

Contents

Preface	vii
1 Introduction	1
1.1 Brief History	1
1.2 Motivating Examples	2
1.3 Challenges	12
1.4 Overview of the Book	14
2 High-Gain Observers	17
2.1 Class of Nonlinear Systems	17
2.2 Observer Design	18
2.3 Lyapunov and Riccati Equation Designs	21
2.4 Reduced-Order Observer	23
2.5 Multi-output Systems	26
2.6 Notes and References	30
3 Stabilization and Tracking	31
3.1 Separation Principle	32
3.2 Robust Stabilization of Minimum-Phase Systems	50
3.3 Tracking	60
3.4 Notes and References	70
4 Adaptive Control	73
4.1 Problem Statement	73
4.2 State Feedback Adaptive Control	76
4.3 Output Feedback Adaptive Control	80
4.4 Examples	85
4.5 Robustness	97
4.6 Approximation-Based Control	101
4.7 Notes and References	106
5 Regulation	107
5.1 Internal Model Principle	108
5.2 Integral Control	109
5.3 Conditional Integrator	118
5.4 Conditional Servocompensator	126
5.5 Internal Model Perturbation	139
5.6 Adaptive Internal Model	145
5.7 Notes and References	158

6	Extended Observer	159
6.1	Motivating Examples	160
6.2	Feedback Control via Disturbance Compensation	164
6.3	Nonminimum Phase Systems	194
6.4	Notes and References	210
7	Low-Power Observers	211
7.1	Cascade Observer	212
7.2	Stabilization	219
7.3	Cascade Observer with Feedback Injection	224
7.4	Notes and References	236
8	Measurement Noise	237
8.1	Observer	237
8.2	Closed-Loop Control	245
8.3	Tracking	253
8.4	Reducing the Effect of Measurement Noise	260
8.5	Notes and References	276
9	Digital Implementation	279
9.1	Observer Discretization	280
9.2	Stabilization	284
9.3	Measurement Noise	298
9.4	Multirate Digital Control	301
9.5	Notes and References	309
Bibliography		313
Index		323