

Table of Contents

1 Justification, objectives and contributions	1
1.1 Thesis' s goals	1
1.2 Summary of the original contributions of this work	2
1.3 Thesis organization	2
2 Problem statement	5
2.1 Introduction to the nonlinear flat systems	5
2.2 General approach of the robust controllers design procedure	8
2.2.1 Basic notations	8
2.2.2 Expanding the output space	10
2.2.3 Expanding the state and input space from output space	10
2.2.4 Phases of the robust controllers design procedure	13
2.3 Main problems to be solved	17
2.4 Example applied to a first-order linear system	22
3 Preliminaries	35
3.1 Introduction	35
3.2 Differential flatness	36
3.2.1 Flatness in the context of parametric uncertainty	45
3.3 Modal Interval Analysis	56
3.3.1 Classic intervals and its limitations	56
3.3.2 Modal intervals	62
3.3.3 f^* and f^{**} semantic extensions	64
3.3.4 Applications of the Modal Interval Analysis	70
3.4 Constraints Satisfaction Problems	74
3.5 Quantified Constraints Satisfaction Problems	75
3.6 Conclusions	85
4 Approach to robust possibilistic control of nonlinear flat systems	87
4.1 Levels of possibility	87
4.2 The robust possibilistic control approach	90
4.3 Quantified set inversion	91
4.3.1 Quantified Sets Inversion Algorithm	93
4.4 Set inversion applied to nonlinear flat systems	94
4.4.1 Determining hard and soft uncertainty of the plant	95
4.4.2 Determining hard and soft controllers	100
4.4.3 Determining hard and soft specifications	104
4.4.4 Controller design based on differential flatness to trajectory tracking	107
4.5 Method design	109
4.6 Advantages and limitations of the proposed technique	110
4.7 Conclusions	110
5 Applications	113

5.1 Applications to linear systems	113
5.1.1 Dynamic model of a DC motor	113
5.1.2 Simulation of the system considering a region of flat output	114
5.1.3 Determining the maximum permissible uncertainty in plant parameters	116
5.1.4 Computation of hard and soft controllers	121
5.1.5 Computation of attainable specifications by a nominal controller	122
5.1.6 Robustness test	125
5.1.7 Designing a state feedback controller	126
5.2 Applications to simple pendulum	132
5.2.1 Dynamic model of the simple pendulum	132
5.2.2 Simulation of the system considering a region of flat output	133
5.2.3 Determining the maximum permissible uncertainty in plant parameters	136
5.2.4 Computation of a family of controllers	137
5.2.5 Computation of attainable specifications by a nominal controller	138
5.2.6 Robustness test	139
5.2.7 Designing a state feedback controller	140
5.3 Applications to fed-batch bioreactors.	146
5.3.1 Dynamic model	146
5.3.2 Simulation of the system considering a region of flat outputs	148
5.3.3 Robustness analysis of a nominal controller	151
5.3.4 Computation of a family of controllers	153
5.3.5 Computation of attainable specifications by a nominal controller	155
5.3.6 Robustness test	157
5.3.7 Computation of state feedback controller parameters.	160
5.3.8 Robustness test	164
5.4 Conclusions	164
6 Conclusions and future works.	167
6.1 Conclusions	167
6.2 Future works.	168
Modal intervals	169
A.1 Definitions and properties	169
A.2 Modal interval relations and operations	170
A.3 Semantic extensions of continuous functions	174
A.4 Examples of range computations	182
Exact linearization controller design	203
B.1 SISO systems input-output linearization	203
B.1.1 Application to control of fed-batch bioreactors	205
References	207