

عنوان مقاله:

Neuro-Adaptive Sliding Mode Based Control of Nonlinear Systems Using Radial Basis Function Networks

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خلاصه مقاله:

In this paper, a new method for robust control of nonlinear systems using neural network and SMC methodology is proposed. In this method, a radial basis function network is used as a controller whose parameters must be updated. A modified SMC methodology is used to adjust the parameter of controller such that a zero learning error level is reached in one-dimensional phase space defined on the system output. The performance of the proposed method is demonstrated via simulations

کلمات کلیدی:

Sliding Mode Control, Neural Control, Adaptive Control, Radial Basis Function Neural Network

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