



Discrete Sliding Mode Control For Robust Tracking Of Time

Mike Jess



Discrete Sliding Mode Control For Robust Tracking Of Time:

Sliding Mode Control Using Novel Sliding Surfaces B. Bandyopadhyay, Fulwani Deepak, Kyung-Soo Kim, 2009-09-23

After a survey paper by Utkin in the late 1970s sliding mode control methodologies emerged as an effective tool to tackle uncertainty and disturbances which are inevitable in most of the practical systems. Sliding mode control is a particular class of variable structure control which was introduced by Emel'yanov and his colleagues. The design paradigms of sliding mode control has now become a mature design technique for the design of robust controller of uncertain system. In sliding mode technique the state trajectory of the system is constrained on a chosen manifold or within some neighborhood thereof by an appropriate control action. This manifold is also called a switching surface or a sliding surface. During sliding mode system dynamics is governed by the chosen manifold which results in a well celebrated invariance property towards certain classes of disturbance and model mismatches. The purpose of this monograph is to give a different dimension to sliding surface design to achieve high performance of the system. Design of the switching surface is vital because the closed loop dynamics is governed by the parameters of the sliding surface. Therefore sliding surface should be designed to meet the closed loop specifications. Many systems demand high performance with robustness. To address this issue of achieving high performance with robustness we propose nonlinear surfaces for different classes of systems. The nonlinear surface is designed such that it changes the system's closed loop damping ratio from its initial low value to a final high value.

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Table of Contents Discrete Sliding Mode Control For Robust Tracking Of Time

1. Understanding the eBook Discrete Sliding Mode Control For Robust Tracking Of Time
 - The Rise of Digital Reading Discrete Sliding Mode Control For Robust Tracking Of Time
 - Advantages of eBooks Over Traditional Books
2. Identifying Discrete Sliding Mode Control For Robust Tracking Of Time
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in a Discrete Sliding Mode Control For Robust Tracking Of Time
 - User-Friendly Interface
4. Exploring eBook Recommendations from Discrete Sliding Mode Control For Robust Tracking Of Time
 - Personalized Recommendations
 - Discrete Sliding Mode Control For Robust Tracking Of Time User Reviews and Ratings
 - Discrete Sliding Mode Control For Robust Tracking Of Time and Bestseller Lists
5. Accessing Discrete Sliding Mode Control For Robust Tracking Of Time Free and Paid eBooks
 - Discrete Sliding Mode Control For Robust Tracking Of Time Public Domain eBooks
 - Discrete Sliding Mode Control For Robust Tracking Of Time eBook Subscription Services
 - Discrete Sliding Mode Control For Robust Tracking Of Time Budget-Friendly Options

6. Navigating Discrete Sliding Mode Control For Robust Tracking Of Time eBook Formats
 - ePub, PDF, MOBI, and More
 - Discrete Sliding Mode Control For Robust Tracking Of Time Compatibility with Devices
 - Discrete Sliding Mode Control For Robust Tracking Of Time Enhanced eBook Features
7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Discrete Sliding Mode Control For Robust Tracking Of Time
 - Highlighting and Note-Taking Discrete Sliding Mode Control For Robust Tracking Of Time
 - Interactive Elements Discrete Sliding Mode Control For Robust Tracking Of Time
8. Staying Engaged with Discrete Sliding Mode Control For Robust Tracking Of Time
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Discrete Sliding Mode Control For Robust Tracking Of Time
9. Balancing eBooks and Physical Books Discrete Sliding Mode Control For Robust Tracking Of Time
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Discrete Sliding Mode Control For Robust Tracking Of Time
10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
11. Cultivating a Reading Routine Discrete Sliding Mode Control For Robust Tracking Of Time
 - Setting Reading Goals Discrete Sliding Mode Control For Robust Tracking Of Time
 - Carving Out Dedicated Reading Time
12. Sourcing Reliable Information of Discrete Sliding Mode Control For Robust Tracking Of Time
 - Fact-Checking eBook Content of Discrete Sliding Mode Control For Robust Tracking Of Time
 - Distinguishing Credible Sources
13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements

- Interactive and Gamified eBooks

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