt{\frac{t}{\pi}}$
$\frac{1}{\sqrt{s}(s+1)}$	$\frac{2}{\sqrt{\pi}}\operatorname{daw}\left(\sqrt{t}\right)$	$\frac{\sqrt{s}}{s+1}$	$\frac{1}{\sqrt{\pi t}} - \frac{2}{\sqrt{\pi}} \operatorname{daw}\left(\sqrt{t}\right)$
$\frac{1}{\sqrt{s(s+a^2)}}$	$\sqrt{t} \mathscr{E}_{1,3/2}\left(-a^2t\right)$	$\frac{s}{(s-a)\sqrt{s-a}}$	$\frac{1}{\sqrt{\pi t}} e^{at} (1 + 2at)$
$\frac{\sqrt{s}}{s+a^2}$	$\boxed{\frac{1}{\sqrt{t}}\mathscr{E}_{1,1/2}\left(-a^2t\right)}$	$\frac{1}{\sqrt{s}+a}$	$\frac{1}{\sqrt{\pi t}} - a e^{a^2 t} \operatorname{erfc}\left(a\sqrt{t}\right)$
$\frac{1}{s\sqrt{s+1}}$	$\operatorname{erf}\left(\sqrt{t}\right)$	$\frac{\sqrt{s}}{s-a^2}$	$\frac{1}{\sqrt{\pi t}} + a e^{a^2 t} \operatorname{erf}\left(a\sqrt{t}\right)$
$\frac{1}{\sqrt{s(s-a^2)}}$	$\frac{1}{a}e^{a^2t}\operatorname{erf}\left(a\sqrt{t}\right)$	$\frac{1}{\sqrt{s}(s+a^2)}$	$\frac{2}{a\sqrt{\pi}}e^{-a^2t}\int_0^{a\sqrt{t}}e^{\tau^2}d\tau$
$\frac{1}{\sqrt{s}(\sqrt{s}+a)}$	e^{a^2t} erfc $\left(a\sqrt{t}\right)$	$\frac{s\sqrt{s}}{s+1}$	$2\sqrt{\frac{t}{\pi}} - \frac{2}{\sqrt{\pi}} \operatorname{daw}\left(\sqrt{t}\right)$
$\frac{1}{\sqrt{s+1}}$	$\frac{\mathrm{e}^{-t}}{\sqrt{\pi t}}$	$\frac{1}{\sqrt{s(s-1)}}$	$\operatorname{e}^t \mathrm{erf} \left(\sqrt{t} \right)$
$\frac{\sqrt{s}}{s-1}$	$\frac{1}{\sqrt{\pi t}} + e^t \operatorname{erf}\left(\sqrt{t}\right)$	$\frac{k!}{\sqrt{s} \pm \lambda}$	$t^{(k\!-\!1)/2} \mathscr{E}^{(k)}_{1/2,1/2} \left(\mp \lambda \sqrt{t}\right), \Re(s) \!>\! \lambda^2$
$\frac{1}{s^{\alpha}}$	$\frac{t^{\alpha-1}}{\Gamma(\alpha)}$	$\frac{s^{\alpha-1}}{s^{\alpha} \pm \lambda}$	$\mathscr{E}_{\alpha}\left(\mp\lambda t^{\alpha}\right), \ \Re(s) > \left \lambda\right ^{1/\alpha}$

394 Appendix

Table A.2 (continued)

F(s)	$f(t) = \mathcal{L}^{-1}[F(s)]$
$\frac{1}{\sqrt{s(s+a)}(\sqrt{s+a}+\sqrt{s})^{2\nu}}$	$\frac{1}{a^{\nu}} e^{-at/2} \mathscr{I}_{\nu} \left(\frac{a}{2} t \right), k > 0$
$\frac{\Gamma(k)}{(s+a)^k(s+b)^k}$	$\sqrt{\pi} \left(\frac{t}{a-b} \right)^{k-\frac{1}{2}} \mathrm{e}^{-\frac{1}{2}(a+b)t} \mathscr{I}_{k-\frac{1}{2}} \left(\frac{a-b}{2} t \right)$
$\frac{1}{\sqrt{s^2 + a^2}(s + \sqrt{s^2 + a^2})^N}$	$\frac{J_N(at)}{a^N}$
$\frac{1}{\sqrt{s^2 + a^2}(s + \sqrt{s^2 + a^2})}$	$rac{J_1(at)}{a}$
$\frac{b^2 - a^2}{\sqrt{s}(s - a^2)(\sqrt{s} + b)}$	$e^{a^{2}t} \left[\frac{b}{a} \operatorname{erf} \left(a\sqrt{t} \right) - 1 \right] + e^{b^{2}t} \operatorname{erfc} \left(b\sqrt{t} \right)$
$\frac{a\mathrm{e}^{-k\sqrt{s}}}{s(a+\sqrt{s})}$	$-\mathrm{e}^{ak}\mathrm{e}^{a^2t}\mathrm{erfc}\left(a\sqrt{t}+\frac{k}{2\sqrt{t}}\right)+\mathrm{erfc}\left(\frac{k}{2\sqrt{t}}\right)$
$\frac{1}{\sqrt{s+a}(s+b)\sqrt{s+b}}$	
$\frac{e^{-\sqrt{s}}}{\sqrt{s}+1}$	$\frac{e^{-\frac{1}{4k}}}{\sqrt{\pi t}} - e^{t+1} \operatorname{erfc}\left(\sqrt{t} + \frac{1}{2\sqrt{t}}\right)$
$\frac{e^{-\sqrt{s}}}{s(\sqrt{s}+1)}$	$\operatorname{erfc}\left(\frac{1}{2\sqrt{t}}\right) - \operatorname{e}^{t+1}\operatorname{erfc}\left(\sqrt{t} + \frac{1}{2\sqrt{t}}\right)$

- K.J. Äström, R.M. Murray. Feedback Systems: An Introduction for Scientists and Engineers. Princeton University Press, 2008
- K.S. Miller, B. Ross. An Introduction to the Fractional Calculus and Fractional Differential Equations. New York: John Wiley and Sons, 1993
- I. Podlubny. Fractional Differential Equations, Mathematics in Science and Engineering, volume 198. San Diego: Academic Press, 1999
- 4. R.L. Magin. Fractional Calculus in Bioengineering. Begell House, 2006
- K.B. Oldham, J. Spanier. The Fractional Calculus. Theory and Applications of Differentiation and Integration of Arbitrary Order. New York: Dover, 2006
- S. Dugowson. Les Différentielles Métaphysiques: Histoire et Philosophie de la Généralisation de l'Ordre de Dérivation. Ph.D. thesis, University of Paris, 1994
- V. Kiryakova. Generalized Fractional Calculus and Applications. Number 301 in Pitman Research Notes in Mathematics. Essex: Longman Scientific & Technical, 1994
- R. Gorenflo, F. Mainardi. Fractional calculus: Integral and differential equations of fractional order. In A. Carpintieri, F. Mainardi eds., Fractals and Fractional Calculus in Continuum Mechanics. Springer Verlag, 1997
- 9. G. Mittag-Leffler. Sur la représentation analytique d'une branche uniforme d'une fonction monogene. Acta Mathematica, 1904, 29:101-181
- R. Gorenflo, Y. Luchko, S. Rogosin. Mittag-Leffler type functions: notes on growth properties and distribution of zeros. Preprint A-97-04, Freie Universität Berlin, 1997
- I. Podlubny. Numerical solution of ordinary fractional differential equations by the fractional difference method. In S. Elaydi, I. Gyori, G. Ladas eds., Advances in Difference Equations. Proceedings of the Second International Conference on Difference Equations. CRC Press, 1997
- S. Westerlund, L. Ekstam. Capacitor theory. IEEE Transactions on Dielectrics and Electrical Insulation, 1994, 1(5):826–839
- M. Cuadrado, R. Cabanes. Temas de Variable Compleja. Madrid: Servicio de Publicaciones de la ETSIT UPM, 1989
- D. Matignon. Stability properties for generalized fractional differential systems.
 D. Matignon, G. Montseny, eds., Proceedings of the Colloquium Fractional Differential Systems: Models, Methods and Applications, 5. Paris, 1998, 145–158
- S. Manabe. The non-integer integral and its application to control systems. Japanese Institute of Electrical Engineers Journal, 1961, 6(3-4):83–87
- A. Oustaloup. La Dérivation non Entière. Paris: Hermès, 1995
- A. Oustaloup, B. Mathieu. La Commande CRONE: du Scalaire au Multivariable. Paris: Hermès, 1999
- 18. K.J. Åström. Limitations on control system performance. Preprint, 1999

19. R.L. Bagley, P.J. Torvik. On the appearance of the fractional derivative in the behavior of real materials. Journal of Applied Mechanics, 1984, 51:294–298

