

Contents

Nomenclature	XI
Abstract	XIII
Deutsche Kurzfassung	XV
1 Introduction	1
1.1 Motivation and Focus of the Thesis	2
1.2 Contributions of the Thesis	6
1.3 Outline of the Thesis	8
2 Nonlinear Model Predictive Control	11
2.1 Review on Predictive Control	11
2.1.1 NMPC of Continuous-Time Nonlinear Systems	12
2.1.2 NMPC of Discrete-time Systems	16
2.2 Robust NMPC approaches	18
2.3 LMI-based Design of Stabilising NMPC for Continuous-time Systems	20
2.4 LMI-based Robust NMPC for Discrete-time Systems	22
2.5 Discussion and Motivation of New Contributions	25
3 Periodic Systems	27
3.1 Discrete-time Periodic Systems	27
3.1.1 Nonlinear Periodic Systems	27
3.1.2 Linear Periodic Systems	28
3.1.3 Stability of Periodic Systems	28
3.2 Periodic Lyapunov Functions	31
3.2.1 Relaxed Stability Conditions	31
3.2.2 Computation of a Region of Attraction	34
3.2.3 Illustrative Example	36
3.3 Periodic Control Systems	38
3.3.1 Nonlinear Periodic Control Systems	39
3.3.2 Periodic Polytopic Linear Difference Inclusions	39
3.3.3 Linear Periodic Control Systems	40
3.3.4 Polytopic Uncertain Linear Periodic Control Systems	41
3.4 Control of Periodic Systems	41
3.5 Summary and Discussion	44

4	Predictive Control of Periodic Systems	45
4.1	Provisional Result	45
4.2	Quasi-infinite Horizon NMPC for Periodic Systems	48
4.3	Robust NMPC for Polytopic Uncertain Linear Periodic Systems	52
4.4	Efficient offline formulation	55
4.5	Trajectory-dependent Periodic Control Lyapunov Functions	59
4.5.1	Trajectory-dependent Control Lyapunov Functions for Time-invariant Systems	60
4.5.2	Synthesis of Periodic Control Lyapunov Functions	61
4.5.3	Implementation via semi-definite programming	65
4.5.4	Illustrative Example	67
4.6	Summary and Discussion	69
4.6.1	Further Interesting NMPC Results Related to this Thesis	69
4.6.2	Summary	70
4.6.3	Possible Extensions and New Research Ideas	71
5	Satellite Control with Magnetic Actuation	73
5.1	Introduction to the Control Problem	73
5.2	Satellite Dynamics	75
5.3	Spacecraft Rate Damping with Predictive Control	78
5.3.1	Predictive Rate Damping Controller	79
5.3.2	Simulation Results	81
5.4	Satellite Attitude Control with Periodic NMPC	83
5.4.1	Control Task and System Parameters	83
5.4.2	Controller Design Parameters	84
5.4.3	Simulation Results	84
5.4.4	Outlook	86
5.5	Summary and Discussion	86
6	Predictive Control of Lur'e Systems	89
6.1	Introduction to Lur'e Systems	89
6.1.1	Stability Analysis of Autonomous Lur'e Systems	90
6.1.2	Control of Lur'e Systems	92
6.1.3	Control Task and Problem Setup	92
6.2	Robust Stabilisation of Uncertain Lur'e Systems	93
6.3	Quasi-infinite Horizon NMPC for Nominal Lur'e Systems	95
6.4	Robust NMPC of Lur'e Systems	98
6.5	Efficient Offline Formulation	101
6.6	Flexible Link Robotic Arm	105
6.6.1	Choice of Design Parameters	106
6.6.2	Simulation Results	107
6.7	Future Research Ideas	110
6.8	Summary and Discussion	111

7	Conclusions	113
7.1	Summary	113
7.2	Outlook and Perspectives for Future Research	114
A	Fundamentals of Semi-definite Programming	117
A.1	Positive and Negative Definite Matrices	117
A.2	Linear Matrix Inequalities	117
A.3	Useful Results Involving LMIs	118
A.4	Semi-definite Programs	119
A.5	Maximising the Size of Ellipsoids	119
B	Stability of Dynamical Systems	121
B.1	Stability of Continuous-time Systems	121
B.2	Stability of Discrete-time Systems	122
C	Spacecraft Dynamics - Auxiliary Models and Proof of Theorem 5.1	125
C.1	Model of the Earth Magnetic Field	125
C.2	Linearisation of Attitude Dynamics	126
C.3	Proof of Theorem 5.1	127
	Bibliography	129