

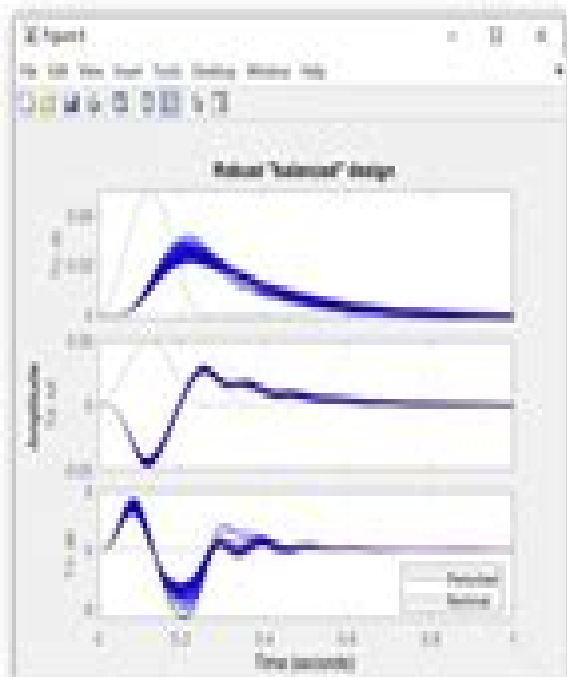
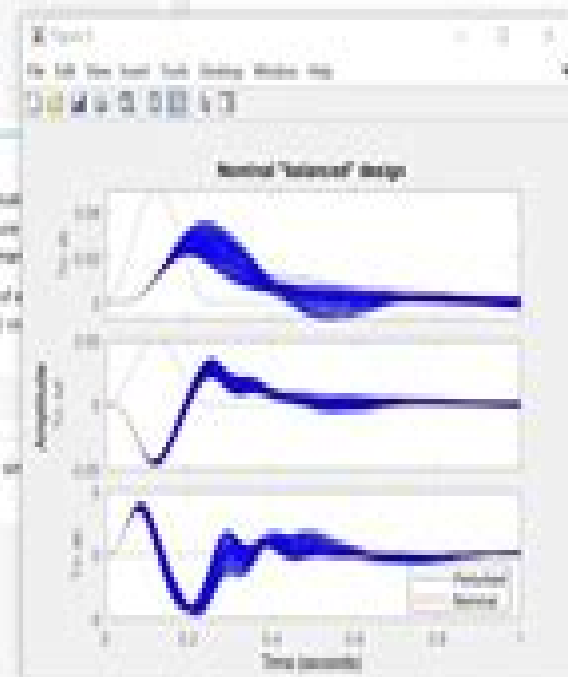
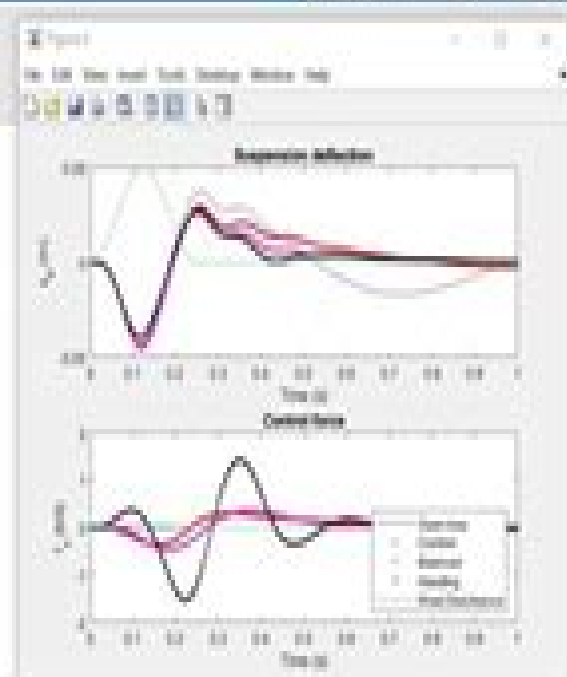
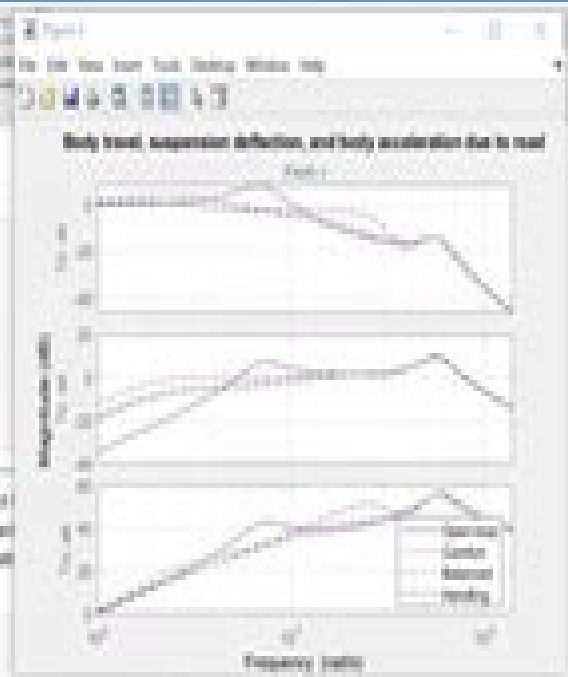
```

% Nominal Mu Design
% Use h2opt to compute  $H_2$  controllers for each value of the bending factor  $\beta$ 

%
% Agent = 2, 5 are control signals,  $u$ 
% meas = 2, 5 are measurement signals,  $z$  and  $w$ 
%  $\beta$  = scenario(meas,meas,H2)
% gains = gains(2,5)
% for j=1:3
%     [G1,j,G2,j,gains(1,j)] = h2opt(gains(1,j),G1,meas,meas);
% end
%
%
%
%
% The three controllers achieve closed-loop  $H_2$  norms of 0.04, 0.07 and 0.09, respectively. (Control
% closed-loop models and compare the gains from road disturbance to  $u_1, u_2, u_3$  for the passive and
% observe that all three controllers reduce suspension deflection and body acceleration below the set
% points)

% 3 closed-loop models
%  $u_1, u_2, u_3 \in [10^3, 10^4] \text{ N}$ ,  $z_1, z_2 \in [1, 10]$ 
%  $\beta_1 = \text{convert}(z_1, \text{m}, \text{feet}), \beta_2 = [10^3, 10^4] \text{ N}$ 
%
% h2mag = [G1, G2, G3, H2(1,1), H2(2,1), H2(3,1)];
% [G1, G2, G3, H2(1,1), H2(2,1), H2(3,1), g1, g2, g3] =
% legend('open-loop', 'Control', 'Isolated', 'Isolation', 'Isolation', 'Isolation');
% [z1, z2, z3, z4, z5, z6, z7, z8, z9, z10, z11, z12, z13, z14, z15, z16, z17, z18, z19, z20, z21, z22, z23, z24, z25, z26, z27, z28, z29, z30, z31, z32, z33, z34, z35, z36, z37, z38, z39, z40, z41, z42, z43, z44, z45, z46, z47, z48, z49, z50, z51, z52, z53, z54, z55, z56, z57, z58, z59, z60, z61, z62, z63, z64, z65, z66, z67, z68, z69, z70, z71, z72, z73, z74, z75, z76, z77, z78, z79, z80, z81, z82, z83, z84, z85, z86, z87, z88, z89, z90, z91, z92, z93, z94, z95, z96, z97, z98, z99, z100] =
% [z1, z2, z3, z4, z5, z6, z7, z8, z9, z10, z11, z12, z13, z14, z15, z16, z17, z18, z19, z20, z21, z22, z23, z24, z25, z26, z27, z28, z29, z30, z31, z32, z33, z34, z35, z36, z37, z38, z39, z40, z41, z42, z43, z44, z45, z46, z47, z48, z49, z50, z51, z52, z53, z54, z55, z56, z57, z58, z59, z60, z61, z62, z63, z64, z65, z66, z67, z68, z69, z70, z71, z72, z73, z74, z75, z76, z77, z78, z79, z80, z81, z82, z83, z84, z85, z86, z87, z88, z89, z90, z91, z92, z93, z94, z95, z96, z97, z98, z99, z100]
%
%
% Robust Mu Design
% So far you have designed  $H_2$  controllers that meet the performance objectives for the nominal vehicle