- R.L. Bagley, R.A. Calico. Fractional-order state equations for the control of viscoelastic damped structures. J Guidance, Control and Dynamics, 1991, 14(2):304–311
- A. A. Kilbas, H. M. Srivastava, J. J. Trujillo. Theory and Applications of Fractional Differential Equations. North-Holland, 2006
- 22. K. Ogata. Modern Control Engineering, 4th edition. Prentice Hall, 2001
- R.A. Horn, C.R. Johnson. Topics in Matrix Analysis. Cambridge University Press, 1991
- M. Abramowitz, I.A. Stegun. Handbook of Mathematical Functions. Dover Publications, 1972
- D. Matignon, B. d'Andréa-Novel. Some resuts on controllability and observability of finite-dimensional fractional differential systems. http://www-sigenstfr/matignon
- 26. L. Zadeh, C.A. Desoer. Linear Systems Theory. McGraw-Hill, 1963
- 27. K.B. Oldham, J. Spanier. The Fractional Calculus. New York: Academic Press, 1974
- P. Ostalczyk. The non-integer difference of the discrete-time function and its application to the control system synthesis. International Journal of Systems Science, 2000, 31(12):1551–1561
- A. Dzieliński, D. Sierociuk. Stability of discrete fractional order state-space systems. Journal of Vibration and Control, 2008, 14(9-10):1543-1556
- S. Guermah, S. Djennoune, M. Bettayeb. Controllability and observability of linear discrete-time fractional-order systems. Int J Applied Mathematics and Computer Science, 2008, 18(2):213–222
- C.L. Phillips, Jr. H. Troy Nagle. Digital Control System. Analysis and Design. New Jersey, USA: Prentice Hall, 1984
- 32. D. Sierociuk. Fractional Order Discrete State-Space System Simulink Toolkit User Guide. [online] http://www.ee.pw.edu.pl/dsieroci/fsst/fsst.htm
- A. Dzieliński, D. Sierociuk. Simulation and experimental tools for fractional order control education. Proceedings of 17th World Congress The International Federation of Automatic Control, Seoul, Korea, July 6-11. IFAC WC 2008, 2008, 11654–11659
- 34. A. Dzieliński, D. Sierociuk. Observer for discrete fractional order-space state. Proceedings of the Second IFAC Workshop on Fractional Derivatives and Its Applications (FDA'06), Porto, Portugal, 2006
- D.L. Debeljković, M. Aleksendrić, N. Yi-Yong, et al. Lyapunov and non-Lyapunov stability of linear discrete time delay systems. Facta Universitatis, Series: Mechanical Engineering, 2002, 1(9):1147–1160
- 36. R. Hilfer. Applications of Fractional Calculus in Physics. World Scientific, 2000
- A. Dzieliński, D. Sierociuk. Reachability, controllability and observability of fractional order discrete state-space systems. Proceedings of the 13th IEEE/IFAC International Conference on Methods and Models in Automation and Robotics (MMAR'07), Szczecin, Poland, 2007
- L. Dorčak, I. Petráš, I. Koštial, et al. State-space controller design for the fractionalorder regulated aystem. Proceedings of the ICCC'2001. Krynica, Poland, 2001, 15–20
- D. Matignon, B. d'Andréa-Novel. Observer-based controllers for fractional differential systems. 36st IEEE-CSS SIAM Conference on Decision and Control, 1997
- Y.Q. Chen, H.S. Ahn, I. Podlubny. Robust stability check of fractional order linear time invariant systems with interval uncertainties. Signal Processing, 2006, 86:2611– 2618
- Y.Q. Chen, H.S. Ahn, D.Y. Xue. Robust controllability of interval fractional order linear time invariant systems. Signal Processing, 2006, 86:2794–2802
- 42. A. Si-Ammour, S. Djennoune, M. Bettayeb. A sliding mode control for linear fractional dystems with input and state delays. Communications in Nonlinear Science and Numerical Simulation, 2009, 14:2310–2318

 D. Sierociuk, A. Dzieliński. Fractional Kalman filter algorithm for states, parameters and order of fractional system estimation. International Journal of Applied Mathematics and Computer Science, 2006, 16(1):129–140

- 44. D. Sierociuk. Estimation and control of discrete dynamic fractional order state space systems. Ph.D. thesis, Warsaw University of Technology, 2007. In polish
- A. Dzieliński, D. Sierociuk. Adaptive feedback control of fractional order discrete state-space systems. Proceedings of International Conference on Computational Intelligence for Modelling Control and Automation, volume 1. CIMCA'2005, 2005, 804–809
- H. Bode. Relations between attenuation and phase in feedback amplifier design. Bell System Technical Journal, 1940, 19:421–454
- 47. H. Bode. Network Analysis and Feedback Amplifier Design. Van Nostrand, 1945
- B.M. Vinagre, C.A. Monje, A.J. Calderón, et al. The fractional integrator as a reference function. Proceedings of the First IFAC Workshop on Fractional Differentiation and Its Applications. ENSEIRB, Bordeaux, France, 2004, 150–155
- R.S. Barbosa, J.A. Tenreiro, I.M. Ferreira. A fractional calculus perspective of PID tuning. Proceedings of the ASME 2003 Design Engineering Technical Conferences and Computers and Information in Engineering Conference, Chicago, USA, 2003
- A. Oustaloup. La Commade CRONE: Commande Robuste d'Ordre Non Entier. Hermes, Paris, 1991
- 51. A. Oustaloup, F. Levron, F. Nanot, et al. Frequency band complex non integer differentiator: characterization and synthesis. IEEE Transactions on Circuits and Systems I: Fundamental Theory and Applications, 2000, 47(1):25–40
- 52. I. Podlubny. Fractional-order systems and $PI^{\lambda}D^{\mu}$ controllers. IEEE Transactions on Automatic Control, 1999, 44:208–214
- 53. B.M. Vinagre, I. Podlubny, L. Dorčák, et al. On fractional PID controllers: a frequency domain approach. Proceedings of the IFAC Workshop on Digital Control. Past, Present and Future of PID Control. Terrasa, Spain, 2000, 53–58
- R. Caponetto, L. Fortuna, D. Porto. Parameter tuning of a non integer order PID controller. 15th International Symposium on Mathematical Theory of Networks and Systems, Notre Dame, Indiana, 2002
- R. Caponetto, L. Fortuna, D. Porto. A new tuning strategy for a non integer order PID controller. Proceedings of the First IFAC Workshop on Fractional Differentiation and Its Application. ENSEIRB, Bordeaux, France, 2004, 168–173
- 56. J.F. Leu, S.Y. Tsay, C. Hwang. Design of optimal fractional-order PID controllers. Journal of the Chinese Institute of Chemical Engineers, 2002, 33(2):193–202
- 57. B.M. Vinagre. Modelado y Control de Sistemas Dinámicos Caracterizados por Ecuaciones Íntegro-Diferenciales de Orden Fraccional. PhD Thesis, Universidad de Educación a Distancia (UNED), Madrid, Spain, 2001
- 58. B. M. Vinagre, Y. Q. Chen. Lecture Notes on Fractional Calculus Applications in Automatic Control and Robotics. The 41st IEEE CDC2002 Tutorial Workshop # 2. Las Vegas, Nevada, USA, 2002, 1-310. [Online] http://mechatronics.ece.usu.edu/foc/cdc02_tw2_ln.pdf
- R.S. Barbosa, J.A. Tenreiro Machado. Describing function analysis of systems with impacts and backlash. Nonlinear Dynamics, 2002, 29(1-4):235–250
- R. Barbosa, J.A. Tenreiro, I.M. Ferreira. Tuning of PID controllers based on Bode's ideal transfer function. Nonlinear Dynamics, 2004, 38:305

 –321
- R. Barbosa, J.A. Tenreiro, I.M. Ferreira. PID controller tuning using fractional calculus concepts. Fractional Calculus and Applied Analysis, 2004, 7(2):119–134
- 62. Y.Q. Chen, K.L. Moore, B.M. Vinagre, et al. Robust PID controller autotuning with a phase shaper. Proceedings of the First IFAC Workshop on Fractional Differentiation and Its Application. ENSEIRB, Bordeaux, France, 2004, 162–167
- 63. C.A. Monje, A.J. Calderón, B.M. Vinagre. PI vs fractional DI control: first results. Proceedings of the CONTROLO 2002: 5th Portuguese Conference on Automatic Control. Aveiro, Portugal, 2002, 359–364

64. Y.Q. Chen, B.M. Vinagre, C.A. Monje. Une proposition pour la synthèse de correcteurs PI d'ordre non entier. Proceedings of the Action Thématique Les Systèmes à Dérivées Non Entières, LAP-ENSEIRB, Bordeaux, France, 2003

- C.A. Monje, B.M. Vinagre, V. Feliu, et al. Tuning and auto-tuning of fractional order controllers for industry applications. Control Engineering Practice, 2008, 16(7):798– 812
- R. Malti, M. Aoun, O. Cois, et al. Norm of fractional differential systems. Proceedings of the ASME 2003 Design Engineering Technical Conferences and Computers and Information in Engineering Conference, Chicago, USA, 2003
- I. Petráš, M. Hypiusova. Design of fractional-order controllers via H_∞ norm minimisation. Selected Topics in Modelling and Control, 2002, 3:50–54
- B.S.Y. Sánchez. Fractional-PID control for active reduction of vertical tail buffeting.
 MSc Thesis, Saint Louis University, St. Louis, USA, 1999
- A. Oustaloup, B. Mathieu, P. Lanusse. The CRONE control of resonant plants: application to a flexible transmission. European Journal of Control, 1995, 1(2):113–121
- D. Valério. Fractional order robust control: an application. Student forum, University of Porto, Portugal, 2001
- P. Lanusse, T. Poinot, O. Cois, et al. Tuning of an active suspension system using a fractional controller and a closed-loop tuning. Proceedings of the 11th International Conference on Advanced Robotics. Coimbra, Portugal, 2003, 258–263
- A.J. Calderón, B.M. Vinagre, V. Feliu. Linear fractional order control of a DC-DC buck converter. Proceedings of European Control Conference, Cambridge, UK, 2003
- A.J. Calderón. Control Fraccionario de Convertidores Electrónicos de Potencia tipo Buck. MS Thesis, Escuela de Ingenierías Industriales, Universidad de Extremadura, Badajoz, Spain, 2003
- V. Pommier, R. Musset, P. Lanusse, et al. Study of two robust control for an hydraulic actuator. ECC 2003: European Control Conference, Cambridge, UK, 2003
- C.A. Monje, F. Ramos, V. Feliu, et al. Tip position control of a lightweight flexible manipulator using a fractional order controller. IEE Proceeding-D: Control Theory and Applications, 2007, 1(5):1451–1460
- J.A. Tenreiro, A. Azenha. Fractional-order hybrid control of robot manipulators. Proceedings of the 1998 IEEE International Conference on Systems, Man and Cybernetics: Intelligent Systems for Humans in a Cyberworld, San Diego, California, USA. 1998, 788–793
- N.M. Fonseca, J.A. Tenreiro. Fractional-order hybrid control of robotic manipulators. Proceedings of the 11th International Conference on Advanced Robotics, Coimbra, Portugal. 2003, 393–398
- B.M. Vinagre, I. Petráš, P. Merchán, et al. Two digital realizations of fractional controllers: application to temperature control of a solid. Proceedings of the European Control Conference, Porto, Portugal. 2001, 1764–1767
- I. Petráš, B.M. Vinagre. Practical application of digital fractional-order controller to temperature control. Acta Montanistica Slovaca, 2002, 7(2):131–137
- I. Petráš, B.M. Vinagre, L. Dorčák, et al. Fractional digital control of a heat solid: experimental results. Proceedings of the International Carpathian Control Conference, Malenovice, Czech Republic. 2002, 365–370
- 81. J. Sabatier, P. Melchior, A. Oustaloup. Réalisation d'un banc d'essais thermique pour l'enseignement des systemes non entier. Proceedings of the Colloque sur l'Enseignement des Technologies et des Sciences de l'Information et des Systemes, Université Paul Sabatier, Toulouse, France. 2003, 361–364
- J. G. Zeigler, N. B. Nichols. Optimum settings for automatic controllers. Transactions of ASME, 1942, 64:759–768
- H.N. Koivo, J.N. Tanttu. Tuning of PID controllers: survey of SISO and MIMO techniques. Proceedings of Intelligent Tuning and Adaptive Control, Singapore, 1991

