Robust control

Sliding mode

To achieve robust performance and/or stability in presence of bounded modeling error







General

 

 

Let 



Proof:











Introduce 











Exponentially stable

So:





图表, 折线图

描述已自动生成

滑膜对执行器的挑战很大

High gain and high frequency

High gain ： 用足够大的输入抵消不确定性

High frequency ：

Proof:





Case1:





Introduce 











同滑膜

Case2:





Introduce 













Globally uniformly ultimately bounded



Proof







 其中



Same as uaux2