% dynamics model. This model is only an approximation of the true vehicle and you need to make sure
% performance is maintained in the face of model errors and uncertainties. This is called robust performance.
% Next use  $\mu$ -synthesis to design a controller that achieves robust performance for the entire family of a
% robust controller is synthesized with the  $\mu$ -synthesis using the standard model  $\text{getmdl}(\beta, \beta)$  or
% "balanced" performance ( $\beta = 0.5$ )
%
% [ctrl, rgt] = muopt(gains(1,1), G1, meas, meas);
%
% Simulate the nominal response to a road bump with the robust controller  $\text{ctrl}$ . The responses are all
% obtained with the "balanced"  $H_2$  controller
%
% % 3 closed-loop models (nominal)
%  $u_1, u_2, u_3 \in [10^3, 10^4] \text{ N}$ 
%  $z_1, z_2 \in [1, 10]$ 
%  $\beta_1 = \text{convert}(z_1, \text{m}, \text{feet}), \beta_2 = [10^3, 10^4] \text{ N}$ 
%
% h2mag = [G1, G2, G3, H2(1,1), H2(2,1), H2(3,1)];
% [G1, G2, G3, H2(1,1), H2(2,1), H2(3,1), g1, g2, g3] =
% legend('open-loop', 'Control', 'Isolated', 'Isolation', 'Isolation', 'Isolation');
% [z1, z2, z3, z4, z5, z6, z7, z8, z9, z10, z11, z12, z13, z14, z15, z16, z17, z18, z19, z20, z21, z22, z23, z24, z25, z26, z27, z28, z29, z30, z31, z32, z33, z34, z35, z36, z37, z38, z39, z40, z41, z42, z43, z44, z45, z46, z47, z48, z49, z50, z51, z52, z53, z54, z55, z56, z57, z58, z59, z60, z61, z62, z63, z64, z65, z66, z67, z68, z69, z70, z71, z72, z73, z74, z75, z76, z77, z78, z79, z80, z81, z82, z83, z84, z85, z86, z87, z88, z89, z90, z91, z92, z93, z94, z95, z96, z97, z98, z99, z100] =
% [z1, z2, z3, z4, z5, z6, z7, z8, z9, z10, z11, z12, z13, z14, z15, z16, z17, z18, z19, z20, z21, z22, z23, z24, z25, z26, z27, z28, z29, z30, z31, z32, z33, z34, z35, z36, z37, z38, z39, z40, z41, z42, z43, z44, z45, z46, z47, z48, z49, z50, z51, z52, z53, z54, z55, z56, z57, z58, z59, z60, z61, z62, z63, z64, z65, z66, z67, z68, z69, z70, z71, z72, z73, z74, z75, z76, z77, z78, z79, z80, z81, z82, z83, z84, z85, z86, z87, z88, z89, z90, z91, z92, z93, z94, z95, z96, z97, z98, z99, z100]
%
% % Simulate
% % of a "balanced"  $H_2$  controller

```



# Matlab Robust Control Toolbox Manual

**Mark Steyvers**



## **Matlab Robust Control Toolbox Manual:**

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