84. S. Yamamoto, I. Hasimoto. Present status and future needs: the view from Japanese industry. In Arkun and Ray *ed* Proceedings of 4th International Conference on Chemical Process Control, Texas, 1991

- 85. L. Debnath. A brief historical introduction to fractional calculus. Int J Math Educ Sci Technol, 2004, $35(4){:}487{-}501$
- R.L. Magin. Fractional calculus in bioengineering. Critical ReviewsTM in Biomedical Engineering, 2004, 32(1-4)
- 87. D.Y. Xue, Y.Q. Chen. A comparative introduction of four fractional order controllers. Proc. of The 4th IEEE World Congress on Intelligent Control and Automation (WCICA02). Shanghai, China: IEEE, 2002, 3228–3235
- Y.Q. Chen. Ubiquitous fractional order controls? Proc. of The Second IFAC Symposium on Fractional Derivatives and Applications (IFAC FDA06, Plenary Paper.). Porto, Portugal, 2006, 19–21
- D.Y. Xue, C.N. Zhao, Y.Q. Chen. Fractional order PID control of a DC-motor with an elastic shaft: a case study. Proceedings of American Control Conference. Minneapolis, Minnesota, USA, 2006, 3182–3187
- S. Manabe. The non-integer integral and its application to control systems. Japanese Institute of Electrical Engineers Journal, 1960, 80(860):589–597
- 91. A. Oustaloup. Linear feedback control systems of fractional order between 1 and 2. Proc. of the IEEE Symposium on Circuit and Systems. Chicago, USA, 1981,
- M. Axtell, E.M. Bise. Fractional calculus applications in control systems. Proc. of the IEEE 1990 Nat. Aerospace and Electronics Conf. New York, USA, 1990, 563–566
- J.A.T. Machado. Analysis and design of fractional-order digital control systems. J of Systems Analysis-Modeling-Simulation, 1997, 27:107

 –122
- J.A.T. Machado (Guest Editor). Special Issue on Fractional Calculus and Applications. Nonlinear Dynamics, 2002, 29:1–385
- M.D. Ortigueira and J.A.T. Machado (Guest Editors). Special Issue on Fractional Signal Processing and Applications. Signal Processing, 2003, 83(11):2285–2480
- 96. C. Ricardo, L. Fortuna, D. Porto. A new tuning strategy for a non integer order PID controller. Proc of 1st IFAC Workshop on Fractional Differentiation and its Applications, Bordeaux, France, 2004
- D. Valério, J.S. da Costa. Tuning-rules for fractional PID controllers. Proceedings of The Second IFAC Symposium on Fractional Differentiation and its Applications (FDA06), Porto, Portugal, 2006
- 98. C.A. Monje Micharet. Design Methods of Fractional Order Controllers for Industrial Applications. Ph.D. thesis, University of Extremadura, Spain, 2006
- 99. C.A. Monje Micharet. Auto-tuning of fractional PID controllers. IEEE Control System Society San Diego Chapter Meeting. In Trex Enterprises, San Diego, California, USA, 2005, Slides available at http://mechatronics.ece.usu.edu/foc/
- C.N. Zhao. Research on Analyse and Design Methods of Fractional Order System. Ph.D. thesis, Northeastern University, China, 2006
- K.J. Åström, H. Panagopoulos, T. Hägglund. Design of PI controllers based on nonconvex optimization. Automatica, 1998, 34(5):585–601
- K.J. Åström, H. Panagopoulos, T. Hägglund. Design of PID controllers based on constrained optimization. IEE Proceedings of Control Theory and Application, 2002, 149(1):32–40
- K.J. Åström, T. Hägglund. PID Controller: Theory, Design and Tuning. Research Triangle Park, NC: Instrument Society of America, 1995
- 104. K.J. Åström, T. Hägglund. Automatic Tuning of PID Controllers. Reading, MA: Instrumentation Society, 1998
- K.J. Åström, T. Hägglund. Revisiting the Ziegler-Nichols tuning rules for PI control. Asian Journal of Control, 2002, 4(4):364–380
- Y.Q. Chen, K.L. Moore. Analytical stability bound for a class of delayed fractionalorder dynamic systems. Nonlinear Dynamics, 2002, 29(1-4):191–200

107. B.J. Lurie. Three-parameter tunable tilt-integral-derivative (TID) controller. US Patent US5371670, 1994

- A. Oustaloup, X. Moreau, M. Nouillant. The CRONE suspension. Control Engineering Practice, 1996, 4(8):1101–1108
- A. Oustaloup, P. Melchoir, P. Lanusse, et al. The CRONE toolbox for MATLAB. Proc of the 11th IEEE International Symposium on Computer Aided Control System Design, Anchorage, USA, 2000
- 110. C.A. Monje, B.M. Vinagre, Y.Q. Chen, et al. Proposals for fractional PI^λD^μ tuning. Proceedings of The First IFAC Symposium on Fractional Differentiation and its Applications (FDA04), Bordeaux, France, 2004
- C.N. Zhao, D.Y. Xue, Y.Q. Chen. A fractional order PID tuning algorithm for a class of fractional order plants. Proceedings of the International Conference on Mechatronics and Automation. Niagara, Canada, 2005, 216–221
- A. Oustaloup, J. Sabatier, P. Lanusse. From fractional robustness to CRONE control. Fractional Calculus and Applied Analysis, 1999, 2(1):1–30
- R.C. Dorf, R.H. Bishop. Modern Control Systems. Upper Saddle River: Pearson Education, 2005
- 114. Y. Tarte, Y.Q. Chen, W. Ren, et al. Fractional horsepower dynamometer a general purpose hardware-in-the-loop real-time simulation platform for nonlinear control research and education. Proceedings of IEEE Conference on Decision and Control. San Diego, California, USA, 2006, 3912–3917
- G. Franklin, J. Powell, A. Naeini. Feedback Control of Dynamic Systems. Addison-Wesley, 1986
- Y.Q. Chen, C.H. Hu, K.L. Moore. Relay feedback tuning of robust PID controllers with iso-damping property. Proceedings of the 42nd IEEE Conference on Decision and Control. Hawaii, USA, 2003, 347–352
- 117. J. Pintér. Global Optimization in Action. The Netherlands: Kluwer Academic Publishers, 1996
- 118. W.S. Levine. The Control Handbook. CRC Press and IEEE Press, 1996
- 119. A. Oustaloup. From fractality to non integer derivation through recursivity, a property common to these two concepts: a fundamental idea from a new process control strategy. Proceedings of the 12th IMACS World Congress. Paris, France, 1998, 203–208
- H.F. Raynaud, A. Zergaïnoh. State-space representation for fractional order controllers. Automatica, 2000, 36:1017–1021
- S.B. Skaar, A.N. Michel, R.K. Miller. Stability of viscoelastic control systems. IEEE Transactions on Automatic Control, 1998, 33(4):348–357
- 122. C.A. Monje, A.J. Calderón, B.M. Vinagre, et al. The fractional order lead compensator. Proceedings of the IEEE International Conference on Computational Cybernetics. Vienna, Austria, 2004, 347–352
- 123. C. A. Monje, B. M. Vinagre, A. J. Calderón, et al. Auto-tuning of fractional leadlag compensators. Proceedings of the 16th IFAC World Congress, Prague, Czech Republic, 2005
- K.K. Tan, S. Huang, R. Ferdous. Robust self-tuning PID controller for nonlinear systems. Journal of Process Control, 2002, 12(7):753–761
- C.C. Hang, K.J. Åström, Q.G. Wang. Relay feedback auto-tuning of process controllers — a tutorial review. Journal of Process Control, 2002, 12:143–162
- 126. D. Valério. Fractional Robust System Control. Ph.D. thesis, Instituto Superior Técnico, Universidade Técnica de Lisboa, 2005
- I.D. Landau, D. Rey, A. Karimi, et al. A flexible transmission system as a benchmark for robust digital control. European Journal of Control, 1995, 1(2):77–96
- D.F. Thomson. Optimal and Sub-Optimal Loop Shaping in Quantitative Feedback Theory. West Lafayette, IN, USA: School of Mechanical Engineering, Purdue University, 1990

