

Contents

| | |
|--|------------|
| Abstract | iii |
| Contents | ix |
| Summary of the thesis | 1 |
| Motivation and objectives | 1 |
| Structure of the thesis | 2 |
| Contributions | 4 |
| | |
| I State of the Art | 7 |
| | |
| 1 Linear matrix inequalities in control | 9 |
| 1.1 Definitions, problems, and properties | 9 |
| 1.2 LMIs in linear time-invariant systems | 14 |
| | |
| 2 LMI-based nonlinear control | 25 |
| 2.1 Takagi-Sugeno models | 25 |
| 2.2 Nonlinear control | 31 |
| | |
| 3 Set-based control theory | 51 |
| 3.1 Invariant sets | 51 |
| 3.2 Convex functions and sets | 54 |
| 3.3 One-step sets | 56 |
| 3.4 Polytopes and Multi-Parametric programming (MPT) | 63 |
| 3.5 Convex Difference Inclusions | 65 |
| | |
| II Contributions | 71 |
| | |
| 4 Choosing a Takagi-Sugeno model for improved performance | 73 |
| 4.1 Introduction | 74 |

| | | |
|----------|--|------------|
| 4.2 | Preliminaries | 75 |
| 4.3 | Linear Coordinate Transformations | 77 |
| 4.4 | A Hessian-based methodology | 78 |
| 4.5 | Linearization-based methodology | 82 |
| 4.6 | Conclusions | 86 |
| 5 | Subspace-Based Modelling for Improved LMI Performance | 89 |
| 5.1 | Introduction | 90 |
| 5.2 | Preliminaries | 91 |
| 5.3 | Systematic TS modelling | 96 |
| 5.4 | Coordinate transformations | 99 |
| 5.5 | TS models with optimal performance in a subspace | 102 |
| 5.6 | Use of optimal TS models in LMIs | 110 |
| 5.7 | Discussion | 113 |
| 5.8 | Additional Examples | 114 |
| 5.9 | Conclusions | 119 |
| 6 | Optimal-Performance Models via the LMI Null Space | 123 |
| 6.1 | Introduction | 124 |
| 6.2 | Preliminaries | 125 |
| 6.3 | Main result | 129 |
| 6.4 | Decay-Rate analysis example | 133 |
| 6.5 | Conclusion | 136 |
| 7 | On Modelling of Nonlinear Systems as Quasi-LPV Ones | 137 |
| 7.1 | Introduction | 138 |
| 7.2 | Preliminaries | 140 |
| 7.3 | Main Result | 144 |
| 7.4 | Examples | 152 |
| 7.5 | Conclusions | 160 |
| 8 | Gain-Scheduled Control via Polytopic Difference Inclusions | 163 |
| 8.1 | Introduction | 164 |
| 8.2 | Preliminaries | 165 |
| 8.3 | Set-based approach to dynamic system analysis and control design | 168 |
| 8.4 | Main result: computation of gain-scheduled one-step sets | 172 |
| 8.5 | Convexification of product nonlinearities | 178 |
| 8.6 | Numerical Example | 179 |
| 8.7 | Conclusions | 182 |
| 8.8 | Appendix | 183 |

| | | |
|------------|-------------------------------------|------------|
| III | Conclusions and Bibliography | 187 |
| | Conclusions | 189 |
| | Bibliography | 193 |