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## **Nonlinear Adaptive Observer Based Sliding**

An adaptive back-stepping sliding mode controller (ABSMC) algorithm was developed for nonlinear uncertain systems based on a nonlinear disturbance observer (NDO). The developed ABSMC was applied to attitude control for the dual arm of a humanoid robot.

## **Sliding mode nonlinear disturbance observer-based adaptive ...**

Nonlinear Disturbance Observer-Based Adaptive Sliding Mode Control for a Generic Hypersonic Vehicle In this

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paper, a new adaptive sliding mode control method is presented for the longitudinal model of a generic hypersonic vehicle subject to uncertainties and external disturbance.

### **Nonlinear Disturbance Observer-Based Adaptive Sliding Mode ...**

Adaptive nonlinear observer-based sliding mode control of robotic manipulator for handling an unknown payload Guiying Li, Shuyang Wang, and Zhigang Yu Proceedings of the Institution of Mechanical Engineers, Part I: Journal of Systems and Control Engineering 0  
10.1177/0959651820969461

### **Adaptive nonlinear observer-based sliding mode control of ...**

Both the interconnections and the isolated subsystems are nonlinear. Sliding mode control method and adaptive techniques are employed together to design an observer to estimate the state variables of the

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systems in presence of unknown TVPs.

## **Adaptive Sliding Mode Observer for Nonlinear ...**

The designed observer-based adaptive sliding mode controller not only can adapt the unknown upper bounds of matched nonlinearity and disturbance but also the reachability of system state trajectories, and the error state system can be satisfied. Meanwhile, the stochastic stability of the closed-loop system can be guaranteed.

## **Observer-based adaptive sliding mode control for nonlinear ...**

The robust disturbance observer based sliding surface and the adaptive multivariable super-twisting controller are designed in Section 3. Simulation studies are then shown in Section 4 to verify the effectiveness of the proposed control strategy. The conclusions are presented in Section 5. 2. Problem formulation and preliminaries

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## **Nonlinear disturbance observer based adaptive super ...**

An adaptive super twisting sliding mode controller (ST-SMC) is designed based on system states and estimated disturbance. The nonlinear disturbance observer (NDO) estimates the mismatch between the electrical and mechanical power and then the estimated value is employed in the controller design to compensate the disturbance.

## **Nonlinear disturbance observer based adaptive super ...**

This paper investigates an observer-based adaptive event-triggered sliding mode control (SMC) problem for nonlinear networked systems subject to actuator and sensor saturation with cyber-attacks. First, an improved adaptive event triggering scheme is put forward to reduce the frequency of data communication between the networked system components, and thus the potential communication cost.

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## **Observer-based adaptive event-triggered sliding mode ...**

The adaptive high gain observer that we consider in this paper is addressed to a particular class of nonlinear systems in the block triangular canonical form subject to nonlinear functions with a triangular structure with respect to the subblocks (in our case) which includes several mechanical systems and particularly the self-balancing robot system. The minimum phase assumption and the observer-matching condition are not needed in our adaptive high gain estimation approach, and the unknown

...

## **Adaptive Observer-Based Output Feedback Control for Two ...**

Abstract: This paper deals with the observer-based adaptive sliding mode control (OBASMC) design for nonlinear uncertain singular semi-Markov jump systems. The system satisfies the singular property and follows a stochastic semi-Markov process related

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## **Observer-Based Adaptive SMC for Nonlinear Uncertain ...**

nonlinear systems. A nonlinear adaptive sliding-mode observer is proposed based on a nonlinear parameter estimation algorithm. It is shown that such a nonlinear algorithm provides a rate of convergence faster than exponential, i.e. faster than the classic linear algorithm. Then, the proposed parameter estimation

## **An Adaptive Sliding-Mode Observer for a Class of Uncertain ...**

In this paper, a sliding mode control (SMC) scheme is proposed for a class of nonlinear systems based on disturbance observers. For a nonlinear system, the disturbance that cannot be directly measured is estimated using a nonlinear disturbance observer.

## **Sliding mode control for a class of uncertain nonlinear ...**

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### **Nonlinear Adaptive Observer Based Sliding Mode Control For**

An adaptive disturbance observer (ADO)-based practical terminal sliding mode control (TSMC) that required no exact feedback linearization about the plant dynamics was suggested in [15]. The ADO ...

### **Practical terminal sliding mode control of nonlinear ...**

A new methodology for an adaptive state observer design for a class of nonlinear systems with unknown parameters in unmeasured state dynamics Nabil Oucief, Mohamed

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Tadjine, and Salim Labiod Transactions  
of the Institute of Measurement and  
Control 201640:4, 1297-1308

## **A new methodology for an adaptive state observer design ...**

Chattering in the traditional sliding mode control method is minimized by introducing a continuous term in switching function. An enhanced nonlinear disturbance observer is designed to ensure the robustness of the proposed controller. Through rigorous analysis, the stability is proved using the Lyapunov method.

## **Enhanced nonlinear disturbance observer based sliding mode ...**

nonlinear adaptive sliding-mode observer is proposed based on a nonlinear parameter estimation algorithm.

## **Adaptive Estimation for Uncertain Nonlinear Systems: A ...**

Continuous nonsingular terminal sliding

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mode control based on adaptive sliding mode disturbance observer. In this section by using the proposed disturbance observer in Theorem 10 and the sliding surface stated in Lemma 6, a CNTSMC for system (1) is proposed. Theorem 13. Consider the nonlinear system (1) and the sliding surface  $s$  in (13).

## **Continuous nonsingular terminal sliding mode control based ...**

Abstract: This study gives the mathematic model of a quadrotor unmanned aerial vehicle (UAV) and then proposes a robust nonlinear controller which combines the sliding-mode control technique and the backstepping control technique. To achieve Cartesian position trajectory tracking capability, the construction of the controller can be divided into two stages: a regular SMC controller for attitude subsystem (inner loop) is first developed to guarantee fast convergence rapidity of Euler angles ...

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