 A. Gera, I. Horowitz. Optimization of the loop transfer function. International Journal of Control, 1980, 31:389–398

- C.M. Frannson, B. Lenmartson, T. Wik, et al. Global controller optimization using Horowitz bounds. Proceedings of the IFAC 15th Trienial World Congress, Barcelona, Spain, 2002
- Y. Chait, Q. Chen, C.V. Hollot. Automatic loop-shaping of QFT controllers via linear programming. ASME Journal of Dynamic Systems, Measurements and Control, 1999, 121:351–357
- W.H. Chen, D.J. Ballance, Y. Li. Automatic Loop-Shaping of QFT using Genetic Algorithms. Glasgow, UK: University of Glasgow, 1998
- 133. C. Raimúndez, A. Ba nos, A. Barreiro. QFT controller synthesis using evolutive strategies. Proceedings of the 5th International QFT Symposium on Quantitative Feedback Theory and Robust Frequency Domain Methods. Pamplona, Spain, 2001, 291–296
- J. Cervera, A. Baños. Automatic loop shaping QFT using CRONE structures. Journal of Vibration and Control, 2008, 14:1513–1529
- 135. J. Cervera, A. Baños. Automatic loop shaping in QFT by using a complex fractional order terms controller. Proceedings of the 7th International Symposium on QFT and Robust Frequency, University of Kansas, USA, 2005
- 136. I. Horowitz. Quantitative Feedback Design Theory QFT (Vol.1). Boulder, Colorado, USA: QFT Press, 1993
- I. Horowitz. Optimum loop transfer function in single-loop minimum-phase feedback systems. International Journal of Control, 1973, 18:97–113
- B.J. Lurie, P.J. Enright. Classical Feedback Control with MATLAB. New York, USA: Marcel Dekker, 2000
- 139. J. Cervera, A. Baños, C.A. Monje, et al. Tuning of fractional PID controllers by using QFT. Proceedings of the 32nd Annual Conference of the IEEE Industrial Electronics Society, IECON'06, Paris, France, 2006
- C. Edwards, S.K. Spurgeon. Sliding Mode Control. Theory and Applications. Taylor and Francis, 1998
- 141. V. Utkin. Variable structure systems with sliding modes. IEEE Transactions on Automatic Control, 1977, 22:212–222
- A.J. Calderón, B.M. Vinagre, V. Feliu. Fractional order control strategies for power electronic buck converters. Signal Processing, 2006
- K.J. Astrom, B. Wittenmark. Adaptive Control. Second Edition. Reading: Addison-Wesley Publishing Company Inc., 1995
- 144. C.C. Hang, P.C. Parks. Comparative studies of model reference adaptive control systems. IEEE Transaction on Automatic Control, 1973, 18:419–428
- 145. J.C. Clegg. A nonlinear integrator for servomechanism. Trans AIEE, 1958, 77:41–42
- J. Liu. Comparative Study of Differentiation and Integration Techniques for Feedback Control Systems. Ph.D. thesis, Cleveland State University, Cleveland, 2002
- 147. H. Hu, Y. Zheng, Y. Chait, et al. On the zero-input stability of control systems with Clegg integrators. Proceedings of the American Control Conference. Alburquerque, Nw Mexico, USA, 1997, 408–410
- 148. Y.Q. Chen, K.L. Moore. Discretization schemes for fractional-order differentiators and integrators. IEEE Transactions on Circuits and Systems-I: Fundamental Theory and Applications, 2002, 49(3):363–367
- L. Zaccarian, D. Nesic, A.R. Teel. First order reset elements and the Clegg integrator revisited. Proceedings of the American Control Conference. Portland, Oregon, USA, 2005, 563–568
- O. Beker, C.V. Hollot, Y. Chait, et al. Fundamental properties of reset control systems. Automatica, 2004, 40:905–915
- A. Gelb, W.E. Vander. Multiple-Input Describing Functions and Nonlinear System Design. McGraw-Hill, 1968

 D.P. Atherton. Nonlinear Control Engineering — Describing Function Analysis and Design. London: Van Nostrand Reinhold Co., 1975

- 153. K.H. Johansson. The quadruple-tank process: A multivariable laboratory process with an adjustable zero. IEEE Transactions on Control Systems Technology, 2000, 8(3):456–465
- 154. I. Petráš, I. Podlubny, P. O'Leary. Analogue Realization of Fractional Order Controllers. Fakulta BERG, TU Košice, 2002
- 155. G.W. Bohannan. Analog realization of a fractional controller, revisited. In: BM Vinagre, YQ Chen, eds, Tutorial Workshop 2: Fractional Calculus Applications in Automatic Control and Robotics, Las Vegas, USA, 2002
- M. Ichise, Y. Nagayanagi, T. Kojima. An analog simulation of non-integer order transfer functions for analysis of electrode processes. Journal of Electroanalytical Chemistry, 1971, 33:253–265
- K.B. Oldham. Semiintegral electroanalysis: Analog implementation. Analytical Chemistry, 1973, 45(1):39–47
- 158. M. Sugi, Y. Hirano, Y.F. Miura, et al. Simulation of fractal immittance by analog circuits: An approach to optimized circuits. IEICE Trans Fundamentals, 1999, E82-A(8):1627–1635
- I. Podlubny, I. Petráš, B.M. Vinagre, et al. Analogue realizations of fractional-order controllers. Nonlinear Dynamics, 2002, 29(1-4):281–296
- 160. B.M. Vinagre, I. Podlubny, A. Hernández, et al. Some approximations of fractional order operators used in control theory and applications. Fractional Calculus and Applied Analysis, 2000, 3(3):231–248
- 161. D.Y. Xue, Y.Q. Chen. Sub-optimum H₂ pseudo-rational approximations to fractional order linear time invariant systems. In: J. Sabatier, J. Machado, O. Agrawal, eds., Advances in Fractional Calculus: Theoretical Developments and Applications in Physics and Engineering. Springer Verlag, 2007, 61–75
- 162. D. Valério. Ninteger Toolbox. [online] http://www.mathworks.com/matlabcentral/fileexchange/8312-ninteger
- 163. D.Y. Xue, C.N. Zhao, Y.Q. Chen. A modified approximation method of fractional order system. Proceedings of IEEE Conference on Mechatronics and Automation. Luoyang, China, 2006, 1043–1048
- 164. B.M. Vinagre, I. Podlubny, A. Hernandez, et al. On realization of fractional-order controllers. Proc of the Conference Internationale Francophone d'Automatique, Lille, France, 2000
- 165. B.M. Vinagre, Y.Q. Chen, I. Petras. Two direct Tustin discretization methods for fractional-order differentiator/integrator. The Journal of Franklin Institute, 2003, 340(5):349–362
- Y.Q. Chen, B.M. Vinagre. A new IIR-type digital fractional order differentiator. Signal Processing, 2003, 83(11):2359–2365
- 167. M. A. Al-Alaoui. Novel digital integrator and differentiator. Electronics Letters, 1993, 29(4):376–378
- 168. M. A. Al-Alaoui. A class of second-order integrators and low-pass differentiators. IEEE Trans on Circuit and Systems I: Fundamental Theory and Applications, 1995, 42(4):220–223
- 169. M. A. Al-Alaoui. Filling the gap between the bilinear and the backward difference transforms: an interactive design approach. Int J of Electrical Engineering Education, 1997, 34(4):331–337
- C.C. Tseng, S.C. Pei, S.C. Hsia. Computation of fractional derivatives using Fourier transform and digital FIR differentiator. Signal Processing, 2000, 80:151–159
- 171. C.C. Tseng. Design of fractional order digital FIR differentiator. IEEE Signal Processing Letters, 2001, 8(3):77–79
- 172. Y.Q. Chen, B.M. Vinagre, I. Podlubny. A new discretization method for fractional order differentiators via continued fraction expansion. Proc. of The First Symposium

- on Fractional Derivatives and Their Applications at The 19th Biennial Conference on Mechanical Vibration and Noise, the ASME International Design Engineering Technical Conferences & Computers and Information in Engineering Conference (ASME DETC2003). Chicago, Illinois, 2003, 1–8, DETC2003/VIB--48391
- 173. I. Petráš. Digital fractional order differentiator/integrator FIR type. [online] http://www.mathworks.com/matlabcentral/fileexchange/3673
- 174. The MathWorks Inc. MATLAB Control System Toolbox, User's Guide, 2000
- 175. Y.Q. Chen. Contributed files to MATLAB Central. [online] http://www.mathworks.com/matlabcentral/fileexchange/authors/9097
- 176. The MathWorks, Inc. MATLAB Signal Processing Toolbox. User's Guide, 2000
- D. Xue, D. P. Atherton. A suboptimal reduction algorithm for linear systems with a time delay. International Journal of Control, 1994, 60(2):181–196
- K.J. Åström. Introduction to Stochastic Control Theory. London: Academic Press, 1970
- 179. W. H. Press, B. P. Flannery, S. A. Teukolsky. Numerical Recipes, the Art of Scientific Computing. Cambridge: Cambridge University Press, 1986
- 180. F.S. Wang, W.S. Juang, C.T. Chan. Optimal tuning of PID controllers for single and cascade control loops. Chemical Engineering Communications, 1995, 132:15–34
- 181. D.Y. Xue, Y.Q. Chen. Advanced Applied Mathematical Problem Solutions with MATLAB. Beijing: Tsinghua University Press, 2004. In Chinese
- D.Y. Xue, Y.Q. Chen. Solving Applied Mathematical Problems with MATLAB. Boca Raton: CRC Press, 2008
- D.Y. Xue, Y.Q. Chen, D.P. Atherton. Linear Feedback Control Analysis and Design with MATLAB. Philadelphia: SIAM Press, 2007
- 184. I. Podlubny. Mittag-Leffler function, [online] http://www.mathworks.com/matlabcentral/fileexchange/8738, 2005
- A.K. Shukla, J.C. Prajapati. On a generalization of Mittag-Leffler function and its properties. Journal of Mathematical Analysis and Applications, 2007, 336(1):797–811
- 186. A.A. Kilbas, M. Saigob, R.K. Saxena. Generalized Mittag-Leffler function and generalized fractional calculus operators. Integral Transforms and Special Functions, 2004, 15(1):31–49
- 187. The MathWorks Inc. Simulink User's Guide, 2009
- 188. C.R. Houck, J.A. Joines, M.G. Kay. A Genetic Algorithm for Function Optimization: a MATLAB Implementation. Electronic version of the GAOT Manual, 1995
- The MathWorks Inc. Genetic Algorithm and Direct Search Toolbox, 2009
- V. Feliu, S. Feliu. A method of obtaining the time domain response of an equivalent circuit model. Journal of Electroanalytical Chemistry, 1997, 435(1–2):1–10
- 191. L. Ljung. System Identification. Theory for the User. Prentice Hall, 1987
- 192. R. Pintelon, P. Guillaume, Y. Rolain, et al. Parametric identification of transfer functions in the frequency domain: A survey. IEEE Transactions on Automatic Control, 1994, 39(11):2245–2259
- Ch.M.A. Brett, A.M. Oliveira. Electrochemistry Principles. Methods and Applications. Oxford University Press, 1983
- 194. R. de Levie. Fractals and rough electrodes. Journal of Electroanalytical Chemistry, 1990, $281:1\hbox{--}21$
- R. de Levie, A. Vogt. On the electrochemical response of rough electrodes. Journal of Electroanalytical Chemistry, 1990, 281:23–28
- A.A. Pilla. A transient impedance technique for the study of electrode kinetics.
 Journal of Electrochemical Society, 1970, 117(4):467–477
- P. Agarwal, M.E. Orazem. Measurement models for electrochemical impedance spectroscopy. Journal of Electrochemical Society, 1992, 139(7):1917–1927
- A. Sadkowski. Time domain responses of constan phase electrodes. Electrochimica Acta, 1993, 38(14):2051–2054
- 199. F.H. van Heuveln. Analysis of nonexponential transient response due to a constantphase element. J Electrochem Soc, 1994, 141(12):3423–3428

