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For a first course on nonlinear control that can be taught in one semester ζ This book emerges from the award-winning book, *Nonlinear Systems*, but has a distinctly different mission and ζ organization. While *Nonlinear Systems* was intended as a reference and a text on nonlinear system analysis and its application to control, this streamlined book is intended as a text for a first course on nonlinear control. In *Nonlinear Control*, author Hassan K. Khalil employs a writing style that is intended to make the book accessible to a wider audience without compromising the rigor of the presentation.

ζ Teaching and Learning Experience This program will provide a better teaching and learning experience—for you and your students. It will help: Provide an Accessible Approach to Nonlinear Control: This streamlined book is

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intended as a text for a first course on nonlinear control that can be taught in one semester. Support Learning: Over 250 end-of-chapter exercises give students plenty of opportunities to put theory into action.

This text emphasizes classical methods and presents essential analytical tools and strategies for the construction and development of improved design methods in nonlinear control. It offers engineering procedures for the frequency domain, as well as solved examples for clear understanding of control applications in the industrial, electrical, process, manufacturing, and automotive industries. The authors discuss Properties of nonlinear systems, stability, linearization methods, operating modes and dynamic analysis methods,

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phase trajectories in dynamic analysis of nonlinear systems, and harmonic linearization in dynamic analysis of nonlinear control systems operating in stabilization mode.

There has been much excitement over the emergence of new mathematical techniques for the analysis and control of nonlinear systems. In addition, great technological advances have bolstered the impact of analytic advances and produced many new problems and applications which are nonlinear in an essential way. This book lays out in a concise mathematical framework the tools and methods of analysis which underlie this diversity of applications.

Designed to meet the needs of a wide audience without

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sacrificing mathematical depth and rigor, Adaptive Control Tutorial presents the design, analysis, and application of a wide variety of algorithms that can be used to manage dynamical systems with unknown parameters. Its tutorial-style presentation of the fundamental techniques and algorithms in adaptive control make it suitable as a textbook. Adaptive Control Tutorial is designed to serve the needs of three distinct groups of readers: engineers and students interested in learning how to design, simulate, and implement parameter estimators and adaptive control schemes without having to fully understand the analytical and technical proofs; graduate students who, in addition to attaining the aforementioned objectives, also want to understand the analysis of simple schemes and get an idea of the steps involved in more

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complex proofs; and advanced students and researchers who want to study and understand the details of long and technical proofs with an eye toward pursuing research in adaptive control or related topics. The authors achieve these multiple objectives by enriching the book with examples demonstrating the design procedures and basic analysis steps and by detailing their proofs in both an appendix and electronically available supplementary material; online examples are also available. A solution manual for instructors can be obtained by contacting SIAM or the authors. Preface; Acknowledgements; List of Acronyms; Chapter 1: Introduction; Chapter 2: Parametric Models; Chapter 3: Parameter Identification: Continuous Time; Chapter 4: Parameter Identification: Discrete Time; Chapter 5:

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Continuous-Time Model Reference Adaptive Control; Chapter 6: Continuous-Time Adaptive Pole Placement Control; Chapter 7: Adaptive Control for Discrete-Time Systems; Chapter 8: Adaptive Control of Nonlinear Systems; Appendix; Bibliography; Index

The objective of the EU Nonlinear Control Network Workshop was to bring together scientists who are already active in nonlinear control and young researchers working in this field. This book presents selectively invited contributions from the workshop, some describing state-of-the-art subjects that already have a status of maturity while others propose promising future directions in nonlinear control. Amongst others, following topics of nonlinear and adaptive control are

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included: adaptive and robust control, applications in physical systems, distributed parameter systems, disturbance attenuation, dynamic feedback, optimal control, sliding mode control, and tracking and motion planning.

Mathematics is playing an ever more important role in the physical and biological sciences, provoking a blurring of boundaries between scientific disciplines and a resurgence of interest in the modern as well as the classical techniques of applied mathematics. This renewal of interest, both in research and teaching, has led to the establishment of the series: Texts in Applied Mathematics (TAM). The development of new courses is a natural consequence of a high level of excitement on the research frontier as newer

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techniques, such as numerical and symbolic computer systems, dynamical systems, and chaos, mix with and reinforce the traditional methods of applied mathematics. Thus, the purpose of this textbook series is to meet the current and future needs of these advances and encourage the teaching of new courses. TAM will publish textbooks suitable for use in advanced undergraduate and beginning graduate courses, and will complement the Applied Mathematical Sciences (AMS) series, which will focus on advanced textbooks and research level monographs. Preface to the Second Edition This book covers those topics necessary for a clear understanding of the qualitative theory of ordinary differential equations and the concept of a dynamical system. It is written for advanced undergraduates

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and for beginning graduate students. It begins with a study of linear systems of ordinary differential equations, a topic already familiar to the student who has completed a first course in differential equations.

In this work, the authors present a global perspective on the methods available for analysis and design of non-linear control systems and detail specific applications. They provide a tutorial exposition of the major non-linear systems analysis techniques followed by a discussion of available non-linear design methods.

The book blends readability and accessibility common to undergraduate control systems texts with the mathematical

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rigor necessary to form a solid theoretical foundation. Appendices cover linear algebra and provide a Matlab overview and files. The reviewers pointed out that this is an ambitious project but one that will pay off because of the lack of good up-to-date textbooks in the area.

Planning algorithms are impacting technical disciplines and industries around the world, including robotics, computer-aided design, manufacturing, computer graphics, aerospace applications, drug design, and protein folding. This coherent and comprehensive book unifies material from several sources, including robotics, control theory, artificial intelligence, and algorithms. The treatment is centered on robot motion planning, but integrates material on planning in

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discrete spaces. A major part of the book is devoted to planning under uncertainty, including decision theory, Markov decision processes, and information spaces, which are the 'configuration spaces' of all sensor-based planning problems. The last part of the book delves into planning under differential constraints that arise when automating the motions of virtually any mechanical system. This text and reference is intended for students, engineers, and researchers in robotics, artificial intelligence, and control theory as well as computer graphics, algorithms, and computational biology.

Provides complete coverage of both the Lyapunov and Input-Output stability theories, in a readable, concise manner. *

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Supplies an introduction to the popular backstepping approach to nonlinear control design * Gives a thorough discussion of the concept of input-to-state stability * Includes a discussion of the fundamentals of feedback linearization and related results. * Details complete coverage of the fundamentals of dissipative system's theory and its application in the so-called L2gain control problem, for the first time in an introductory level textbook. * Contains a thorough discussion of nonlinear observers, a very important problem, not commonly encountered in textbooks at this level. * An Instructor's Manual presenting detailed solutions to all the problems in the book is available from the Wiley editorial department.

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