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Soft Computing: Theories and Applications
Iterative Learning Control
A Contribution to Adaptive
Sliding-Mode Control with Gaussian Radial-Basis-Function Networks
Proceedings, IEEE Control
Systems Society ... Symposium on Computer-Aided Control System Design (CACSD). Rajesh Kumar
Hyo-Sung Ahn Lei Ma

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this book focuses on soft computing and how it can be applied to solve real world problems arising in various domains ranging from medicine and health care to supply chain management image processing and cryptanalysis it gathers high quality papers presented at the international conference on soft computing theories and applications socta 2022 held at university institute of technology himachal pradesh university shimla himachal pradesh india the book offers valuable insights into soft computing for teachers and researchers alike the book inspires further research in this dynamic field

this monograph studies the design of robust monotonically convergent it ative learning controllers for discrete time systems iterative learning control ilc is well recognized as an e cient method that o ers significant p formance improvement for systems that operate in an iterative or repetitive fashion e g robot arms in manufacturing or batch processes in an industrial setting though the fundamentals of ilc design have been well addressed in the literature two key problems have been the subject of continuing search activity first many ilc design strategies assume nominal knowledge of the system to be controlled only recently has a comprehensive approach to robust ilc analysis and design been established to handle the situation where the plant model is uncertain second it is well known that many ilc algorithms do not produce monotonic convergence though in applications monotonic convergencecan be essential this monograph addresses these two keyproblems by providingauni ed analysisanddesignframeworkforrobust monotonically convergent ilc the particular approach used throughout is to consider ilc design in the iteration domain rather than in the time domain using a lifting technique the two dimensionalilc system

which has dynamics in both the time and iteration domains is transformed into a one dimensional system with dynamics only in the iteration domain the so called super vector framework resulting from this transformation is used to analyze both robustness and monotonic convergence for typical uncertainty models including parametric interval certainties frequency like uncertainty in the iteration domain and iteration domain stochastic uncertainty

in der vorliegenden dissertation wurden untersuchungen zur adaptiven sliding mode regelung mit netzen von gaussianischen radialen basisfunktionen vorgestellt ergebnisse aus simulationen bzw laborexperimenten wurden dargestellt um die leistungsfähigkeit der vorgeschlagenen regelungsverfahren zu veranschaulichen grundlagen der sliding mode regelung wurden in kapitel 2 zusammengefasst die unsicherheit der regelstrecke kann durch eine hochfrequente störfunktion unterdrückt werden die genau einer regelung mit hoher verstärkung der niedrigeren frequenz entspricht die synthese der sliding mode regelung basierend auf der direkten methode von lyapunow mit asymptotischer konvergenz wurde dargestellt in diesem kapitel wurde ein überblick zur adaptiven sliding mode regelung gegeben während die klassischen methoden zur parameterschätzung das adaptive problem für systeme in der linear in parameter form relativ gut lösen wurden neue verfahren der adaptiven regelung mit neuronalen netzen für systeme eingeführt die nicht diese form aufweisen diese verfahren beantworten allerdings meistens nicht die frage der stabilität hinsichtlich der approximationsfehler neuronaler netze eine der hauptideen dieser arbeit ist die integration von smc mit direkter adaptiver regelung in der die stabilität durch die direkte methode von lyapunow sichergestellt wird netze mit gaussianischen radialen basisfunktionen grbf netze wurden als kompensatoren der unsicherheit eingeführt der grund für die auswahl der grbf netze war daß ihre ausgegangslinarkombinationen der ausgangsgewichtungen sind so dass die stabilität des regelkreises einfacher zu erreichen ist grbf netze besitzen neben der besseren konvergenz auch ein schnelleres lernverhalten verglichen mit den multilayer feedforward netzen

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