200. A.A. Sagüés, S.C. Kraus, E.I. Moreno. The time-domain response of a corroding system with constant phase angle interfacial component: Application to steel in concrete. Corrosion Science, 1995, 37(7):1097–1113

- H. Schiessel, R. Metzler, A. Blumen, et al. Generalized viscoelastic models: their fractional equations with solutions. J Physics A: Math Gen, 1995, 28:6567–6584
- 202. S.S. Rao. Mechanical Vibrations. Addison-Wesley, 1990
- 203. H.R. Pota, T.E. Alberts. Multivariable transfer functions for a slewing piezoelectric laminate beam. ASME Journal of Dynamic Systems, Measurements, and Control, 1995, 117
- F. Wang, Y. Gao. Advanced Studies of Flexible Robotic Manipulators, Modeling, Design, Control and Applications. New Jersey, USA: World Scientific, 2003
- A. Benosman, G. Le Vey. Control of flexible manipulators: A survey. Robotica, 2004, 22(5):533-545
- M. Zinn, O. Khatib, B. Roth, et al. Playing it safe [Human-Friendly Robots]. IEEE Robotics and Automation Magazine, 2004, 11(2):12–21
- S.K. Dwivedy, P. Eberhard. Dynamic analysis of flexible manipulators, a literature review. Mechanism and Machine Theory, 2006, 41(7):749-777
- V. Feliu. Robots flexibles: Hacia una generación de robots con nuevas prestaciones.
 Revista Iberoamericana de Automática e Informática Industrial, 2006, 3(3):24-41
- W.J. Book. Modeling, Design and Control of Flexible Manipulator Arms. Ph.D. thesis, Department of Mechanical Engineering, Massachusetts Institute of Technology, Cambridge MA, 1974
- O. Maizza-Neto. Modal Analysis and Control of Flexible Manipulator Arms. Ph.D. thesis, Department of Mechanical Engineering, Massachusetts Institute of Technology, Cambridge MA, 1974
- 211. W.J. Book, O. Maizza-Neto, D.E. Whitney. Feedback control of two beam, two joint systems with distributed flexibility. Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME, 1975, 97G(4):424–431
- J. Denavit, R.S. Hartenberg. A kinematic notation for lower-pair mechanisms based on matrices. ASME Journal of Applied Mechanics, 1955, June:215–221
- W.J. Book. Recursive Lagrangian dynamics of flexible manipulator arms. International Journal of Robotics Research, 1984, 3(3):87–101
- M.J. Balas. Active control of flexible systems. Journal of Optimisation Theory and Applications, 1978, 25(3):415–436
- M.J. Balas. Trends in large space structures control theory: Fondest hopes, wildest dreams. IEEE Transactions on Automatic Control, 1982, 27(3):522–535
- R.H. Cannon, E. Schmitz. Initial experiments on the end-point control of a flexible robot. International Journal on Robotics Research, 1984, 3(3):62–75
- A. De Luca, B. Siciliano. Trajectory control of a non-linear one-link flexible arm. International Journal of Control, 1989, 50(5):1699-1715
- E. Bayo. A finite-element approach to control the end-point motion of a single-link flexible robot. Journal of Robotics Systems, 1987, 4(1):63-75
- D. Wang, M. Vidyasagar. Transfer functions for a single flexible link. International Journal on Robotics Research, 1991, 10(5):540–549
- W.J. Book. Controlled motion in an elastic world. Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME, 1993, 115(2):252–261
- J.H. Yang, F.L. Lian, L.C. Fu. Nonlinear adaptive control for flexible-link manipulators. IEEE Transactions on Robotics and Automation, 1997, 13(1):140–148
- T.C. Yang, J.C.S. Yang, P. Kudva. Load adaptive control of a single-link flexible manipulator. IEEE Transactions on Systems, Man and Cybernetics, 1992, 22(1):85–91
- J.J. Feliu, V. Feliu, C. Cerrada. Load adaptive control of single-link flexible arms based on a new modeling technique. IEEE Transactions on Robotics and Automation, 1999, 15(5):793–804

224. K. Takahashi, I. Yamada. Neural-network-based learning control of flexible mechanism with application to a single-link flexible arm. Journal of Dynamic Systems Measurement and Control, Transactions of the ASME, 1994, 116(4):792–795

- 225. M. Isogai, F. Arai, T. Fukuda. Modeling and vibration control with neural network for flexible multi-link structures. Proceedings of the IEEE International Conference on Robotics and Automation. San Diego, USA, 1999, 1096–1101
- A.C. Huang, Y.C. Chen. Adaptive sliding control for single-link flexible-joint robot with mismatched uncertainties. IEEE Transactions on Control Systems Technology, 2004, 12(5):770-775
- 227. S.B. Choi, C.C. Cheong, H.C. Shin. Sliding mode control of vibration in a single-link flexible arm with parameter variations. Journal of Sound and Vibration, 1995, 179:737–748
- V. Feliu, J. A. Somolinos, C. Cerrada, et al. A new control scheme of single-link flexible manipulators robust to payload changes. Journal of Intelligent and Robotic Systems, 1997, 20:349–373
- S.S. Ge, T.H. Lee, G. Zhu. Energy-based robust controller design for multi-link flexible robots. Mechatronics, 1996, 6(7):779-798
- V. Feliu, F. Ramos. Strain gauge based control of single-link very lightweight flexible robots to payload changes. Mechatronics, 2005, 15(5):547–571
- 231. I.D. Landau, J. Langer, D. Rey, et al. Robust control of a 360 degrees flexible arm using the combined pole placement/sensitivity function shaping method. IEEE Transactions on Control Systems Technology, 1996, 4(4):369–383
- J. Daafouz, G. García, J. Bernussou. Robust control of a flexible robot arm using the quadratic D-stability approach. IEEE Transactions on Control Systems Technology, 1998, 6(4):524–533
- 233. H.R. Karimi, M.K. Yazdanpanah, R.V. Patel, et al. Modeling and control of linear two-time scale systems: Applied to single-link flexible manipulator. Journal of Intelligent and Robotics Systems, 2006, 45(3):235–265
- 234. L.Y. Pao, W.E. Singhose. Robust minimum time control of flexible structures. Automatica, 1998, 34(2):229–236
- V. Feliu, K.S. Rattan, H.B. Brown Jr. Control of flexible arms with friction in the joints. IEEE Transactions on Robotics and Automation, 9(4):467–475
- 236. V. Feliu, B.M. Vinagre, C.A. Monje. Fractional control of a single-link flexible manipulator. Proceedings of the ASME International Design Engineering Technical Conference and Computer and Information in Engineering Conference, Long Beach, California, USA, 2005
- 237. C.A. Monje, A.J. Calderón, B.M. Vinagre, et al. On fractional PI^{λ} controllers: Some tuning rules for robustness to plant uncertainties. Nonlinear Dynamics, 2004, 38(1-4):369–381
- 238. D. Valério, J. Sá Da Costa. Ziegler-Nichols type tuning rules for fractional PID controllers. Proceedings of the ASME International Design Engineering Technical Conference and Computer and Information in Engineering Conference, Long Beach, California, USA, 2005
- C.O. Stockle. Environmental impact of irrigation. Proceedings of the IV International Congress of Agricultural Engineering, Chillan, Chile, 2001
- 240. P.O. Malaterre, D.C. Rogers, J. Schuurmans. Classification of canal control algorithms. Journal of Irrigation and Drainage Engineering, 1998, 124(1):3–10
- X. Litrico, D. Georges. Robust continuous-time and discrete-time flow control of a dam-river system. (I) Modelling. Applied Mathematical Modelling, 1999, 23:809–827
- X. Litrico, V. Fromion. Advanced control politics and optimal performance for irrigation canal. Proceedings of the European Control Conference. Cambridge, UK, 2003,
- 243. B.T. Wahlin, A.J. Clemmens. Automatic downstream water-level feedback control of branching canal networks: theory. Journal of Irrigation and Drainage Engineering, 2006, 132(3):198–207

P.O. Malaterre. Regulation of irrigation canals: characterization and classification.
 International Journal of Irrigation and Drainage Systems, 1995, 9(4):297–327

- 245. A.J. Clemmens. Canal automation. Resource Magazine, 2006, 9:7-8
- F. Liu, F. Feyen, J. Berlamont. Downstream control of multireach canal systems. Journal of Irrigation and Drainage Engineering, 1995, 121(2):179–190
- E. Weyer. System identification of an open water channel. Control Engineering Practice, 2001, 9(12):1289–1299
- J. Schuurmans, A.J. Clemmens, S. Dijkstra, et al. Modeling of irrigation and drainage canals for controller design. Journal of Irrigation and Drainage Engineering, 1999, 125(6):338–344
- 249. X. Litrico, V. Fromion. H_∞ control of an irrigation canal pool with a mixed control politics. IEEE Transactions on Control Systems Technology, 2006, 14(1):99–111
- R.R. Pérez, V. Feliu, L.S. Rodríguez. Robust system identification of an irrigation main canal. Advances in Water Resources, 2007, 130:1785–1796
- X. Litrico. Nonlinear diffusive wave modeling and identification of open channels. Journal of Hydraulic Engineering, 2001, 127(4):313–320
- J.L. Deltour, F. Sanfilippo. Introduction of Smith predictor into dynamic regulation.
 Journal of Irrigation and Drainage Engineering, 1998, 124(1):3–30
- J.P. Baume, P.O. Malaterre, J. Sau. Tuning of PI controllers for an irrigation canal using optimization tools. Proceedings of the Workshop on Modernization of Irrigation Water Delivery Systems. Phoenix, Arizona, USA, 1999, 483–500
- 254. A.J. Clemmens, J. Schuurmans. Simple optimal downstream feedback canal controllers: theory. Journal of Irrigation and Drainage Engineering, 2004, 130(1):26–34
- 255. A.J. Clemmens, B.T. Wahlin. Simple optimal downstream feedback canal controllers: ASCE test case results. Journal of Irrigation and Drainage Engineering, 2004, 130(1):35–46
- A. Montazar, P.J. Van Overloop, R. Brouver. Centralized controller for the Narmada main canal. Irrigation and Drainage, 2005, 54(1):79–89
- 257. K. Akouz, A. Benhammou, P.O. Malaterre, et al. Predictive control applied to ASCE canal 2. Proceedings of the IEEE International Conference on Systems, Man & Cybernetics. San Diego, USA, 1998, 3920–3924
- X. Litrico, V. Fromion, J.P. Baume. Tuning of robust distant downstream PI controllers for an irrigation canal pool. II: Implementation issues. Journal of Irrigation and Drainage Engineering, 2006, 132(4):369–379
- V. Feliu, R.R. Pérez, L.S. Rodríguez. Fractional robust control of main irrigation canals with variable dynamic parameters. Control Engineering Practice, 2007, 15(6):673–686
- V. Feliu, R.R. Pérez, L.S. Rodríguez, et al. Robust fractional order PI controller implemented on a hydraulic canal. Journal of Hydraulic Engineering, 2009, 135(5):271–282
- V. Feliu, R.R. Pérez, F.J.C. García, et al. Smith predictor based robust fractional order control: Application to water distribution in a main irrigation canal pool. Journal of Process Control, 2009, 19(3):506–519
- V. Feliu, R.R. Pérez, F.J.C. García. Fractional order controller robust to time delay for water distribution in an irrigation main canal pool. Computers and Electronics in Agriculture, 2009, 69(2):185–197
- 263. V.T. Chow. Open-Channels Hydraulics. New York, USA: McGraw-Hill, 1988
- X. Litrico, V. Fromion. Analytical approximation of open-channel flow for controller design. Applied Mathematical Modelling, 2004, 28:677

