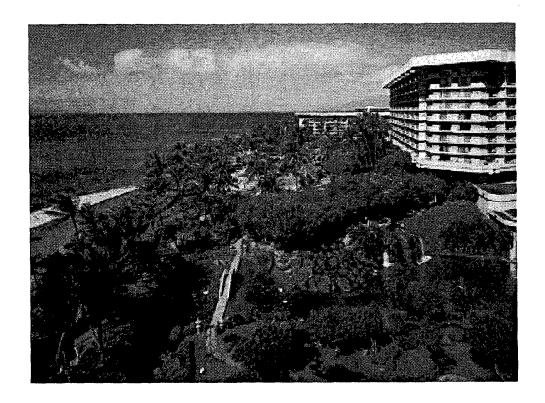
### 42nd IEEE CONFERENCE ON DECISION AND CONTROL

# **PROCEEDINGS**





December 9-12, 2003





The Hyatt Regency Resort & Spa Maui, Hawaii, USA







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9-12 December 2003 The Hyatt Regency Resort & Spa Maui, Hawaii, USA

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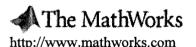
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### I. INVITATION

Aloha! and welcome to your 42nd IEEE Conference on Decision and Control being held at the Hyatt Regency Maui, Hawaii during December 9-12, 2003. It took us 13 years to come back to Hawaii, for a repeat performance of the widely successful 1990 CDC conference in Waikiki beach, Oahu. Our magnificent venue is situated on a beautiful, wide stretch of Kaanapali Beach beside the jewel-like Pacific. Four miles south is the quaint historical whaling port of Lahaina, and few miles beyond is Haleakala Mountain and volcano. Maui offers the adventurous opportunities to bike, hike, snorkel, and scuba dive, and to those who enjoy fine dining, an endless array of restaurants catering to your every taste.

The "Hawaii factor" has contributed to a record submission and acceptance of papers. Our program contains 1115 papers in all, for a 61% acceptance rate. We plan on 14 parallel sessions, and for the first time, one poster/interactive session. Also notable is the sponsorship by industry. Our major industry sponsors are Honeywell, Xerox, National Instruments, and The MathWorks. Each of these will have a special evening sponsor's session.

CDC 03 has a rich plenary structure. The Bode Lecture will be delivered by Lennart Ljung of Linköping University. The Plenary Speakers are Katsuhisa Furuta, past president of Japan's SICE, Vladimir Kucera, President of IFAC, and Tamer Basar, past president of IEEE Control Systems Society. Also attending will be Ioan Landau, Founder and First President of the European Union Control Association. Janusz Bryzek will give a keynote talk about Control Issues for MEMS. Kishan Baheti and Murti Salapaka have organized a special track on Nanotechnology. There are three Plenary Panels: International Funding Thrusts and Mechanisms, History of Controls, and CSS Presidents Panels.

Five workshops spanning the spectrum of current research interest areas in our field have been proposed. Whale season starts in early December, so you may see the humpback whales out of

Lahaina, or even from our conference venue. Finally, opening and closing receptions on the beachside with music and cultural dancers are calculated to round out the experience to a full one both in technical and social terms.

It will be wonderful to see all of you in Maui. We trust that you will take time from attending the technical sessions to stroll down the beach and to capture some of the Hawaii magic. And when you have the time, please let someone on the organizing committee know your feelings about this CDC. It will help improve your future CDCs.

### Aloha and Mahalo,

Frank L. Lewis, The University of Texas at Arlington, General Chair, CDC 2003 Maui

Chaouki Abdallah, The University of New Mexico, Program Chair, CDC 2003 Maui

### II. CONFERENCE HIGHLIGHTS

### **Technical Program Overview**

Fort the first time, the CDC technical program was handled using Paperplaza, a web-based system developed by Professor Huibert Kwakernaak, and managed by Professors Thomas Parisini, Douglas Lawrence and Pradeep Misra. Despite the novelty and technical glitches, Paperplaza helped in handling the largest amount of submissions ever (1850 papers) and successfully managed the reviews and program statistics.

This year's technical program introduces the Poster/Interactive (P/I) format to the CDC. The P/I papers have received the same review as those submitted under the usual oral format. Glancing through the sessions titles, it is obvious that our field continues to evolve with new topics (hybrid, time-delay, communications, autonomous systems, quantum control, biomedical, MEMS) rising in popularity, while "old favorites" such as nonlinear systems, and robust control remain strong.

In addition to the 14 parallel oral sessions, and to the 1 Poster/Interactive session, the program contains the following:

### **Plenary Sessions**

Tuesday morning at 8:00am Professor Vladimir Kucera of Czech Technical University in Prague will present a lecture entitled "Feedback Control: the Origins, the Milestones, and the Trends."

Wednesday morning at 8:00am Professor Katsuhisa Furuta of Tokyo Denki University will present a lecture entitled "Control of Pendulum: - From Super Mechano-System to Human Adaptive Mechatronics."

Thursday morning at 8:00am Professor Tamer Basar of The University of Illinois will present a lecture entitled "Entanglement of Communication and Control."

### **Bode Lecture**

Friday morning at 11:00am Professor Lennart Ljung of Linköping University will deliver the Bode lecture, titled "Challenges of Nonlinear Identification."

### **Keynote Talks**

Wednesday afternoon at 2:20pm Dr. Kishan Baheti of the U.S. National Science Foundation will present a lecture entitled "Nanoscale Science and Engineering at NSF."

Wednesday evening at 7:00pm Dr. Janusz Bryzek will present a lecture entitled "Control Issues for MEMS."

### **Plenary Panels**

Tuesday at noon Dr. Paul Werbos of the U.S. National Science Foundation will chair a panel on "International Funding Thrusts and Mechanisms."

Wednesday at noon Dr. Danny Abramovitch of Agilent Labs will chair a panel on "History of Controls."

Thursday at noon Dr. Mike Masten of Texas Instruments will chair the CSS Presidents Panel.

### **Industry Sponsor Evening Sessions**

Our Major Industry Sponsor Sessions are as follows:

Tuesday evening at 7:00pm

Honeywell Industry Session

http://www.honeywell.com

National Instruments Industry Session

http://www.ni.com

Wednesday evening at 7:00pm

Xerox Industry Session
The MathWorks Industry Session

http://www.xerox.com http://www.mathworks.com

### The First NSF Workshop for Women in Control - Dedicated to Cheryl Schrader, CSS President

Wednesday 9:30am-1:30pm Professor Bozenna Pasik-Duncan of the University of Kansas will lead a workshop entitled "After Graduation: Women in Control Taking a Leadership Role." Dr. Vasundara V. Varadan, Division Director—Electrical & Communications Systems from the U.S. National Science Foundation will be a keynote speaker. Leadership activities will include panels, lectures, informal discussions and case studies. Panel and discussions will address issues concerning involvement in professional societies, being a departmental or college administrator, a research leader, a community leader, an effective mentor, and challenges in balancing a career and family. The workshop is open to all participants of the 2003 CDC.

