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Slotine, J.-J. E. (Jean-Jacques E.) Applied nonlinear control / Jean-Jacques E. Slotine, Weiping Li p. cm. Includes bibliographical references. ISBN 0-13-040890-5 1, Nonlinear control theory. I. Li,

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J. Slotine, W. Li. Published 1991. Engineering. Covers in a progressive fashion a number of analysis tools and design techniques directly applicable to nonlinear control problems in high performance systems (in aerospace, robotics and automotive areas). uta.edu. Save to Library.

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Textbook reference for lectures 1-13 is . Applied Nonlinear Control, Slotine and Li, Prentice-Hall 1991. Main references for lectures 14-20 are . R1 Lohmiller, W., and Slotine, J.J.E.,"On Contraction Analysis for Nonlinear Systems," Automatica, 34(6), 1998 R2 Slotine, J.J.E., "Modular Stability Tools for Distributed Computation and Control," Int. J. Adaptive Control and Signal Processing, 17(6 ...

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Books Slotine, J.J.E., and Li, W., Applied Nonlinear Control, Prentice-Hall, 1991. Asada, H., and Slotine, J.J.E., Robot Analysis and Control, John Wiley & Sons, New ...

Nonlinear Systems Laboratory Homepage

Slotine minimizes a lot of that dense math and, in my opinion, focuses on the important concepts of nonlinear control without getting bogged down. On the negative side, as others have pointed out, Slotine's book doesn't have the detailed mathematical treatment of other books on nonlinear control.

Applied Nonlinear Control: Slotine, Jean-Jacques, Li ...

Tracking control of non-linear systems using sliding surfaces, with application to robot manipulators JJ Slotine, SS Sastry International

journal of control 38 (2), 465-492 , 1983

This unique book presents an analytical uniform design methodology of continuous-time or discrete-time nonlinear control system design which guarantees desired transient performances in the presence of plant parameter variations and unknown external disturbances. All results are illustrated with numerical simulations, their practical importance is highlighted, and they may be used for real-time control system design in robotics, mechatronics, chemical reactors, electrical and electro-mechanical systems as well as aircraft control systems. The book is easy reading and is suitable for

teaching.

For a first course on nonlinear control that can be taught in one semester ¿ This book emerges from the award-winning book, Nonlinear Systems, but has a distinctly different mission and¿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. ¿ 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 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.

An introduction to aspects of the theory of dynamial systems based on extensions of Liapunov's direct method. The main ideas and structure for the theory are presented for difference equations and for the analogous theory for ordinary differential equations and retarded functional differential equations. The latest results on invariance properties for non-autonomous time-varying systems processes are presented for difference and differential equations.

Nonlinear Dynamical Systems and Control presents and develops

an extensive treatment of stability analysis and control design of nonlinear dynamical systems, with an emphasis on Lyapunov-based methods. Dynamical system theory lies at the heart of mathematical sciences and engineering. The application of dynamical systems has crossed interdisciplinary boundaries from chemistry to biochemistry to chemical kinetics, from medicine to biology to population genetics, from economics to sociology to psychology, and from physics to mechanics to engineering. The increasingly complex nature of engineering systems requiring feedback control to obtain a desired system behavior also gives rise to dynamical systems. Wassim Haddad and VijaySekhar Chellaboina provide an exhaustive treatment of nonlinear systems theory and control using the highest standards of exposition and rigor. This graduate-level textbook goes well beyond standard treatments by developing

Lyapunov stability theory, partial stability, boundedness, input-to-state stability, input-output stability, finite-time stability, semistability, stability of sets and periodic orbits, and stability theorems via vector Lyapunov functions. A complete and thorough treatment of dissipativity theory, absolute stability theory, stability of feedback systems, optimal control, disturbance rejection control, and robust control for nonlinear dynamical systems is also given. This book is an indispensable resource for applied mathematicians, dynamical systems theorists, control theorists, and engineers.

This practical yet rigorous book provides a development of nonlinear, Lyapunov-based tools and their use in the solution of

control-theoretic problems. Rich in motivating examples and new design techniques, the text balances theoretical foundations and real-world implementation.

This book presents recent advances in robot control theory on task space sensory feedback control of robot manipulators. By using sensory feedback information, the robot control systems are robust to various uncertainties in modelling and calibration errors of the sensors. Several sensory task space control methods that do not require exact knowledge of either kinematics or dynamics of robots, are presented. Some useful methods such as approximate Jacobian control, adaptive Jacobian control, region control and multiple task space regional feedback are included. These formulations and methods give robots a high degree of flexibility in dealing with

unforeseen changes and uncertainties in its kinematics and dynamics, which is similar to human reaching movements and tool manipulation. It also leads to the solution of several long-standing problems and open issues in robot control, such as force control with constraint uncertainty, control of multi-fingered robot hand with uncertain contact points, singularity issue of Jacobian matrix, global task-space control, which are also presented in this book. The target audience for this book includes scientists, engineers and practitioners involved in the field of robot control theory.

Fundamental and technological topics are blended uniquely and developed clearly in nine chapters with a gradually increasing level of complexity. A wide variety of relevant problems is raised throughout, and the proper tools to find engineering-oriented

solutions are introduced and explained, step by step. Fundamental coverage includes: Kinematics; Statics and dynamics of manipulators; Trajectory planning and motion control in free space. Technological aspects include: Actuators; Sensors; Hardware/software control architectures; Industrial robot-control algorithms. Furthermore, established research results involving description of end-effector orientation, closed kinematic chains, kinematic redundancy and singularities, dynamic parameter identification, robust and adaptive control and force/motion control are provided. To provide readers with a homogeneous background, three appendices are included on: Linear algebra; Rigid-body mechanics; Feedback control. To acquire practical skill, more than 50 examples and case studies are carefully worked out and interwoven through the text, with frequent resort to simulation. In

addition, more than 80 end-of-chapter exercises are proposed, and the book is accompanied by a solutions manual containing the MATLAB code for computer problems; this is available from the publisher free of charge to those adopting this work as a textbook for courses.

VECPAR is a series of international conferences dedicated to the promotion and advancement of all aspects of high-performance computing for computational science, as an industrial technique and academic discipline, extending the fr- tier of both the state of the art and the state of practice. The audience for and participants in VECPAR are seen as researchers in academic departments, g- ernment laboratories and industrial organizations. There is now a permanent website for the series, http://vecpar.fe.up.pt, where the

history of the conf- ences is described. ThesixtheditionofVECPAR wasthe?rsttimetheconferencewascelebrated outside Porto – at the Universitad Politecnica de Valencia (Spain), June 28–30, 2004. The whole conference programme consisted of 6 invited talks, 61 papers and26posters,outof130contributionsthatwereinitiallysubmitted.The major themes were divided into large-scale numerical and non-numerical simulations, parallel and grid computing, biosciences, numerical algorithms, data mining and visualization. This postconference book includes the best 48 papers and 5 invited talks presented during the three days of the conference. The book is organized into 6 chapters, with a prominent position reserved for the invited talks and the Best Student Paper. As a whole it appeals to a wide research community, from those involved in the engineering applications to those interested in the actual details of

the hardware or software implementations, in line with what, in these days, tends to be considered as computational science and engineering (CSE).