 –695
- 265. M.H. Chaudhry. Open-Channels Flow. Englewoods Clifs: Prentice-Hall, 1993
- 266. P.I. Kovalenko. Automation of Land Reclamation Systems. Moscow: Kolos, 1983
- C.M. Burt, R.S. Mills, R.D. Khalsa, et al. Improved proportional integral (PI) logic for canal automation. Journal of Irrigation and Drainage Engineering, 1998, 124(1):53–57

268. V. Feliu, R. Rivas Pérez, L. Sánchez Rodríguez, et al. Robust fractional order PI controller for a main irrigation canal pool. Proceedings of the 17th International Federation of Automatic Control World Congress, Seoul, South Korea, 2008

- X. Litrico, V. Fromion, J.P. Baume, et al. Experimental validation of a methodology to control irrigation canals based on Saint-Venant equations. Control Engineering Practice, 2005, 13(11):1341–1454
- S.K. Ooi, M.P.M. Krutzen, E. Weyer. On physical and data driven modelling of irrigation channels. Control Engineering Practice, 2005, 13(4):461–471
- G. Corriga, S. Sanna, G. Usai. Estimation of uncertainty in an open-channel network mathematical model. Applied Mathematical Modelling, 1989, 13:651–657
- J.P. Baume, J. Sau, P.O. Malaterre. Modeling of irrigation channel dynamics for controller design. Proceedings of the IEEE International Conference on Systems, Man & Cybernetics (SMC98), San Diego, California, USA, 1998
- 273. R. Rivas Pérez, V. Feliu, F.J. Castillo García, et al. System identification for control of a main irrigation canal pool. Proceedings of the 17th International Federation of Automatic Control World Congress, Seoul, South Korea, 2008
- 274. V. Feliu, R. Rivas Pérez, F.J. Castillo García. Fractional robust control to delay changes in main irrigation canals. Proceedings of the 16th International Federation of Automatic Control World Congress, Prague, Czech Republic, 2005
- 275. B.T. Wahlin, A.J. Clemmens. Performance of historic downstream canal control algorithms on ASCE test canal 1. Journal of Irrigation and Drainage Engineering, 2002, 128(6):365–375
- 276. R. Rivas Pérez, J.R. Perán González, B. Pineda Reyes, et al. Distributed control under centralized intelligent supervision in the Gira de Melena Irrigation System. Ingeniería Hidráulica en México, 2003, 18(2):53–68
- 277. P.J. van Overloop. Model Predictive Control on Open Water Systems. The Netherlands: IOS Press Inc, 2006
- M. J. Shand. Automatic downstream control systems for irrigation Canals. Ph.D. thesis, University of California, Berkeley, USA, 1971
- Z.J. Palmor, Y. Halevi. On the design and properties of multivariable dead time compensators. Automatica, 1983, 19:255–264
- D.L. Laughlin, D.E. Rivera, M. Morari. Smith predictor design for robust performance. International Journal of Control, 1987, 46:477–504
- Z.J. Palmor. The Control Handbook. Time Delay Compensation: Smith Predictor and its Modifications. New York, USA: CRC Press and IEEE Press, 1996
- 282. F.J. Castillo García, R. Rivas Pérez, V. Feliu. Fractional I^{α} controller combined with a Smith predictor for effective water distribution in a main irrigation canal pool. Proceedings of the 17th International Federation of Automatic Control World Congress, Seoul, South Korea, 2008
- R. Rivas Pérez. Automatic control of water distribution in irrigation systems. Ph.D. thesis, Institute of Hydraulic Engineering and Land Reclamation, Ukrainian Academy of Agricultural Sciences, Kiev, Ukraine, 1990
- 284. T. Hägglund. An industrial dead-time compensating PI controller. Control Engineering Practice, 1996, 4(6):749–756
- K.J. Aström, B. Wittenmark. Computer Controlled Systems: Theory and Design. Englewoods Clifs, New Jersey, USA: Prentice-Hall, 1997
- 286. T.H. Lee, Q.G. Wang. Robust Smith-predictor controller for uncertain delay systems. AIChE Journal, 1996, 42(4):1033–1040
- 287. A.J. Calderón, C.A. Monje, B.M. Vinagre, et al. Implementación de controladores de orden fraccionario mediante autómatas programables. Proceedings of the XXV Jornadas de Automatica, Ciudad Real, Spain, 2004
- T. Habetler, R. Harley. Power electronic converter and system control. Proceeding of the IEEE, 2001, 89(6):913–924

289. H. Sira-Ramirez. A geometric approach to pulse-width-modulated control design. Proceedings of the 26th IEEE Conference on Decision and Control. Los Angeles, CA, USA, 1987, 1771–1776

- S.L. Jung, Y.Y. Tzou. Discrete sliding-mode control of a PWM inverter for sinusoidal output waveform synthesis with optimal sliding curve. IEEE Transactions on Power Electronics, 1996, 11(4):567–577
- G. Spiazzi, P. Mattavelli, L. Rossetto. Sliding mode control of DC-DC converters. 4
 Congresso Brasileiro de Electronica de Potencia, Belo Horizonte, Brasil, 1997, 59–68
- R. Middlebrook, S. Cuk. A general unified approach to modelling switching-converter power stages. International Journal of Electronics, 1977, 42(6):521–550
- 293. J. Agrawal. Power Electronic Systems: Theory and Design. Prentice Hall, 2001
- 294. I. de la Nuez, V. Feliu. On the voltage pulse-width modulation control of L-C filters. IEEE Transaction on Circuits and Systems I: Fundamental Theory and Applications, 2000, 47(3):338–349
- 295. J. Alvarez-Ramírez, I. Cervantes, G. Espinosa-Pérez, et al. A stable design of PI for DC-DC converters with an RHS zero. IEEE Transaction on Circuits and Systems I: Fundamental Theory and Applications, 2001, 48(1):103–106
- 296. R. Martin, I. Aspiazu, I. de la Nuez. Sliding control of a buck converter with variable load. IASTED International Conference Control and Applications, Banf, Canada, 1999
- 297. M. Castilla, I. García de Vicuña, M. López. On the design of sliding mode control schemes for quantum resonant converters. IEEE Transactions on Power Electronics, 2000, 15(6):960–973
- 298. L. Dorčak, I. Petráš, I. Kostial. Modeling and analysis of fractional-order regulated systems in the state-space. Proceedings of the International Carpathian Control Conference. High Tatras, Podbanské, Slovak Republic, 2000, 185–188
- A.J. Calderón. Fractional Control of Power Electronic Buck Converters. Ph.D. thesis, Industrial Engineering School, University of Extremadura, 2003
- 300. Y.Q. Chen, I. Petráš, B.M. Vinagre. A list of Laplace and inverse Laplace transforms related to fractional order calculus. [online] http://www.steveselectronics.com/petras/foc_laplace.pdf, 2007

accelerometer, 266, 282	modal canonical form, see modal
active suspension, 76	canonical form
actuator saturation, 128, 250, 254, 273, 327, 331	observable form, see observable canonical form
adaptation gain, 175, 176, 178	Caputo's definition, 11, 13, 36, 43, 214,
adaptive control, 74, 174, 188, 287	217, 220
AMIGO method, 101, 102	Cauchy principal value, 21
anomalous relaxation, 14, 259	Cauchy's argument principle, 23
antiderivative, 5	Cauchy's formula, 6, 7, 10, 218, 219
arbitrary order, 4, 9	Cayley–Hamilton method, 46–53
argument principle, 23	Cayley–Hamilton Theorem, 46
armature circuit current, 280	CFE, see continued fraction expansion
asymptotic stability, 376	characteristic equation, 22, 25, 26, 42, 46,
auto-tuning, 76, 133, 141–147, 353, 358,	170, 178
359	characteristic parameter, 32
	characteristic polynomial, 22
bilinear transformation, 198	charge transfer, 262
binomial coefficient, 7, 218, 222	Clegg integrator, 181–183
block diagram, 77, 78, 176, 212, 213,	closed-form solution, 159, 213, 221–223,
243–248, 253, 256, 285, 286, 312, 376,	231, 243, 249
380	collision avoidance, 273, 277, 300
Bode plot, 107, 112, 126, 152, 241, 289,	commensurate-order system, 17, 18, 22,
315, 373	26–28, 35–37, 43, 54, 56, 74, 224–226,
magnitude Bode plot, see magnitude	237, 239, 260
Bode plot	compensating term, 283
Bode's ideal loop transfer function, 31 , 75,	complementary sensitivity function, 90,
151, 153, 273, 277, 282, 287, 288, 366,	123
367, 371, 372, 374, 381	complete difference equation, 64
bounded-input bounded-output, 21, 37, see BIBO	complex plane, 19, 24, 26, 37, 77–79, 90,
buck converter, 76, 365, 365 , 366, 367,	135–137, 146, 289
371, 376, 378, 384, 387, 388	condition number, 261, 264, 266
371, 370, 370, 364, 367, 366	constant overshoot, 151, 273, 287, 291, 300
cononical state anger representation 27	constant phase element, 4, 262
canonical state-space representation, 37 controllable form, see controllable	constant phase margin, 75, 151, 286–288
canonical form	constrained optimization, 252
Jordan form, see Jordan canonical form	continued fraction, 192–193, 195, 197, 383
Jordan form, see Jordan Canonical form	Communica machon, 132 133, 130, 131, 303

