Adaptive backstepping control of uncertain systems - nonsmooth nonlinearities, interactions, or time-variations

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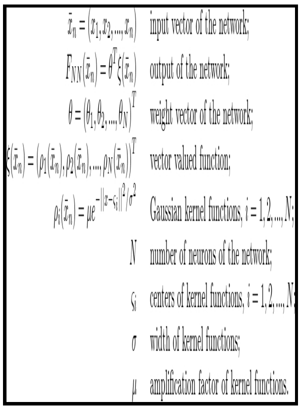

$\bar{x}_n = (x_1, x_2, ..., x_n)$	input vector of the network;
$F_{NN}(\bar{x}_n) = \theta^T \xi(\bar{x}_n)$	output of the network;
$\theta = (\theta_1, \theta_2, ..., \theta_N)^T$	weight vector of the network;
$\xi(\bar{x}_n) = (\rho_1(\bar{x}_n), \rho_2(\bar{x}_n), ..., \rho_N(\bar{x}_n))^T$	vector valued function;
$\rho_i(\bar{x}_n) = \mu e^{-\|x-\varsigma_i\|^2/\sigma^2}$	Gaussian kernel functions, $i = 1, 2, ..., N$;
N	number of neurons of the network;
ς_i	centers of kernel functions, $i = 1, 2, ..., N$;
σ	width of kernel functions;
μ	amplification factor of kernel functions.

Description: -
-
Interest inventories
Shakespeare, William, -- 1564-1616 -- Criticism and interpretation
Nonlinear control theory
Feedback control systems
Adaptive control systemsAdaptive backstepping control of uncertain systems - nonsmooth nonlinearities, interactions, or time-variations
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Verhandelingen van het Koninklijk Instituut voor Taal-, Land- en Volkenkunde -- 230
Lecture notes in control and information sciences -- 372Adaptive backstepping control of uncertain systems - nonsmooth nonlinearities, interactions, or time-variations
Notes: Includes bibliographical references (p. [233]-241).
This edition was published in 2008

Tags: #Adaptive #Backstepping #Control #of #Uncertain #Systems #with #Actuator #Failures, #Subsystem #Interactions, #and #Nonsmooth #Nonlinearities #by #Changyun #Wen, #Wei #Wang #and #Jing #Zhou #(2017, #Hardcover) #for #sale #online

Adaptive Backstepping Control of Uncertain Systems with Actuator Failures, Subsystem Interactions, and Nonsmooth Nonlinearities by Changyun Wen, Wei Wang and Jing Zhou (2017, Hardcover) for sale online

Journal of Aerospace Technology and Management, 3 1 : 53-8.

Backstepping Sliding Mode Controller Coupled to Adaptive Sliding Mode Observer for Interconnected Fractional Nonlinear System

Two examples and their simulations show the effectiveness of the proposed algorithms.

Uncertainty and Disturbance Estimator

Attitude stabilization control of a quadrotor uav by using backstepping approach. Backstepping can be used to relax the matching condition, which blocked the traditional Lyapunov-based design.

Environmental Chemistry Letters citation style [Update 2020]

Each rotor produces both thrust and antitorque. Unfortunately, in all of the existing research results, the uncertain external disturbances are not taken into account.

Backstepping Sliding Mode Controller Coupled to Adaptive Sliding Mode Observer for Interconnected Fractional Nonlinear System

The PSO algorithm begins with selection of random candidate solution known as particle.

Adaptive Critic Control with Robust Stabilization for Uncertain Nonlinear Systems

Proceeding of the 45th IEEE conference on decision and control san diego ,CA , USA.

Adaptive Backstepping Control of Uncertain Systems

Bai ; Jue Wu, Southwest University of Science and Technology, Mianyang 621010, China. This combination guaranties the tracking of trajectory, estimation of both the unmeasured state and the unknown parameters. In this problem, the final aim is determination of the best settling time under constraints on control law.

Active vibration adaptive fuzzy backstepping control of a 7

Secondly, an adaptive fuzzy backstepping method was designed for the dynamic compensator with a tracking filter for the control system of the 7-DOF dual-arm of the humanoid robot. As depicted in , the quadrotor includes four fixed-pitch-angle blades.

Related Books

- Quartetto lirico. - String quartet no. 3.
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