## The NSF Workshop for High School Teachers and Students for Maui District, which includes the islands of Maui, Lanai, and Molokai.

Tuesday 8:30am- 4:00pm Professor Bozenna Pasik-Duncan of the University of Kansas will lead a workshop for high school teachers and students, entitled "Ideas and Technology of Control and Systems". The purpose of the workshop is to increase the general awareness among high school teachers and students of the importance of control and systems technology and its cross-disciplinary nature. Workshop activities will include panels, lectures, informal discussions and case studies. The list of speakers with their talks include: Dr. Christos G. Cassandras, "Joys and Perils of Automation," Dr. Raffaello D'Andrea, "Control of Autonomous Vehicles," Dr. Theodore E. Djaferis, "The Power of Feedback," Dr. Katsuhisa Furuta, "Understanding Phenomena Through Real Physical Objects—Understanding Controlling Pendulum," Dr. P.R. Kumar, "How the Internet and Wireless Networks are Controlled: What's happening behind the screen," Dr. Richard Murray, "Autonomous Vehicles: Racing from Los Angeles to Las Vegas," Dr. Mark Spong, "Future Careers in Embedded Systems, Mechatronics, and Control." The workshop is open to all participants of the 2003 CDC.

## Decision and Control for Unmanned Autonomous Vehicles (UAVs) – New Developments and New Directions

Tuesday evening at 7:00 pm - 8:30 pm Honeywell Laboratories will sponsor a special industry session on "Decision and Control for Unmanned Autonomous Vehicles (UAVs)—New Developments and New

Directions, organized by Drs. Datta Godbole and Tariq Samad of Honeywell Labs. Unmanned aerial vehicles have been on military roadmaps and in the air for, literally, decades, but it is only recently that meaningful levels of *autonomy* have started to be realized. Control engineering has been a key discipline for enabling this progress and continues to be viewed as critical for the future. This special session, which includes representatives from academe, government, and industry, will highlight recent accomplishments in the control of autonomous vehicles and identify priorities and programs for future controls-related research in this area. The session will consist of the following five presentations followed by discussion: "Session objectives and introduction," *Tariq Samad* (Honeywell Labs), "Coordination and control of multivehicle teams," *Shankar Sastry* (University of California, Berkeley), "High-performance autonomous rotorcraft," *George J. Vachtsevanos* (Georgia Institute of Technology), "Guidance and control for the DARPA/Honeywell Organic Air Vehicle," *Dale F. Enns* (Honeywell Labs), "DoD research opportunities for UAVs," *John S. Bay* (DARPA).

### **Tutorial Workshops**

Five workshops will be held on Sunday and Monday prior to the conference. The tutorial workshop presenters are leaders in their fields who have published extensively and are experienced lecturers. Workshop registration fees include lecture notes and are payable either through pre-registration or on-site at the Registration Desk (see "Registration" for details). There is an NSF-sponsored workshop on "Cross-Disciplinary Research and the Role of Industry" that is gratis to all conference registrants.

### **Exhibits and Information for Industry Exhibitors**

Exhibits will be presented by book publishers and developers of control software and hardware products. For information about exhibiting for your company please contact Exhibits Chair Professor Hua Wang of Boston University. The benefits and details about exhibiting are on the CDC website.

### **CSS Board of Governors Meeting**

The semiannual IEEE Control System Society Board of Governors Meeting will be held 12:00-6:00pm Monday. This is an open meeting and all members of the Society are invited to attend.

### TUESDAY PLENARY

Feedback Control: the Origins, the Milestones, and the Trends

# Vladimir Kucera Czech Technical University in Prague, Czech Republic kucera@fel.cvut.cz, http://www.fel.cvut.cz/dean/

This plenary reviews the major trends in Feedback Control, identifies emerging challenges for control theory, and forecasts future technological developments in the field. Realizing that the best way to understand an area is to examine its evolution and the reasons for its existence, a brief history of feedback control is provided first. Ingenious feedback devices can be traced back to the ancient Alexandria. The milestones of this evolution were the flying ball governor of James Watt and its stability analysis by Maxwell, the stability theory of Lyapunov, the conception of three-term or PID controllers, the invention of negative feedback amplifiers, the introduction of Nyquist and Bode charts, and Wiener's cybernetics.

The post war developments included optimal control and filtering, adaptive control, robust control, and hybrid control systems. The computer technology in particular has had a tremendous impact on control theory and its application.



Today, as a result of this evolution, it is possible to implement advanced control methodologies. We have smart sensors and smart actuators. The most dramatic impact of electronic processing occurs in controllers. In times past, computational demands of adaptive, optimal and robust control techniques could not be easily performed. With modern electronics, such operations are possible. Modern electronic implementations are also more immune to aging effects, system noise and disturbances.

The forecast of future technological developments is based on the methods and technologies that emerge in computers, communications, networking, manufacturing, nanoscale science, medicine, and biology. Control theory, on the other hand, is looking for new solutions. There is a strong influence of computer science and engineering. Feedback will be used mostly to stabilize the process and to counteract uncertainties, with other functions achieved by a feedforward. The truly exciting developments in any field will occur where there is a confluence of application drivers and disciplinary development of the subject. Automatic control is no exception. Much attention will have to be paid to education and training. The education must be multidisciplinary, with a focus on teaching general methods rather than vocational skills.

The International Federation of Automatic Control, known as IFAC, represents the worldwide community of automatic control. The most important events of IFAC are the Triennial World Congresses. The forthcoming congress, in 2005, will be held in Prague, Czech Republic.

Every member of the broad automatic control community is invited to visit and regularly follow the Congress WebPages at www.ifac.cz and ultimately take part in the Congress activities during July 4-8, 2005.

Vladimir Kucera was born in Prague, Czechoslovakia in 1943. He studied at the Czech Technical University in Prague, where he obtained an Ing. degree in Electrical Engineering with distinction in 1966. He received the CSc. and DrSc. research degrees in Control Engineering from the Czechoslovak Academy of Sciences in 1970 and 1979, respectively.

