Table of Contents

Notations ix

Introduction xiii

Chapter 1. Multiple Model Representation 1

1.1. Introduction 1
1.2. Techniques for obtaining multiple models 2
1.2.1. Construction of multiple models by identification 3
1.2.2. Multiple model construction by linearization 8
1.2.3. Multiple model construction by mathematical transformation 14
1.2.4. Multiple model representation using the neural approach. 22
1.3. Analysis and synthesis tools 29
1.3.1. Lyapunov approach 29
1.3.2. Numeric tools: linear matrix inequalities 31
1.3.3. Multiple model control techniques 38

Chapter 2. Stability of Continuous Multiple Models 41

2.1. Introduction 41
2.2. Stability analysis 42
2.2.1. Exponential stability 48
2.3. Relaxed stability 49
2.4. Example 52
2.5. Robust stability 54
2.5.1. Norm-bounded uncertainties. 56
2.5.2. Structured parametric uncertainties 57

2.5.3. Analysis of nominal stability 60
2.5.4. Analysis of robust stability 62
2.6. Conclusion 63

Chapter 3. Multiple Model State Estimation 65

3.1. Introduction 65
3.2. Synthesis of multiple observers 67
3.2.1. Linearization 68
3.2.2. Pole placement 70
3.2.3. Application: asynchronous machine 72
3.2.4. Synthesis of multiple observers 75
3.3. Multiple observer for an uncertain multiple model. 77
3.4. Synthesis of unknown input observers. 82
3.4.1. Unknown inputs affecting system state 83
3.4.2. Unknown inputs affecting system state and output. . . . 87
3.4.3. Estimation of unknown inputs 88
3.5. Synthesis of unknown input observers: another approach . . 93
3.5.1. Principle 93
3.5.2. Multiple observers subject to unknown inputs and uncertainties 96
3.6. Conclusion 97

Chapter 4. Stabilization of Multiple Models 99

4.1. Introduction 99
4.2. Full state feedback control. 99
4.2.1. Linearization 101
4.2.2. Specific case 103
4.2.3. α-stability: decay rate 106
4.3. Observer-based controller 113
4.3.1. Unmeasurable decision variables. 115
4.4. Static output feedback control 119
4.4.1. Pole placement 122
4.5. Conclusion 126

Chapter 5. Robust Stabilization of Multiple Models 127

5.1. Introduction 127
5.2. State feedback control. 129
5.2.1. Norm-bounded uncertainties. 129
5.2.2. Interval uncertainties 131
5.3. Output feedback control 137
5.3.1. Norm-bounded uncertainties. 137

5.3.2. Interval uncertainties 147
5.4. Observer-based control 150
5.5. Conclusion 156

Conclusion 157

APPENDICES 159

Appendix 1: LMI Regions 161

A1.1. Definition of an LMI region 161
A1.2. Interesting LMI region examples 162
A1.2.1. Open left half-plane. 163
A1.2.2. α-stability 163
A1.2.3. Vertical band 163
A1.2.4. Horizontal band 164
A1.2.5. Disk of radius R, centered at (q,0) 164
A1.2.6. Conical sector. 165

Appendix 2: Properties of M-Matrices 167

Appendix 3: Stability and Comparison Systems 169

A3.1. Vector norms and overvaluing systems 169
A3.1.1. Definition of a vector norm 169
A3.1.2. Definition of a system overvalued from a continuous process. 170
A3.1.3. Application 172
A3.2. Vector norms and the principle of comparison. 173
A3.3. Application to stability analysis 174

Bibliography. 175

Index 185