control law, 128, 134, 165, 166, 168, 170, double integrator, 165-170, 273, 282, 284, 279, 283, 327, 361, 375-378 295, 300 Control System Toolbox, 213, 231, 241, 256 elastic limit, 295, 297 controllability, 35, 54-56, 275 elastic manipulator, 275 controllability criterion, 56, 71 electrical dynamics, 280 controllability Gramian, 69 electrochemical process, 260, 261, 265, 271 controllability matrix, 56 electromechanical actuator, 280 controllable canonical form, 38, 50, 52, 53, end effector, 273, 274 56, 58 equivalent control, 168, 170, 172, 377–380 convolution, 6, 10, 43, 259 equivalent electrical circuit, 4, 261 Coulomb friction, 277, 280, 281, 283, 297, erfc function, 51 298, 300 Euler-Bernouilli beam, 266 coupling torque, 280, 281, 283-285, 292, evolutionary algorithm, 159, 162, 163 295, 300 expanded state, 61 CPE, see constant phase element exponential function, 13, 44, 214, 215 critically damped, 283, 286 CRONE controller, 31, 76, 134, 151, F-MIGO method, 88-92, 95-97, 100-104 151-157, 159, 162 fast Fourier transform, 16 FDE, see fractional-order differential d-stability, 278 equation damped oscillation, 14, 20, 27 feasible region, 124 damping ratio, 32, 33, 122, 154-156, 314 feasible solution, 97, 124, 388 data acquisition, 115, 126, 146, 353, 355, feedforward, 177, 276, 278, 352, 386 384 feedforward gain, 180 FFT, see fast Fourier transform DC motor, 108, 115, 118, 280, 305, 307, 365 Final-Value Theorem, 123, 288, 313, 320 DC/DC converter, 365-369, 371, 387 finite differences formula, 297 dead beat, 365 finite impulse response, 198 delay dominant, 97-99, 101, 104 finite-dimensional system, 191, 198, 205, derivative action, 4, 77, 79, 80 212, 296 describing function, 183 finite-time ITAE criterion, 213, 249, 250, design specification, 121, 122, 124, 126, 253, 256 129, 142, 158, 161, 162, 166, 181, 289, FIR, see finite impulse response 314, 317, 356, 361, 374, 375, 381 first-order backward difference, 61 DF, see describing function first-order forward difference, 60 diagonal matrix, 50, 369 first-order plus dead-time, 87, 95, 107 diagonalizable, 369 flatness of the phase curve, 133, 135, 140, diffusion, 4, 259, 261, 265, 271 142, 145, 147 Dirac's delta function, 43 flexible manipulator, 77, 273-276, 289, 292, direct discretization, 196 direct transmission matrix, 35 multi-link flexible manipulator, see discrete implementation, 196-201, 291, 300 multi-link flexible arms discrete-time, 59-74 single-link flexible manipulator, see discretization, 60, 61, 196, 197, 199, 296, single-link flexible arm 326 two-link flexible manipulator, see direct discretization, see direct two-link flexible arms discretization flexible robot, 266, 274–276, 292 indirect discretization, see indirect flexible structure, 260, 271, 275, 278 discretization flexible transmission, 76 Tustin method, see Tustin method FOLLC, see fractional-order lead-lag distributed mass, 292 compensator distributed-parameter systems, 271 FOPDT, see first-order plus dead-time

force control, 274

dominant time constant, 311, 323

FOTF object, 196, 213, 232, 232-243, 256 gain crossover frequency, 31, 75, 76, 107. 109, 111, 122, 135, 138, 141, 145, 152, Fourier transform 161, 199, 289 inverse Fourier transform, see inverse gain margin, 32, 154, 301, 303, 314-316, Fourier transform 324, 328, 329 fractional calculus, 3, 4, 7, 12, 17, 75, 76, generalized hyperbolic function, 259 214 - 231generalized Mittag-Leffler function, 215, Caputo's, see Caputo's definition 216 Cauchy's formula, see Cauchy's formula global optimization, 124 Grünwald-Letnikov's, see Grünwald-Grünwald-Letnikov's definition, 7, 11, 12, Letnikov's definition 15, 16, 60, 61, 63, 71, 214, 217-221, Riemann-Louiville's, see Riemann-323 Louiville's definition gradient approach, 174 fractional horsepower dynamometer, 115 fractional sliding mode control, 365, \mathcal{H}_2 norm, 76, 205, 206, 212, 242 375-380, 388 \mathcal{H}_{∞} norm, 242 fractional sliding surface, 367, 378-380 high-frequency dynamics, 277, 334 fractional switching function, 170 high-frequency gain, 160 fractional-order, 391 high-frequency noise, 4, 80, 122 fractional-order transfer function, see homogeneous difference equation, 62 FOTF hydraulic actuator, 76 fractional-order control, 34, 75-84 CRONE, see CRONE IAE, 90, 249 FOLLC, see fractional-order lead-lag ideal cutoff characteristic, 75 compensator ideal sliding mode, 168 F_RSMC, see fractional-order sliding identity matrix, 36 mode control IE, 90 PD^{μ} , see fractional-order PD IIR, see infinite impulse response $PI^{\lambda}D^{\mu}$, see fractional-order PID immersed plate, 56, 58 impedance measurement, 261 PI^{λ} , see fractional-order PI FPI-PI, see FPI-PI controller impulse response, 13-15, 27, 224, 226, 227, QFT, see QFT impulse response invariant, 192, 198, 200 reset control, see reset control indirect discretization, 196, 296, 358 fractional-order delay system, 245 infinite impulse response, 197 fractional-order differential equation, infinite-dimensional system, 61, 66, 269, 12-16, 213, 214, 221-231, 239, 240, 245, 256, 264 initial condition, 4, 13-15, 18, 36, 69, 70, fractional-order Kalman filter, 74 82, 95, 124, 125, 133, 141, 166, 223, fractional-order lag compensator, 133, 138 225, 227, 277, 287 fractional-order lead compensator, 133, 142 input matrix, 35 fractional-order lead-lag compensator, 130, integer-order, 13, 17, 18, 22, 30, 44, 45, 56, 141, 147 60, 66, 74, 87, 134, 198, 205, 212, 214, fractional-order PD, 107-119 224, 296, 391 fractional-order PI, 87-106, 301, 303, 304, integral action, 4, 77, 78, 80 312 - 352integral criterion fractional-order PID, 76, 81-83, 236, 255, finite-time ITAE, see finite-time ITAE 287, 303, 365, 378, 388 IAE, see IAE fractional-order transfer function, see IE, see IE FOTF ISE, see ISE frequency domain identification, 201, 260, ITAE, see ITAE 296, 361 integral of absolute error, see IAE F_RSMC, see fractional-order sliding mode integral of squared errors, see ISE integral of the error, $see~{\rm IE}$ control

integral of time weighted absolute error, see ITAE integrated absolute error, see IAE interlacing property, 292–295 interval uncertainty, 161 inverse Fourier transform, 16 inverse Laplace transform, 6, 43, 45, 53, 224, 227, $\mathbf{391}$, 391-394 irrational-order, 18, 21, 28, 152, 259, 391 ISE, 76, 88, 90, 249, 250 iso-damping property, 113, $\mathbf{123}$, 147 ITAE, 113, $\mathbf{116}$ –118, 213, 249, 250, 255 iterated integral, 6 iterative algorithm, 261

Jordan canonical form, 369 Jordan matrix, 46 Jury, 23

lag dominant, 99, 101, 102

Kalman filter, 74

Laplace transform, 4, 15, 37, 42, 43, 53, 224, 225, 231, 260, 281, **391**, 391–394 inverse Laplace transform, see inverse Laplace transform LC filter, 368, 381 lead-lag compensator, 81, 133, 134 fractional-order lead-lag compensator, see fractional-order lead-lag compensator linear time invariant, 12, 17, 18, 22, 34, 35 linearized model, 303, 307, 368, 369, 371, 374, 375 link deflection, 282 liquid level system, 125, 126, 160 load disturbance, 89, 90, 101, 102, 122 load disturbance rejection, 88, 89 local optimization, 124 loop shaping, 88, 89, 159, **160**, 161 low-pass filter, 154, 172, 244, 299, 300, 365 LTI, see linear time invariant Lyapunov stability, 277

magnitude Bode plot, 192, 312, 329
MARC, see model reference adaptive
control
marginally stable, 294, 316
mass per unit length, 292
mass transport, 4, 262
MATLAB, 50, 51, 60, 198–210, 213–256
Control System Toolbox, see Control
System Toolbox

