

Contents

Abbreviations	xix
1 Introduction	1
1.1 Impulsive Systems	1
1.2 Variable-structure Systems	4
1.3 Hybrid Systems	7
1.4 Sliding Modes in a Hilbert Space	9
Part I Mathematical Tools	
2 Mathematical Models	13
2.1 Nonlinear Differential Equations in Distributions	13
2.1.1 Preliminaries	13
2.1.2 Instantaneous Impulse Response in a Nonlinear Setting	14
2.1.3 Vibroimpact Solutions	21
2.2 Differential Equations with a Piece-wise Continuous Right-hand Side	23
2.2.1 Filippov Solutions	24
2.2.2 Equivalent Control Method	26
2.2.3 Sliding Modes in a Hilbert Space	28
2.3 Modeling of Electromechanical Nonlinear Phenomena	33
2.3.1 Friction Models	34
2.3.1.1 Static Models	34
2.3.1.2 Dynamic Models	35
2.3.2 The Multistable Backlash Model and Its Single-stability Approximation	36
2.3.3 Limit Cycles and Nonlinear Asymptotic Harmonic Generators	39
2.3.4 Vibroimpact Modeling	41

3	Stability Analysis	45
3.1	Basic Definitions	45
3.2	Stability and Nonsmooth Lyapunov Functions	47
3.3	Invariance Principle	48
3.3.1	Extension to a Class of Discontinuous Systems	49
3.3.2	Illustrative Applications to a Mechanical Oscillator with Coulomb Friction	50
3.3.2.1	Localization of the Equilibria Set	50
3.3.2.2	Asymptotic Stabilization	52
3.3.2.3	Velocity Observer Design	53
3.4	Extended Invariance Principle	54
3.5	Asymptotic Stability and Semiglobal Lyapunov Functions	57
3.6	\mathcal{L}_2 -Gain Analysis	60
3.6.1	Hamilton–Jacobi Inequality	60
3.6.2	Time-varying Strict Bounded Real Lemma	62
3.7	The Lyapunov Analysis of Discrete-continuous Dynamics	65
3.7.1	Global Asymptotic Stability	65
3.7.2	Illustrative Example: Impulsive Stabilization of a Mechanical Oscillator with Coulomb Friction	66
3.7.2.1	Problem Statement	67
3.7.2.2	Controller Design	68
3.7.2.3	Numerical Results	72
3.8	Linear Operator Inequalities in a Hilbert Space	72
3.8.1	Preliminaries	72
3.8.1.1	Historical Remarks	72
3.8.1.2	Background Material	74
3.8.2	Linear Time-delay Systems	75
3.8.3	Well-posedness Issues	77
3.8.4	The Lyapunov–Krasovskii Method	79
3.8.5	Linear Operator Inequalities in a Hilbert Space	81
3.8.6	Illustrative Example: Delay Heat Equation	82
4	Finite-time Stability of Uncertain Homogeneous and Quasihomogeneous Systems	87
4.1	Uncertain Systems and Equiuniform Stability	87
4.2	Homogeneity Degree and Homogeneity Dilation	89
4.3	Finite-time Stability of Locally Homogeneous Systems	91
4.4	Quasihomogeneity Principle	93
4.5	Finite-time Stability of a First-order Quasihomogeneous System	94
4.6	Finite-time Stability of a Second-order Quasihomogeneous System	95

Part II Synthesis

5 Quasihomogeneous Design 105

5.1 Quasihomogeneous Finite-time Stabilization of a Simple Oscillator 105

5.2 Quasihomogeneous Stabilization of Nonlinear Systems of Relative Degree $(2, \dots, 2)$ 106

5.3 Local Quasihomogeneous Stabilization of Underactuated Mechanical Systems 109

6 Unit Feedback Design 113

6.1 Unit Control and Disturbance Rejection 114

6.2 Decomposition of Sliding-mode-based Synthesis Procedure 116

6.3 Global Asymptotic Stabilization of Uncertain Linear Systems 117

6.3.1 State Feedback Design 118

6.3.2 Output Feedback Design 124

6.3.3 Practical Stabilization via Smoothed Unit Feedback 129

6.4 Unit Feedback Control of Minimum Phase Nonlinear Systems 131

7 Disturbance Attenuation via Nonsmooth \mathcal{H}_∞ -design 133

7.1 Nonsmooth \mathcal{H}_∞ -control of Time-varying Systems 134

7.1.1 Problem Statement 134

7.1.2 Global State-space Solution 135

7.1.3 Local State-space Solution 139

7.1.4 Autonomous Case 143

7.2 Local \mathcal{H}_∞ -control Synthesis via Sampled-Data Measurements 145

7.2.1 Main Result 145

7.2.2 Conversion into the \mathcal{H}_∞ -control Synthesis via Continuous Measurements 147

7.2.3 Proof of the Main Result 150

7.3 Unified SMF and CMF \mathcal{H}_∞ -control Synthesis 152

7.3.1 Distribution Formalism 152

7.3.2 The \mathcal{H}_∞ -design Procedure 154

7.3.3 Illustrative Example: The \mathcal{H}_∞ -stabilization of an Inverted Pendulum via Nonlinear Sampled-Data Measurements 154