During 1970-1999, V. Kucera was a member of the Institute of Information Theory and Automation, one of the research institutes of the Academy of Sciences in Prague. He held various research and managerial positions, including Vice-Director (1986-1990) and Director (1990-1998) of

the Institute. Since 1992, he has been active at the Czech Technical University in Prague. During 1999-2000, he was Head of Control Engineering Department and in 2000, he was elected Dean of the Faculty of Electrical Engineering.

V. Kucera held visiting positions at the National Research Council, Ottawa, Canada in 1970-1971; University of Florida, Gainesville, USA in 1977; Ecole Nationale Superieure de Mecanique, Nantes, France in 1981-1982; Australian National University, Canberra, Australia in 1984; Uppsala Universitet, Sweden in 1989; Centro de Investigacion y de Estudios Avanzados del IPN, Mexico City in 1991; ETH Zurich, Switzerland in 1992; University of Newcastle, Australia in 1993; Politecnico di Milano, Italy in 1995 as well as a number of short visiting appointments. He was Nippon Steel Professor at the Chair of Intelligent Control, Tokyo Institute of Technology, Japan in 1994.

The research interests of V. Kucera include control systems analysis and design. He contributed to the theory of Riccati equations and pioneered the use of polynomial equations in the design of control systems. His best result is the parametrization of all controllers that stabilize a given plant, known as the Youla-Kucera parametrization, which has become a new paradigm in robust and optimal control.

The industrial experience of V. Kucera includes the design of an adaptive controller for a rolling mill; the development of fast and precise servomechanisms; a cooperation with the Nippon Steel Corporation, Japan and the participation in European projects Dynamic Control and Management Systems in Manufacturing Processes, and Advanced Methodologies and Tools for Manufacturing Systems. Since 2000, he has been Head of the Center for Applied Cybernetics, Czech Technical University in Prague.

V. Kucera is the author of four books: Algebraic Theory of Discrete Linear Control (in Czech) (Academia, Prague 1978), Discrete Linear Control: The Polynomial Equation Approach (Wiley, Chichester 1979), Analysis and Design of Discrete Linear Control Systems (Prentice-Hall, London 1991), and Polynomial Methods for Control Systems Design, edited with M. J. Grimble (Springer, London 1996). He published 104 research papers in the most influential journals of automatic control, 136 contributions in the proceedings of international conferences, and 70 other works. The citation databases of the Thomson Institute for Scientific Information, Philadelphia include 1,560 citations of his publications, direct and indirect autocitations excluded.

V. Kucera combines research with teaching. Since 1996 he has been a Professor of Engineering Cybernetics at the Czech Technical University in Prague. He teaches graduate courses on systems and control. He has also given many courses at prestigious European, American, Asian, and Australian universities.

V. Kucera serves on the editorial boards of Automa, Slaboproudy obzor, Int. J. Robust and Nonlinear Control, and Bull. Polish Acad. Sciences. He was Editor-in-Chief of Kybernetika (1990-1998), an Associate Editor of Automatica (1987-1996) and a member of the editorial boards of Syst. Control Letters (1987-1994), Int. J. Control (1990-1999), Int. J. Systems Science (1986-1999), J. Math. Systems, Estimation and Control (1991-1998). He is President of the International Federation of Automatic Control, Fellow of IEE, Fellow of IEEE (the first one in the Czech Republic), and was a member of the IEEE Control Systems Society Board of Governors (1996-1998). He is a founding member and Vice-President of the Engineering Academy of the Czech Republic, and past Chairman of the Czech Committee for Automatic Control (1993 – 2002).

V. Kucera received the Prize of the Czechoslovak Academy of Sciences in 1973, Kybernetika Best Paper Award in 1976, National Prize of the Czech Republic in 1989 for his contributions to the theory and practice of automatic control, Automatica Prize Paper Award in 1990 for paper Fundamental Theorem of State Feedback for Singular Systems, Hlávka Foundation Prize in 1992, Outstanding Service Award from IFAC in 1996, and Medal of the Ministry of Education of the Czech Republic in 2000. He is an Honorary Professor at the Northeastern University, Shenyang, China (1996) and received a Doctor honoris causa degree from Université Paul Sabatier, Toulouse (2003).

### WEDNESDAY PLENARY

Control of Pendulum: -From Super Mechano-System to Human Adaptive Mechatronics

### Professor Katsuhisa Furuta School of Science and Engineering Tokyo Denki University

The Super Mechano-System has been a research project at Tokyo Institute of Technology from 1997 to 2002. Human Adaptive Mechatronics (HAM) Project is a new COE research project at Tokyo Denki University; it will extend from 2003 to 2008. Both projects are sponsored by the Ministry of Education, Sports, Culture, Science and Technology in Japan. Super-Mechano Systems (SMS) are defined as mechanical systems that autonomously organize themselves by changing their structure and functions to attain higher performance for given objectives in a varying environment. The speaker was the project leader until 2000, when Prof. S. Hirose succeeded him. Many mechanical systems with functions adapting to varying environments and their relating basic theories have been developed, such as Roller Walker (S.Hirose at el.), Anaconda (S.Hirose and M.Yamakita), Super Mehcano-



Boy (Hirose, Sampei), and others. A concurrent design method for the mechanism and the controller has been developed by the project's control research group (Hara and Iwasaki).

A Human Adaptive Mechatronics system includes a human in the control loop and changes the functions and structure of the man-machine interface according to improvements in the human's operating skill. These systems are considered to change the constraints of their subsystems. In this plenary lecture, some examples of the modeling of multiple pendulums and their control, from the hanging to the upright position, are discussed. Swing-up control of the pendulum will be discussed in terms of global stabilization of a unstable nonlinear system by nonlinear control. Previous results of pendulum control by the speaker are surveyed. A new approach to analysis and design of nonlinear controls based on Fractals will be presented. The results show that the maps of the control parameters and the initial conditions give interesting results.

Katsuhisa Furuta was born in Tokyo, Japan in 1940. He received his BS. MS., and Ph.D. degrees in Engineering from Tokyo Institute of Technology in 1962, 1964, and 1967, respectively. He was a Professor of Control Engineering at Tokyo Institute of Technology until the end of March 2000. He was a Russell Severance Springer Visiting Professor at The University of California at Berkeley in March 1997. He is currently a Professor at Tokyo Denki University in the Department of Computers and Systems Engineering.

He was a Member of The Science Council of Japan from 1997 to 2003. From 1994 to 1999 he was an IFAC Council Member, and he served as the Editor for Control Applications of Automatica from 1996 to 1999. Since June 2002 he has served as the Research Supervisor of Mine Detection and Clearance Activities for Japan Science and Technology, Co.

