

from 0.001 to 0.05, and 0.05 to 0.1, respectively, for each value of the binding factor β .

```

count = 0; % the control signal, y
meas = 0; % the measurement signal, set at 0
t = asctime(now,meas,0);
gens = zeros(1,10);
for p=1:10
    [C,~,J],~,gens[[1]] = fitPop(gens[[1]],J,0,meas,now,t);
end
end

```

The three controllers achieve closed-loop H_2 norms of 1.04, 0.07 and 0.01, respectively. Construct closed-loop models and compare the gains from road disturbance to y_1, y_2, y_3 for the passive and active. Observe that all three controllers reduce suspension deflection and body acceleration below the set points.

[illegible]

So far you have designed \hat{X}_n controllers that meet the performance objectives for the nominal value (nominal) system. This model is only an approximation of the true situation and you need to make sure performance is maintained in the face of model errors and uncertainties. This is called robust performance.

Next you *will* synthesize design \hat{X}_n controllers that achieve robust performance for the entire family of \hat{X}_n models (controllers is synthesized with the design function using the structured model matrix) $\{ \hat{X}_n \}$ or “nominal” performance ($\beta = 0.1$).

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Describe the normal response to a challenge with the ritual substrate (e.g., The response is not observed with the 'balanced' H_2 substrate).

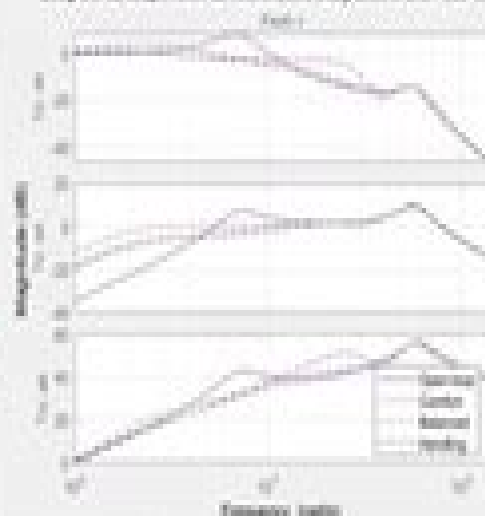
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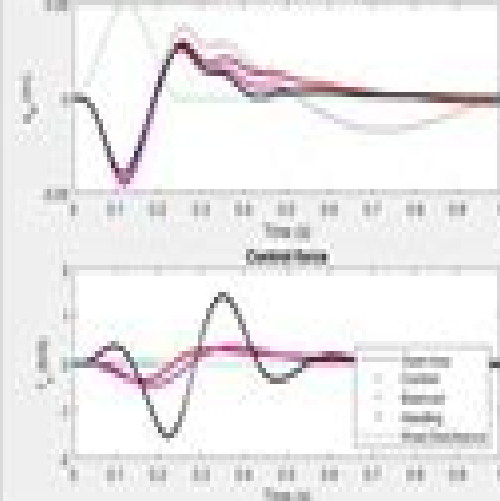
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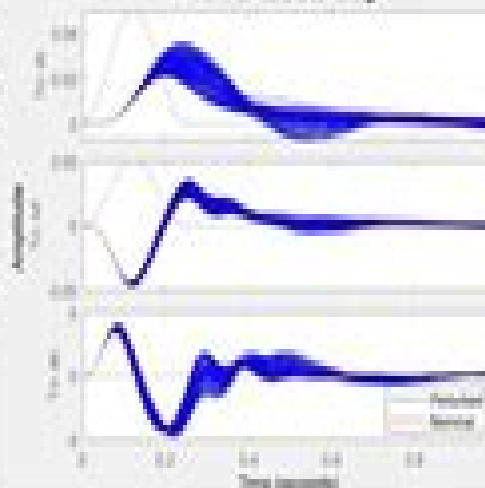
Body travel, suspension deflection, and body acceleration due to road



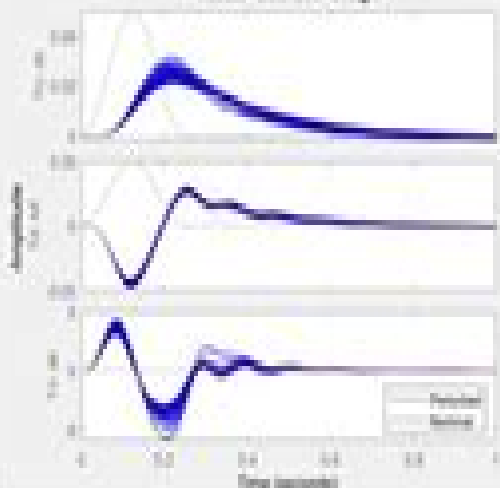
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Matlab Robust Control Toolbox Manual

Tao Wei



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 - Chapter 3: Matlab Robust Control Toolbox Manual in Everyday Life
 - Chapter 4: Matlab Robust Control Toolbox Manual in Specific Contexts
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