Optimization Toolbox, see Optimization Toolbox Real-Time Workshop, see Real-Time Workshop Simulink, see Simulink maximum sensitivity, 88 mechatronic platform, 358 memory, 4, 8, 18, 44, 61, 259, 323 memory length, 16 MIGO method, 88, 93, 100, 105 minimum-phase, 151, 197, 275, 371-373 MIT rule, 175–178 Mittag-Leffler function, 13, 14, 44, 46, 48, 51, 52, 213-217, 229, 256, 260 Mittag-Leffler function evaluation, 214 - 217Mittag-Leffler function in more parameters, 215 Mittag-Leffler function in one parameter, Mittag-Leffler function in two parameters, 15, 214, 215, 217, 259, 288, 289 Mittag-Leffler matrix function, 44, 50, 51 modal canonical form, 39-42, 50-52 model reference, 165 model reference adaptive control, 173–181 modified Oustaloup filter, 192, 195-196, 245, 256 motion control application, 107 motor inertia, 280, 284 motor-gear set, 281 $M_{\rm s}$ constrained integral gain optimization, see MIGO multi-link flexible arms, 278 multinomial coefficient, 230 multiple-input multiple-output, see MIMO multiplicity, 39, 227

n-fold integral, 5, 9, 10
N-integer toolbox, **192**, 193, 213
natural frequency, 32, 281
neural network, 277
Newton's second law, 280
Newton–Raphson technique, 94–96
Newtonian fluid, 40
Nichols chart, 155–157, 159, 241, 317, 329
nominal plant, 160, 278, 308, 311, 313, 317, 318, 321, 324, 329
nominal tip mass, 276
nominal value, 161, 278, 291, 310, 314, 317, 318
non-collocated system, 275
non-convex optimization, 158, 159

non-minimum-phase, 151, 370-372 peak sensitivity, 88, 90 nonlinear constraint, 125, 129 phase crossover frequency, 324, 329 nonlinear control, 115 phase margin, 32, 75, 76, 107, 109, 111, nonlinear equation, 94 122, 133, 135–137, 142, 145, 161, 289, nonlinear system, 243 313, 324, 372 nonlinear time-varying, 367 PI, see proportional integral controller PID, see proportional integral derivative norm, 66, 238, 242-243 $PI^{\lambda}D^{\mu}$, see fractional-order PID \mathcal{H}_2 norm, see \mathcal{H}_2 norm \mathcal{H}_{∞} norm, see \mathcal{H}_{∞} norm PI^{λ} , see fractional-order PI FPI-PI controller, 320-322, 327, 330, 333 null matrix, 62 numerical solution, 15-16, 34, 214-223, 230 pole, 21, 25, 32, 39, 126, 135, 155, 193, 225, Nyquist path, 23, 24 239, 259, 292, 356, 391 Nyquist plot, 31, 75, 90, 143, 241, 294 pole placement, 278 Nyquist stability criterion, 294, 328 pole-zero excess, 160 position control, 273, 284 position servo, 108, 355 object-oriented programming, 213, 234 positive unity-gain feedback, 282, 284 objective function, 76, 205, 252, 254, 256 observability, 35, 57-58, 71, 74 power electronic converters, 366 prewarping, 199 observability criterion, 58 primitive, 5, 10 observability Gramian, 71 observability matrix, 58 principal Riemann sheet, 22 proportional action, 4, 77, 78, 80 observable canonical form, 39 pulse width modulation, see PWM observer, 74 observer-based controller, 74 pure integrator with time delay, 104 pure time delay system, 104 operating point, 310 PWM, 365, 368, 376, 381, 384, 386 operational calculus, 7 optimization, 88, 89, 91-95, 124, 126, 161, 206, 214, 242, 251-256, 300 OFT, 158-163, 203, 300 quantitative feedback theory, see QFT constrained optimization, see constrained optimization quarter amplitude damping design method, optimization constraint, 92, 124, 328 unconstrained optimization, see unconstrained optimization ramp response, 114, 117 Optimization Toolbox, 252 Randle's equivalent circuit, 261, 262, 263 oscillation equation, 12 rational commensurate-order system, 37 Oustaloup recursive approximation rational-order, 17, 41 modified Oustaloup recursive reachability, 68 approximation, see modified reachability condition, 71, 166, 168, 172, Oustaloup filter 378 - 380Real-Time Workshop, 115 Oustaloup's recursive approximation, 97, 112, 126, 152, 154, 186, 192–196, 208, reduction gear, 276, 279, 284 212, 244 reference angle, 283 output disturbance rejection, 123 relative dead time, 88, 96, 97, 100, 101, output equation, 36, 39, 50, 57, 59, 72 104 - 106output matrix, 35 relative stability, 4, 77, 181 overload function, 213, 234, 235, 239, 241, relaxation equation, 12, 31, 271 242, 256 relay test, 142-147, 359, 360 relevant root, 21 Parseval's Theorem, 260 reset control, 181-188 partial fraction expansion, 39, 45, 225, Riemann principal sheet, 23, 25, 27 227 - 229Riemann surface, 19, 20

particular solution, 13, 14

 PD^{μ} , see fractional-order PD

passivity, 275

Riemann-Liouville's definition, 6, 10, 11,

172, 185, 217

rigid robot, 77

rise time, 77, 187, 286, 289 robotic impedance control, 274 robust stability, 151, 160, 163, 314, 316, 324 robustness criterion, 133, 135, 140, 142, 145 Routh, 23, 178 sampler, 59 sampling period, 59-61, 126, 141, 157, 198, 199, 203, 323, 325, 327, 355, 356, 361, saturation, 300, 307, 361 Taylor's matrix series, 46 secondary sheet, 20 template, 153, 159 semi-group property, 45, 64 test batch, 88, 96, 97 sensitivity constraint, 91, 92 thermal system, 77 sensitivity derivative, 174 sensitivity function, 90, 122, 123, 126, 278 servo-amplifier system, 280 set-point, 89, 90, 307, 309, 325 settling time, 77, 79, 295, 296, 314, 319-321, 324, 325, 327, 370 377 short memory principle, 16, 323 signal processing, 198 Simulink, 116, 185, 212, 213, 243-248, 252, 253, 255, 359 single-input single-output, 37, 43, 54, see SISO single-link flexible arm, 275, 278, 279, 282, boundary 292, 295, 297, 300 uncertainty, 155, 159 sliding mode, 277, 375, 377 sliding mode control, 165, 188, 365, 375, 378, 381, 383, 384, 386 sliding surface, 165, 166, 168, 277, 366, 376-380, 382 SMC, see sliding mode control Vandermonde matrix, 47–49 Smith predictor, 301, 303, 304, 371, 372 spillover, 275, 277-279, 291-293, 296 stability, 19-26, 36-37, 66-68, 176-179, 199, 213, 237–239, 277, 285, 312, 314 viscous friction, 280 stability boundary, 160, 162 stability condition, 21, 22, 37, 42, 66, system 178, 294 stability margin, 66, 153, 278 stability radius, 68 state feedback, 74 state pseudo-transition matrix, 45, 46, 47, Young's modulus, 292 49, 63, 64, 67 state transition matrix, 43, 45 state-space state-space canonical realization, see canonical state-space representation state-space difference equation, 62 steady-state error, 123, 154, 181, 255, 277, 313, 320, 327, 357, 377

steady-state error constant, 133, 140 step function, 52, 219, 220, 223, 246 step response, 27, 32, 89, 100, 101, 106, 112-113, 116, 157, 186, 209, 224, 230, 239, 253, 260, 273, 289, 357, 362 step response invariant, 200 strain gauge, 282, 283, 285 structural root, 21, 21, 25, 26, 32 switching function, 165, 167, 168, 375 Sylvester's interpolation formula, 47 symbolic method, 7, 220

tip payload, 273, 276-278, 292, 295 trajectory tracking, 276, 277 transcendental function, 269 transfer function matrix, 36 transient response, 75, 77, 179, 277, 310, tuning method, 87, 88, 106, 107, 117, 121, 122, 125, 133, 138, 355 Tustin method, 192, 198, 199 two-link flexible arm, 277

UHFB, see universal high-frequency uncertainty bound, 278 unconstrained optimization, 251 universal high-frequency boundary, 160

variable structure control system, 165 velocity servo, 353, 355, 357 viscoelastic damped structure, 76 VSCS, see variable structure control

w-transform, 370, 371, 381 Warburg impedance, 4, 262, 265, 271

zero, 81, 126, 193, 259, 292, 356 zero-crossing detector, 182 zero-order hold, 59, 319, 355 Ziegler-Nichols tuning rule, 88, 89, 101, ZOH, see zero-order hold

Other titles published in this series (continued):

Soft Sensors for Monitoring and Control of Industrial Processes
Luigi Fortuna, Salvatore Graziani,
Alessandro Rizzo and Maria G. Xibilia

Adaptive Voltage Control in Power Systems
Giuseppe Fusco and Mario Russo

Advanced Control of Industrial Processes Piotr Tatjewski

Process Control Performance Assessment Andrzej W. Ordys, Damien Uduehi and Michael A. Johnson (Eds.)

Modelling and Analysis of Hybrid Supervisory Systems Emilia Villani, Paulo E. Miyagi and Robert Valette

Process Control
Jie Bao and Peter L. Lee

Distributed Embedded Control Systems Matjaž Colnarič, Domen Verber and Wolfgang A. Halang

Precision Motion Control (2nd Ed.) Tan Kok Kiong, Lee Tong Heng and Huang Sunan

Optimal Control of Wind Energy Systems Iulian Munteanu, Antoneta Iuliana Bratcu, Nicolaos-Antonio Cutululis and Emil Ceangă

Identification of Continuous-time Models from Sampled Data Hugues Garnier and Liuping Wang (Eds.)

Model-based Process Supervision Arun K. Samantaray and Belkacem Bouamama

Diagnosis of Process Nonlinearities and Valve Stiction M.A.A. Shoukat Choudhury, Sirish L. Shah, and Nina F. Thornhill

Magnetic Control of Tokamak Plasmas Marco Ariola and Alfredo Pironti Real-time Iterative Learning Control Jian-Xin Xu, Sanjib K. Panda and Tong H. Lee

Deadlock Resolution in Automated Manufacturing Systems ZhiWu Li and MengChu Zhou

Model Predictive Control Design and Implementation Using MATLAB® Liuping Wang

Fault-tolerant Flight Control and Guidance Systems Guillaume Ducard

Predictive Functional Control
Jacques Richalet and Donal O'Donovan

Fault-tolerant Control Systems Hassan Noura, Didier Theilliol, Jean-Christophe Ponsart and Abbas Chamseddine

Control of Ships and Underwater Vehicles Khac Duc Do and Jie Pan

Detection and Diagnosis of Stiction in Control Loops Mohieddine Jelali and Biao Huang

Stochastic Distribution Control System Design Lei Guo and Hong Wang

Dry Clutch Control for Automotive Applications Pietro J. Dolcini, Carlos Canudas-de-Wit, and Hubert Béchart

Active Control of Flexible Structures Alberto Cavallo, Giuseppe De Maria, Ciro Natale and Salvatore Pirozzi

Nonlinear and Adaptive Control Design for Induction Motors Riccardo Marino, Patrizio Tomei and Cristiano M. Verrelli

Active Braking Control Design for Road Vehicles Sergio M. Savaresi and Mara Tanelli