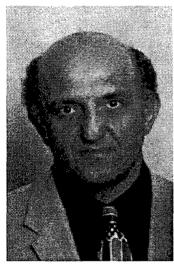
He received an honorary doctorate from Helsinki University of Technology in 1998, and has many international awards, including IEEE CSS Distinguished Member in 1998, and IEEE Third Millennium Medal in 2000. He is a Fellow of both SICE and IEEE.

### THURSDAY PLENARY

### **Entanglement of Communication and Control**

Tamer Basar
Fredric G. and Elizabeth H. Nearing Professor
Dept. Of Electrical and Computer Engineering
University of Illinois at Urbana-Champaign

Availability of accurate and timely information on the state of a dynamic system or on the uncertain environment where the system to be controlled resides has always been an important ingredient of a high-performance controller design. Roughly speaking, the more is communicated to a controller, the better is the performance it delivers. Driven by this dictum, research in control of uncertain systems has addressed for many decades the problems of first how to reshape (for example, encode) the available information within given constraints, and then how to process it (decode or filter) so that it will be of utmost value to the controller. There is also the question of whether and how the control itself can be used to improve the quality of this information (the dual or triple role of control) toward in turn improving its own performance. Hence, by and large, in all these scenarios, communication delivers performance improvement to control.



Recently, a different scenario has emerged, where control delivers performance improvement to communication. Internet is a prime example here, where the main goal is to communicate (involving a very large number of users and a very large scale heterogeneous network with all kinds of uncertainty), and control's role is (in both forward and feedback loops) to enable reliable communication under a 'fair' allocation of the available resources. The last couple of years have witnessed rapid progress in this arena, in both conceptualization and the development of fundamental results, where feedback control plays a central role. It is not at all unreasonable to anticipate for the not too distant future, a transfer of the basic knowledge that is currently being generated and the analytical and computational tools that are being developed, into new transport control protocols and router designs to replace the ones currently in use on the Internet.

This plenary talk will provide an overview of this rapidly advancing field, where control is used to better communication rather than the other way around. To put this in perspective, the talk will also dwell briefly on the former class above, which is still rich in enticing but challenging problems for the decision and control community.

Tamer Basar was born in Istanbul, Turkey, on January 19, 1946. He received B.S.E.E. degree from Robert College, Istanbul, in 1969, and M.S., M.Phil, and Ph.D. degrees in engineering and applied science from Yale University, in 1970, 1971 and 1972, respectively. After stints at Harvard University, Marmara Research Institute (Gebze, Turkey), and Bogaziçi University (Istanbul), he joined the University of Illinois at Urbana-Champaign in 1981, where he is currently the Fredric G. and Elizabeth H. Nearing Professor of Electrical and Computer Engineering, and Research Professor at the Coordinated Science Laboratory. He has spent sabbatical years at Twente University of Technology (the Netherlands; 1978-79), and INRIA (France; 1987-88, 1994-95).

Dr. Basar has authored or co-authored over 150 journal articles and book chapters, as well as numerous conference publications in the general areas of optimal, robust, and adaptive control; large-scale and decentralized systems and control; dynamic games; stochastic control; estimation theory;

stochastic processes; information theory; and mathematical economics. He is co-author of the text Dynamic Noncooperative Game Theory (Academic Press, 1982; second edition, 1995; latest edition in SIAM Series in Classics in Applied Mathematics, 1999), editor of the volume Dynamic Games and Applications in Economics (Springer-Verlag, 1986), co-editor of Differential Games and Applications (Springer-Verlag, 1988), co-editor of Advances in Dynamic Games and Applications (Birkhäuser, 1994), co-author of the text H-infinity Optimal Control and Related Minimax Design Problems (Birkhäuser, 1991; second edition, 1995), and Editor of the centennial volume Control Theory: Twenty-Five Seminal Papers (1932-1981) (IEEE Press, 2001). His current research interests are robust nonlinear and adaptive control; routing, pricing, and congestion control; flow control on communication networks; control over wireless and wired networks; mobile computing; risk-sensitive estimation and control; and robust identification.

Tamer Basar is a member of the National Academy of Engineering (of the USA), and also carries memberships in several scientific organizations, among which are SIAM, SEDC (Society for Economic Dynamics and Control), ISDG (International Society of Dynamic Games), GTS (Game Theory Society), AMS (American Mathematical Society), European Academy of Sciences, and IEEE (Institute of Electrical and Electronics Engineers). He was elected a Fellow of IEEE in 1983, and has served its Control Systems Society in various capacities, among which are: Past President (2001), President (2000), President-Elect (1999), Vice-President for Financial Affairs (1998), Vice-President for Publications (1997), the Editor for Technical Notes and Correspondence for its Transactions on Automatic Control (1992-1994), and as the general chairman (1992) and program chairman (1989) of its major conference (Conference on Decision and Control). He has also been active in IFAC, in the organization of several workshops and symposia, and more recently (since 1992) as Editor and Deputy Editor-in-Chief of Automatica, and vice-chair of its editorial board. During the period 1990-1994, he was the President of the International Society of Dynamic Games (ISDG), and is currently the Managing Editor of the Annals of ISDG (published by Birkhäuser), the Series Editor of Systems & Control: Foundations and Applications (published by Birkhäuser), and Honorary Editor of Applied and Computational Mathematics. He is also associate editor of Systems and Control Letters, and is on the editorial and advisory boards of a number of other international journals. Among some of the recent honors and awards he has received are: Election to the National Academy of Engineering (of the USA) (2000), IEEE Millennium Medal (2000), Nearing Distinguished Professorship at the University of Illinois at Urbana-Champaign (1998), Axelby Outstanding Paper Award (1995) and Distinguished Member Award (1993) of the IEEE Control Systems Society, and Meda of Science of Turkey (1993).

### **BODE LECTURE**

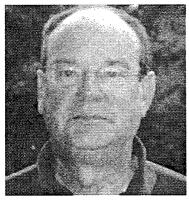
### **Challenges of Nonlinear Identification**

# Lennart Ljung Department of Electrical Engineering Linköping University

Identification of non-linear systems is an important problem in many applications. The topic is substantially richer than linear system identification. One reason for this is of course that the problem is significantly more difficult, but also that it has engaged several different research communities. With origins in statistical non-linear and non-parametric regression theory, areas like neural networks and learning theory can now be seen as research fields in their own right. In addition to the control field, many areas like artificial intelligence, pattern recognition, signal processing, oceanography, geology, etc, have developed their own approaches to the problem. This has lead to a very substantial literature on the topic.

