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book announcements review of advanced h control towards nonsmooth theory bookshelf abstract this book covers disturbance attenuation in nonsmooth dynamic systems developing an h3 approach in the nonsmooth setting similar to the standard nonlinear h3 approach the proposed nonsmooth design guarantees both the internal asymptotic stability of a nominal closedloop system and the

This compact monograph is focused on disturbance attenuation in nonsmooth dynamic systems, developing an H∞ approach in the nonsmooth setting. Similar to the standard nonlinear H∞ approach, the proposed nonsmooth design guarantees both the internal asymptotic stability of a nominal closed-loop system and the dissipativity inequality, which states that the size of an error signal is uniformly bounded with respect to the worst-case size of an external disturbance signal. This guarantee is achieved by constructing an energy or storage function that satisfies the dissipativity inequality and is then utilized as a Lyapunov function to ensure the internal stability requirements. Advanced H∞ Control is unique in the literature for its treatment of disturbance attenuation in nonsmooth systems. It synthesizes various tools, including Hamilton–Jacobi–Isaacs partial differential inequalities as well as Linear Matrix Inequalities. Along with the finite-dimensional treatment, the synthesis is extended to infinite-dimensional setting, involving time-delay and distributed parameter systems. To help illustrate this synthesis, the book focuses on electromechanical applications with nonsmooth phenomena caused by dry friction, backlash, and sampled-data measurements. Special attention is devoted to implementation issues. Requiring familiarity with nonlinear systems theory, this book will be accessible to g raduate students interested in systems analysis and design, and is a welcome addition to the literature for researchers and practitioners in these areas.

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Nonsmooth Lyapunov Analysis in Finite and Infinite Dimensions provides helpful tools for the treatment of a broad class of dynamical systems that are governed, not only by ordinary differential equations but also by partial and functional differential equations. Existing Lyapunov constructions are extended to discontinuous systems—those with variable structure and impact—by the involvement of nonsmooth Lyapunov functions. The general theoretical presentation is illustrated by control-related applications; the nonsmooth Lyapunov construction is particularly applied to the tuning of sliding-mode controllers in the presence of mismatched disturbances and to orbital stabilization of the bipedal gate. The nonsmooth construction is readily extendible to the control and identification of distributed-parameter and time-delay systems. The first part of the book outlines the relevant fundamentals of benchmark models and mathematical basics. The second concentrates on the construction of nonsmooth Lyapunov functions. Part III covers design and applications material. This book will benefit the academic research and graduate student interested in the mathematics of Lyapunov equations and variable-structure control, stability analysis and robust feedback design for discontinuous systems. It will also serve the practitioner working with applications of such systems. The reader should have some knowledge of dynamical systems theory, but no background in discontinuous systems is required—they are thoroughly introduced in both finite- and infinite-dimensional settings.

Mass production companies have become obliged to reduce their production costs and sell more products with lower profit margins in order to survive in competitive market conditions. The complexity and automation level of machinery are continuously growing. This development calls for some of the most critical issues that are reliability and dependability of automatic systems. In the future, machines will be monitored remotely, and computer-aided techniques will be employed to detect faults in the future, and also there will be unmanned factories where machines and systems communicate to each other, detect their own faults, and can remotely intercept their faults. The pioneer studies of such systems are fault diagnosis studies. Thus, we hope that this book will contribute to the literature in this regard.

This book discusses emerging topics in the area of nonsmooth dynamics research, such as numerical methods for nonsmooth systems, impact laws for multi-collisions, nonlinear vibrations and control of nonsmooth systems. It documents original work of researchers at the European Network for NonSmooth Dynamics (ENNSD), which provides a cooperation platform for researchers in the field and promotes research focused on nonsmooth dynamics and its applications. Since the establishment of the network in 2012, six ENNSD symposia have been organized at different European locations. The network brings together 40 specialists from 9 different countries in and outside Europe and a wealth of scientific knowledge has been gathered and developed by this group of experts in recent years. The book is of interest to both new and experienced researchers in the field of nonsmooth dynamics. Each chapter is written in such a way as to provide an introduction to the topic for researchers from other fields.

The field of mechatronics (which is the synergistic combination of precision mechanical engineering, electronic control and systems thinking in the design of products and manufacturing processes) is gaining much attention in industries and academics. It was detected that the topics of computer vision, control and robotics are imperative for the successful of mechatronics systems. This book includes several chapters which report successful study cases about computer vision, control and robotics. The readers will have the latest information related to mechatronics, that contains the details of implementation, and the description of the test scenarios.