Part III Unit Feedback Control of Infinite-dimensional Systems

8 Global Asymptotic Stabilization of Uncertain Linear Systems 161

8.1 Preliminaries 162

8.2 State Feedback Design 165

8.3 Output Feedback Design 170

8.4 Applications to the Linearized Kuramoto–Sivashinsky Equation . . . 175

8.4.1 Numerical Results in the Disturbance-free Case 178

8.4.2 Numerical Results Under Non-vanishing External Disturbances 182

9	Asymptotic Stabilization of Minimum-phase Semilinear Systems	193
9.1	Stabilization in a Hilbert Space	193
9.2	Application to Chemical Tubular Reactor	199
9.2.1	Problem Statement	201
9.2.2	Global Stabilization via State Feedback	202
9.2.3	Concentration Observer Design	205
9.2.4	Regional Stabilization via Temperature Feedback	209
9.2.5	Simulation Results	210
10	Global Asymptotic Stabilization of Uncertain Time-delay Systems . . .	215
10.1	Problem Statement	215
10.2	Background Material on Discontinuous Time-delay Systems	217
10.3	Delay-/Disturbance-dependent Stability Criterion	218
10.4	Unit State Feedback Controller	221
10.5	Numerical Example	224
 Part IV Electromechanical Applications		
11	Local Nonsmooth \mathcal{H}_∞-synthesis Under Friction/Backlash Phenomena	229
11.1	Position Feedback Regulation of a Multi-link Robot Manipulator with Frictional Joints	229
11.1.1	Problem Statement	230
11.1.2	Control Synthesis	231
11.1.3	Experimental Study	233
11.1.3.1	Experimental Setup	233
11.1.3.2	Dynamical Model	233
11.1.3.3	Experimental Results	236
11.2	Output Feedback Regulation of a Servomechanism with Backlash . .	240
11.2.1	Dynamic Model	240
11.2.2	Problem Statement	241
11.2.3	Control Synthesis	243
11.2.4	Experimental Study	244
11.2.4.1	Experimental Setup	244
11.2.4.2	Experimental Results	246
12	Quasihomogeneous Stabilization of Fully Actuated Systems with Dry Friction	249
12.1	Orbital Stabilization of an Inverted Pendulum	249
12.1.1	Tracking of a Modified Van der Pol Oscillator	250
12.1.2	Experimental Study	253
12.2	Global Position Regulation of a Multi-link Robot Manipulator	254
12.2.1	Position Control Synthesis	255
12.2.2	Experimental Study	260

13 Hybrid Control of Underactuated Manipulators with Frictional Joints 265

- 13.1 Stabilization of 2-DOF Systems Using Coulomb Friction Hierarchy 266
 - 13.1.1 Problem Statement 266
 - 13.1.2 Quasihomogeneity-based Control Synthesis 268
 - 13.1.3 Application to a Horizontal Double Pendulum 272
 - 13.1.3.1 State Equations 272
 - 13.1.3.2 Experimental Results 273
- 13.2 Swing-up Control and Stabilization of Pendubot via Orbital Transfer Strategy 275
 - 13.2.1 Orbital Stabilization of Pendubot 275
 - 13.2.1.1 Control Strategy 277
 - 13.2.1.2 Control Synthesis 278
 - 13.2.2 Experimental Study 281
 - 13.2.2.1 Pendubot Prototype 281
 - 13.2.2.2 Swinging Controller Design 281
 - 13.2.2.3 Locally Stabilizing Controller Design 282
 - 13.2.2.4 Hybrid Controller Design 284
 - 13.2.2.5 Experimental Verification 284
- 13.3 Quasihomogeneous Swing-up Control and Stabilization of the Cart-pendulum System 288
 - 13.3.1 State Equations 289
 - 13.3.2 Local Stabilization 290
 - 13.3.2.1 Transformation to a Regular Form 291
 - 13.3.2.2 Locally Stabilizing Synthesis 292
 - 13.3.2.3 Numerical and Experimental Verification 294
 - 13.3.3 Swing-up Control 297
 - 13.3.3.1 Partial Linearization 297
 - 13.3.3.2 Control Strategy and Synthesis 298
 - 13.3.4 Experimental Study 301
 - 13.3.4.1 Swinging Controller Design 302
 - 13.3.4.2 Locally Stabilizing Controller Design 303
 - 13.3.4.3 Hybrid Controller Design 304
 - 13.3.4.4 Numerical Verification 304
 - 13.3.4.5 Experimental Verification 306

References 309

Index 319