This talk will not attempt to give any survey of all approaches. It will focus on some core features of the problem which represent the basic challenges. The foremost problem is the inherent lack of data support to build complex models. A black box model with \$n\$ explaining variables (regressors) can be seen as a surface in \$R^{n+1}\$. Even for moderately large \$n\$, this is a huge space to fill with observations. The remedy will be to assume or look for sub-structures in the model/data,linearity in certain directions etc. For control applications it is natural to complement the data support with structures based on physical insights, "grey-box models". Interfacing physical modeling tools with identification techniques is thus important. Grey-box models, on other hand, typically lead to minimization problem with many local minima. This is another challenge, which possibly can be dealt with using modern computer algebra and optimization techniques.

Lennart Ljung received the MSc degree in Engineering Physics in 1970 and the PhD degree in Automatic Control in 1974 both from Lund Institute of Technology. Since 1976 he is Professor of the chair of Automatic Control In Linkoping, Sweden, and is currently Director of the Competence Center "Information Systems for Industrial Control and Supervision" (ISIS). He has also held visiting positions at Stanford and MIT. His research interests have focused on all aspects of system identification, and he has written many papers and several books. He is also the author of the Matlab System Identification Toolbox. Moreover, he has been involved as chairman and committee member in numerous national and international research organizations. He was IFAC vice President 1987-1993, and is currently chairman of the Engineering



Section of the Swedish Royal Academy of Sciences. He is an IEEE Fellow and an IFAC Advisor as well as a member of the Royal Swedish Academy of Sciences (KVA), a member of the Royal Swedish Academy of Engineering Sciences (IVA), and an Honorary Member of the Hungarian Academy of Engineering. In 1978 and in 1993 he received the Automatica Prize paper award, and in 1979 the George Axelby Outstanding Paper Award. He has received honorary doctorates from the Baltic State Technical University in St Petersburg, and from Uppsala University in Sweden. In 2002 he received the Quazza Medal from IFAC.

### Wednesday Keynote in Nanotechnology

### NANOSCALE SCIENCE AND ENGINEERING AT NSF

# Kishan Baheti U.S. National Science Foundation

The emerging fields of nanoscience and nanoengineering are leading to unprecedented understanding and control over the fundamental building blocks of all physical things. The scientists and engineers are working at the atomic, molecular and supramolecular levels, in the length scale of approximately 1-100 nm range, in order to understand and create materials, devices and systems with fundamentally new properties and functions because of their small structure. Recently, the United States Congress has passed H. R. 766: "Nanotechnology R&D Act of 2003" to significantly increase government funding in this emerging area. The presentation will describe interdisciplinary activities supported by the National Science Foundation for collaborative research and education in nanoscale science and engineering.



Kishan Baheti received the B.E. and M.E. in Electrical Engineering in India from VRCE Nagpur, and from BITS Pilani, respectively. In 1970, he came to USA and received M.S. in Information and Computer Science from University of Oklahoma and Ph.D. in Electrical Engineering from Oregon State University. In 1976, Dr. Baheti joined the Control Engineering Laboratory of GE Corporate Research and Development Center in Schenectady, NY, His work focused on advanced multivariable control for jet engines, computer- aided control system design, vision-based robots for precision welding, model-based fault identification and parallel implementation of Kalman filters. Dr. Baheti and his colleagues received IR-100 award for robotic welding vision system. In 1989, Dr. Baheti joined NSF as a Program Director in the Division of Electrical and Communications Systems. He has been instrumental in the development of NSF initiatives on "Combined Research and Curriculum Development", "Semiconductor Manufacturing", and NSF/EPRI Initiative on "Intelligent Control". His contributions include the development of NSF Initiative on "Research Experience for Teachers" to involve middle and high school teachers in engineering research that can be transferred to pre-college classrooms. He has served as associate editor for IEEE Transactions on Automatic Control, member of the Control Systems Board of Governors, chair for Public Information Committee, and awards chair for the American Automatic Control Council (AACC). He received "Distinguished Member Award" from the IEEE Control Systems Society and was elected a Fellow of IEEE.

### Wednesday MEMS Keynote- Control Issues for MEMS

Dr. Janusz Bryzek, Dr. Eric Abbott, Anthony Flannery, Mitch Novack, David Cagle, Dr. Jacek Maitan Transparent Networks, BN Ventures, Honeywell, Agile Microsystems

MEMS (MicroElectroMechanical Systems) technology defines a broad range of mechanical integrated circuits. Over the last 10 years the sophistication level of MEMS devices increased dramatically, including integration of on-chip actuators and control electronics in devices ranging from ink jet printing heads, servo controlled gyro sensors, HDTV display engines and photonic switches.

This paper discusses control issues for MEMS devices, starting with an evolution of MEMS technology and increasing demand for control technology. A case study is presented outlining control issues in the high port count (1024x1024) photonic crossconnect. In this application, MEMS mirrors are controlled in a closed loop to deliver the low optical connection insertion loss and a high resistance to vibration. To close the control loop, extraction of reduced DOF 3D mirror models from finite element mechanical model is shown to be a very effective approach in



predicting and optimizing dynamic performance of the nonlinear mirror drive Another discussed control issue is time efficient calibration of the million optical connection points.

As the sophistication level of MEMS systems increases, the demand for control is expected to increase as well. It is becoming important that control experts start getting involved early in the design phase, so the development path of advanced MEMS systems and subsystems can be accelerated.

Dr. Bryzek is considered as one of the pioneers of the MEMS industry. He got involved in the development of MEMS pressure sensors in Poland in early 1970, working on technology transfer from Honeywell. In 1979 he joined Foxboro ICT, the first Silicon Valley MEMS sensor spinout from Fairchild Semiconductor. Between 1982 and 2003 Bryzek cofounded six Silicon Valley MEMS companies, all introducing products based on the cutting edge technology: Sensym, ICSensors, NovaSensor, Intelligent MicroSensor Technology, Transparent Networks and BN Ventures.

One of his successful developments was the world's first disposable blood pressure sensor in 1981, currently shipping 20 million units/year. One of his successful marketing efforts was the development of worldwide MEMS market awareness program lunched from NovaSensor in partnership with RGA in 1986, resulting in MEMS coverage by not only the majority of trade publications, but business and financial media as well.

Bryzek has published over 200 papers, wrote sections of 3 books, chaired many international conferences and co-authored 30 patents. Bryzek was actively involved in the MEMS standardization effort, including Disposable Blood Pressure Transducers released by AAMI in 1984 and Smart transducer Interface IEEE-1451 released as several sub-standards in 1990s. In 1994 he was awarded the Lifetime Achievement Award by Sensors Magazine for the achievements in MEMS field.