A compendium of the authors' recently published results, this book discusses sliding mode control of uncertain nonlinear systems, with a particular emphasis on advanced and optimization based algorithms. The authors survey classical sliding mode control theory and introduce four new methods of advanced sliding mode control. They analyze classical theory and advanced algorithms, with numerical results complementing the theoretical treatment. Case studies examine applications of the algorithms to complex robotics and power grid problems. Advanced and Optimization Based Sliding Mode Control: Theory and Applications is the first book to systematize the theory of optimization based higher order sliding mode control and illustrate advanced algorithms and their applications to real problems. It presents systematic treatment of event-triggered and model based event-triggered sliding mode control schemes, including schemes in combination with model predictive control, and presents adaptive algorithms as well as algorithms capable of dealing with state and input constraints. Additionally, the book includes simulations and experimental results obtained by applying the presented control strategies to real complex systems. This book is suitable for students and researchers interested in control theory. It will also be attractive to practitioners interested in implementing the illustrated strategies. It is accessible to anyone with a basic knowledge of control engineering, process physics, and applied mathematics.

A clear and succinct presentation of the essentials of this subject, together with some of its applications and a generous helping of interesting exercises. Following an introductory chapter with a taste of what is to come, the next three chapters constitute a course in nonsmooth analysis and identify a coherent and comprehensive approach to the subject, leading to an efficient, natural, and powerful body of theory. The whole is rounded off with a self-contained introduction to the theory of control of ordinary differential equations. The authors have incorporated a number of new results which clarify the relationships between the different schools of thought in the subject, with the aim of making nonsmooth analysis accessible to a wider audience. End-of-chapter problems offer scope for deeper understanding.

This book focuses on the research topics investigated during the three-year research project funded by the Italian Ministero dell'Istruzione, dell'Universite e della Ricerca (MIUR: Ministry of Education, University and Research) under the FIRB project RBNE01CW3M. With the aim of introducing newer perspectives of the research on complexity, the final results of the project are presented after a general introduction to the subject. The book is intended to provide researchers, PhD students, and people involved in research projects in companies with the basic fundamentals of complex systems and the advanced project results recently obtained.

Now in its third edition, this standard reference is a comprehensive treatment of nonsmooth mechanical systems refocused to give more prominence to issues connected with control and modelling. It covers Lagrangian and Newton–Euler systems, detailing mathematical tools such as convex analysis and complementarity theory. The ways in which nonsmooth mechanics influence and are influenced by well-posedness analysis, numerical analysis and simulation, modelling and control are explained. Contact/impact laws, stability theory and trajectory-tracking control are given detailed exposition connected by a mathematical framework formed from complementarity systems and measure-differential inclusions. Links are established with electrical circuits with set-valued nonsmooth elements as well as with other nonsmooth dynamical systems like impulsive and piecewise linear systems. Nonsmooth Mechanics (third edition) retains the topical structure familiar from its predecessors but has been substantially rewritten, edited and updated to account for the significant body of results that have emerged in the twenty-first century—including developments in: the existence and uniqueness of solutions; impact models; extension of the Lagrange–Dirichlet theorem and trajectory tracking; and well-posedness of contact complementarity problems with and without friction. Many figures (both new and redrawn to improve the clarity of the presentation) and examples are used to illustrate the theoretical developments. Material introducing the mathematics of nonsmooth mechanics has been improved to reflect the broad range of applications interest that has developed since publication of the second edition. The detail of some mathematical essentials is provided in four appendices. With its improved bibliography of over 1,300 references and wide-ranging coverage, Nonsmooth Mechanics (third edition) is sure to be an invaluable resource for researchers and postgraduates studying the control of mechanical systems, robotics, granular matter and relevant fields of applied mathematics. "The book's two best features, in my view are its detailed survey of the literature... and its detailed presentation of many examples illustrating both the techniques and their limitations... For readers interested in the field, this book will serve as an excellent introductory survey." Andrew Lewis in Automatica "It is written with clarity, contains the latest research results in the area of impact problems for rigid bodies and is recommended for both applied mathematicians and engineers." Panagiotis D. Panagiotopoulos in Mathematical Reviews "The presentation is excellent in combining rigorous mathematics with a great number of examples... allowing the reader to understand the basic concepts." Hans Troger in Mathematical Abstracts "/i>