Dr. Bryzek got his MSEE in 1970 and Ph.D. in 1978 from Warsaw Technical University. He completed the executive management program at Stanford University in 1987.

Dr. Bryzek is on the Advisory Boards of Chip Scale Magazine and investment bank Via Inc. Since 2000, he has been involved in performing the startup companies due diligence for VC firms, USVP and Benchmark Capital.

### IEEE CONFERENCE ON DECISION AND CONTROL PAST AND PRESENT

The CDC grew out of the former Symposium on Adaptive Processes, to become the premier conference in the field that it istoday. Early on it was associated with the Joint Automatic Control Conference (JACC - now called the ACC) and later the National Electronics Conference (NEC). Below is the complete list of past CDCs with titles, chairs and locations. In the listing, GC denotes General Chair, PC stands for Program Chair, and SC is Symposium Chair. The proceedings of all past conferences can be found at the IEEE Library, 345 47th Street, New York, NY 10017.

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DISCRETE ADAPTIVE PROCESSES - SYMPOSIUM
AND PANEL DISCUSSION (IEEE); part of 3rd JACC
GC: J. Sklansky
New York University, New York City, NY, 29 June 1962
SYMPOSIUM ON ADAPTIVE PROCESSES; part of NEC
GC: L. Kanal
McCormick Place, Chicago, IL, 28-29 October 1963
SYMPOSIUM ON ADAPTIVE PROCESSES; part of NEC
GC: F. J. Mullin
McCormick Place, Chicago, IL, 19-21 October 1964
SYMPOSIUM ON ADAPTIVE PROCESSES: part of NEC
GC: E. C. Jones, Jr., PC: G. Brown
McCormick Place, Chicago, IL, 25-27 October 1965
SYMPOSIUM ON ADAPTIVE PROCESSES; part of NEC
GC: F. N. Bailey, PC: J. C. Hancock
McComick Place, Chicago, IL, 3-5 October 1966
SYMPOSIUM ON ADAPTIVE PROCESSES; part of NEC
GC: F. M. Waltz, PC: P. E. Mayes
International Amphitheater, Chicago, IL, 23-25 October 1967
IEEE SYMPOSIUM ON ADAPTIVE PROCESSES
GC. PC: J. M. Mendel
UCLA, Los Angeles, CA, 16-18 December 1968
IEEE SYMPOSIUM ON ADAPTIVE PROCESSES
GC: J. B. Lewis, PC: G. J. McMurty
Pennsylvania State University, PA; 17-19 November 1969
1970 SYMPOSIUM ON ADAPTIVE PROCESSES (9th)
DECISION AND CONTROL
GC, PC: D. J. Lainiotis
University of Texas at Austin, Austin, TX, 7-9 December 1970
1971 IEEE CONFERENCE ON DECISION AND CONTROL
including the 10th SYMPOSIUM ON
ADAPTIVE PROCESSES
GC: J. T. Tou, PC: S. K. Mitter, SC: J. M. Mendel
Americana Hotel, Miami Beach, FL, 15-17 December 1971
1972 IEEE CONFERENCE ON DECISION AND CONTROL
including the 11th SYMPOSIUM ON
ADAPTIVE PROCESSES
GC: J. M. Mendel, PC: Y. C. Ho, SC: G. N. Saridis
Fontainebleau Motor Hotel
New Orleans, LA; 13-15 December 1972
1973 IEEE CONFERENCE ON DECISION AND CONTROL
including the 12th SYMPOSIUM ON
ADAPTIVE PROCESSES
GC: J. S. Meditch, PC: D. G. Luenberger, SC: L. A. Gerhardt
Sheraton-Harbor Island Hotel, San Diego, CA;
5-7 December 1973
1974 IEEE CONFERENCE ON DECISION AND CONTROL
including the 13th SYMPOSIUM ON ADAPTIVE
PROCESSES
GC: Elliot Axelband, PC: Stephen Kahne, SC: David P.
Lindorff
Del Webb's Towne House, Phoenix, AZ; 20-22 November
1975 IEEE CONFERENCE ON DECISION AND CONTROL
including the 14th SYMPOSIUM ON ADAPTIVE
PROCESSES
GC: J. B. Cruz, Jr., PC: J. B. Pearson, SC: G. Stein
Hyatt Regency Houston, Houston, TX, 10-12 December 1975
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1976 IEEE CONFERENCE ON DECISION AND CONTROL
including the 15th SYMPOSIUM ON ADAPTIVE
PROCESSES
GC: M. Athans, PC: E. R. Barnes, SC: T. Pavlidis
Sheraton-Sand Key Hotel, Clearwater, FL, 1-3 December
1977 IEEE CONFERENCE ON DECISION AND CONTROL
including the 16th SYMPOSIUM ON ADAPTIVE
PROCESSES
GC: K. S. Fu, PC: H. Sorenson, SC: T. Pavlidis
Fairmont Hotel, New Orleans, LA, 7-9 December 1977
1978 IEEE CONFERENCE ON DECISION AND CONTROL
including the 17th SYMPOSIUM ON ADAPTIVE
PROCESSES
GC: Robert E. Larson, PC: Alan S. Willsky, SC:
Jerry M. Mendel
Islandia Hyatt House Hotel, San Diego, CA, 10-12 January
18th IEEE CONFERENCE ON DECISION AND CONTROL
including the SYMPOSIUM ON ADAPTIVE PROCESSES
GC: Stephen Kahne
PC: Alexander H. Levis, SC: Yaakov Bar-Shalom
Galt Ocean Mile Hotel, Ft. Lauderdale, FL,
12-14 December 1979
19th IEEE CONFERENCE ON DECISION AND CONTROL
including the SYMPOSIUM ON ADAPTIVE PROCESSES
GC: Pierre R. Belanger
PC: David L. Kleinman, SC: Richard V. Monopoli
The Regent Hotel, Albuquerque, NM; 10-12 December 1980
20th IEEE CONFERENCE ON DECISION AND CONTROL
including the SYMPOSIUM ON ADAPTIVE PROCESSES
GC: William R. Perkins
PC: Abraham H. Haddad, SC: Kumpati S. Narendra
Vacation Village Hotel, San Diego, CA; 16-18 December
21st IEEE CONFERENCE ON DECISION AND CONTROL
GC: Alexander H. Levis, PC: William S. Levine
Holiday Inn - International Drive
Orlando, FL, 8-10 December 1982
22nd IEEE CONFERENCE ON DECISION AND CONTROL
GC: James L. Melsa, PC: Steven I. Marcus
Marriott Hotel, San Antonio, TX, 14-16 December 1983
23rd IEEE CONFERENCE ON DECISION AND CONTROL
GC: Abraham H. Haddad, PC: Michael P. Polis
Las Vegas Hilton, Las Vegas, NV, 12-14 December 1984
24th IEEE CONFERENCE ON DECISION AND CONTROL
GC: Gene F. Franklin, PC: Anthony N. Michel
Bonaventure Hotel & Spa
Ft. Lauderdale, FL, 11-13 December 1985
25th IEEE CONFERENCE ON DECISION AND CONTROL
GC: Anthony Ephremides, co-GC: Spyros Tzafestas
PC: H. Vincent Poor
Atheneum Intercontinental Hotel
Athens, GREECE; 10-12 December 1986
26th IEEE CONFERENCE ON DECISION AND CONTROL
GC: William S. Levine, PC: John Baillieul
Westin Century-Plaza Hotel
Los Angeles, CA, 9-11 December 1987
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GC: Michael P. Polis, PC: William E. Schmitendorf Hyatt Regency Austin on Town Lake Austin, TX, 7-9 December 1988 28th IEEE CONFERENCE ON DECISION AND CONTROL GC: Leonard Shaw, PC: Tamer Basar Hyatt Regency Tampa Hotel, Tampa, FL, 13-15 December 29th IEEE CONFERENCE ON DECISION AND CONTROL GC: Charles J. Herget, PC: Raymond A. DeCarlo Hilton Hawaiian Village, Honolulu, HI, 5-7 December 1990 30th IEEE CONFERENCE ON DECISION AND CONTROL GC: Derek Atherton, PC: Panos J. Antsaklis Metropole Hotel, Brighton, ENGLAND, 11-13 December 1991 31st IEEE CONFERENCE ON DECISION AND CONTROL GC: Tamer Baser, PC: Sergio Verdu Westin La Paloma, Tucson, AZ, 16-18 December 1992 32nd IEEE CONFERENCE ON DECISION AND CONTROL GC: Raymond A. DeCarlo, PC: Peter Ramadge Marriott Rivercenter, San Antonio, TX, 15-17 December 1993 33rd IEEE CONFERENCE ON DECISION AND CONTROL GC: Michael K. Masten, PC: N. Harris McClamroch Buena Vista Palace, Lake Buena Vista, FL, 14-16 December 1994 34th IEEE CONFERENCE ON DECISION AND CONTROL GC: Panos J. Antsaklis, PC: Edward W. Kamen

New Orleans Hilton Riverside

New Orleans, LA, 13-15 December 1995

27th IEEE CONFERENCE ON DECISION AND CONTROL

35th IEEE CONFERENCE ON DECISION AND CONTROL GC: Hidenori Kimura Co-PCs: Katsuhisa Furuta, J. Douglas Birdwell Portopia Hotel and International Conference Center Kobe, Japan, 11-13 December 1996 36th IEEE CONFERENCE ON DECISION AND CONTROL GC: Anthony Michel, PC: Theodore E. Djaferis Hyatt Regency San Diego, San Diego, CA, 10-12 December 37th IEEE CONFERENCE ON DECISION AND CONTROL GC: J. Douglas Birdwell, PC: David Castanon Hyatt Regency Westshore, Tampa FL, 16-18 December 1998 38th IEEE CONFERENCE ON DECISION AND CONTROL GC: Edward W. Kamen, PC: Christos Cassandras Crowne Plaza Hotel and Resort, Phoenix, AZ, 7-10 December 1999 39th IEEE CONFERENCE ON DECISION AND CONTROL GC: Robert R. Bitmead, PC: Cheryl B. Schrader Sydney Convention and Exhibition Centre Sydney, NSW Australia; 12-15 December 2000 40th IEEE CONFERENCE ON DECISION AND CONTROL GC: Theodore E. Diaferis, PC: Kevin M. Passino Hyatt Regency Grand Cypress, Orlando, FL, 4-7 December 41st IEEE CONFERENCE ON DECISION AND CONTROL GC: Ümit Özgüner, PC: Kenneth Loparo The Venetian Hotel, Las Vegas, NV, 10-13 December 2002 42nd IEEE CONFERENCE ON DECISION AND CONTROL GC: Frank K. Lewis, PC: Chaouki Abdallah The Hyatt Regency Resort & Spa Maui, Hawaii, 9-12 December 2003

## **TECHNICAL PROGRAM**

### 42<sup>nd</sup> IEEE CONFERENCE ONDECISION AND CONTROL

9-12 December 2003 The Hyatt Regency Resort & Spa - Maui, Hawaii, USA •

# CDC03 Technical Program Tuesday December 9, 2003

Workshop	Spats Trattoria	TuAW	16:00	High School Students Workshop						
Poster/Inter- active (PI)	Grand Promenade			SIAM Poster Papers I			SIAM Poster Papers II		SIAM Poster Papers III	
Track 14	Guest Grand Room 450 Room 451 Promenade			Fault Detection			Predictive Fault Sontrol for Detection Linear and Systems Accommodation I		Fault Detection and Accommo- dation II	uite 4 Isor Sessio
Track 13	Guest Room 450			System Theoretic Methods in Quantum Control			Filtering I Predictive Control for Linear Systems		Filtering II Predictive Control for Nonlinear Systems	TuES2: 19:00-20:20 Maui Suite 4 National Instruments Industry Sponsor Session
Track 12	Maui Suite 5			Fittering and Estimation						2: 19:00-20 ruments In
Track 11	Guest Guest Room 350 Room 351			Distributed Output Parameter Feedback Systems I I	sms		Distributed Output Parameter Feedback Systems II II		Discrete- time Nonlinear Systems	TuES lational Inst
Track 10	Guest Room 350	шоо		Distributed Parameter Systems I	TuNPL: 12:00-14:00 Sunset Terrace Plenary Panel: International Funding Thrusts and Mechanisms		Distributed Parameter Systems II		Optimal Water Robust Distributed Discrete-Control III Vehicles Estimation Parameter time Systems Nonlinear III Systems	2
Track 9	Maui Suite Maui Suite 3 4	TuDPL: 08:00-09:00 Monarchy Ballroom Plenary Talk: Vladimir Kucera	1:20	Robust Control I	TuNPL: 12:00-14:00 Sunset Terrace 8: International Funding Thrusts and	6:20	Robust Control II	8:40	Robust Estimation	
Track 8	Maui Suite 3	11: 08:00-09:00 Monarchy Ball Plenary Talk: Vladimir Kucera	TuA: 09:20 - 11:20	Electro- mechani- cal Control Systems	00-14:00 St	TuM: 14:20 - 16:20	Emerging Control Applica- tions	TuP: 16:40 18:40	Water Vehicles	
Track 7	Regency Board- room	DPL: 08:00 Plenary	Tu/	Optimal Control I	uNPL: 12:( : Internation	¶n_	Optimal Control II	TuT		:
Track 6	Maui Suite Maui Suite 1	ᆵ		Stabiliza- tion of Networked Control Systems	T nary Panel		Networked Control Systems and Packet Losses		Networked Control Systems with Limited Communi- cation	ouite 3 Session
Track 5	Maui Suite 1			Hybrid Systems I	Be		Hybrid		Hybrid Systems III	TuES1: 19:00-20:20 Maui Suite 3 Honevwell Industry Sponsor Session
Track 4	Regency C			Linear Systems					Linear Systems III	11: 19:00-20
Track 3	Regency B			Wireless Networks: Adaptation, Estimation, and Control			Control of Linear Networks I Systems		Control of Networks II	TuES
Track 2	Regency A			Control- lability, Observ- ability and Output Feedback Design of Nonlinear Systems			Coopera- Dynamics Control of tive and Networks Control Control of for Net- Nonlinear worked Systems		Coopera- Nonlinear Control of two two Control of Regulation II Multiple and Auto- Stabiliza- nomous tion Agents	
Track 1	Monarchy Ballroom			Coopera- tive Control for Net- worked UAV I			Coopera- tive Control for Net- worked UAV II		Coopera- tive Control of II Multiple Auto- nomous Agents	

# CDC03 Technical Program Wednesday December 10, 2003

Track 1	Frack 1 Track 2 Track 3 Track	Track 3	~	Track 5	Track 6	Track 7	Track 8	Track 9	Track 10	Track 11	Track 12	Track 13	Track 14	Poster/Inter- active (PI)	4 Track 5 Track 6 Track 7 Track 8 Track 9 Track 10 Track 11 Track 12 Track 13 Track 14 PosteriInter Workshop
onarchy	Monarchy Regency Regercy Regeralinoom A B C	Regency B	_ ⊆	ncy Maui Suite Maui Suite Board- 3 4 Room 350 Room 351 5 Room 450	Maui Suite 2	Regency Board-	Maui Suite 3	Maui Suite 4	Guest Room 350	Guest Room 351	Maui Suite 5	Guest Room 450	Guest Room 451	Li Suite     Guest     Guest     Grand     Spats       4     Room 350 Room 351     5     Room 450 Room 451 Promenade     Trattoria	Spats Trattoria
					7										
						WeDPL	WeDPL: 08:00-09:00 Monarchy Ballroom	Monarchy	Ballroom						
						7	Plenary Lark: Katsubita Fucita	atsuhita Fu	ruta						

	WeAW 09:20- 13:20 Women in Control Workshop
	SIAM Poster papers IV
	Fault Detection and Accommodation III
	Random- Fault ized Detection Algorithms and for Accommo-Analysis dation iil and Synthesis Control Systems
	Chaotic Systems
	Computa- tional and Numerical Issues in Systems and Control
	Linear Distributed Computa- Chaotic Random- Fault Robust Parameter Itonal and Systems Ized Detection Control Systems Numerical Issues in Systems Analysis Addition III and Control Control Systems Systems Systems
1:20	Linear Robust Control
WeA: 09:20 - 11:20	Automo- tive and Vehicle Control
	Optimal Control IV
	avioral Stability of Adaptive Optimal Automostem Hybrid Output Control IV tive and Systems Feedback Systems Control
	Stability of Hybrid Systems
	Behavioral System theory
	Communi- cation Networks: Schedu- ling and Quality of Service
	Coopera- Trends in Communi- Behaviora tive Advanced cation System Control Nonlinear Networks: theory Scheduling and Quality of Service
	Coopera- tive Control

WeNPL: 12:00-14:00 Sunset Terrace Plenary Panel: History of Control

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	Linear	Systems	and	Control	Education						
	Fault-	olerant	ystems								
	Statistical	Learning	Methods	2	Optimiza-	tion,	Control	and	System	Identifica-	tion
	Control of	Nonlinear	Systems								
	Computa-	tional	Method for	System	Modeling Properties Optimiza-						
	Control	and	Control-	Oriented	Modeling	.⊆	Distributed	Compus-	tion and	Flow	
6:20	H-infinity	Control	Adaptive Vehicle								
WeM: 14:20- 16:20	Automo-	tive	Vehicle	Control							
We	Optimal	Control V									
	Applica-	tions of	Adaptive	Control							
	Optimal	Timing	Control of		Systems						
	Nanotech- Optimal	nology:	Control	Needs and Hybrid	Related	Perspec-	tives (I)				
	Pricing	and	ptimiza-	tion of	Communi-	cation	Networks				
	Multiple Nonlinear	Systems I									
	Multiple	Vehicle	Coord	inated	Control						

	ontro	ation:	_	Interactive	-sip	Jary	Session
	<u>გ</u>	Educe	of	Intera		ciplinary	Ses
	Sliding	Mode Education:	Control	Linear	System		
	Statistical	Learning	Methods				
	Markov Structured Compu- Non- Statistical	tational Holonomic Learning	Distributed Methods   Systems   Methods   Control of	and	Robotics		
WeP: 16:40-18:40	Compu-	tational	Methods				
	Structured	and	Distributed	Control			
	Markov	Processes					
	Auto-	motive	and	Aerospace	Optimal Systems		
	MeN	Trends on	Geometric	and	Optimal	Control I	
	Adaptive	Control Trends on motive Processes	Applica- Geometric	tions			
	anotech- Discrete- Adaptive New	Event	Control Systems				
	Nanotech-	nology:	Control	Needs and	Related	Perspec-	tives (II)
	Stochastic	Network	Models				
	Itiple Nonlinear Sto	Systems II					
	Multiple	Agent	Systems				

WeES1: 19:00-20:30 Regency A	WeES2: 19:00-20:20 Maui Suite 4	WeES3: 19:00-20:30 Monarchy Ballroom
Xerox Industry Sponsor Session	The MathWorks Industry Sponsor Session	Keynote Talk: J. Bryzek, Control issues of MEMS

# CDC03 Technical Program Thursday December 11, 2003

rack 1	Track 2	Track 3	Track 4	Track 5	Track 6	Track 7	Track 8	Track 9	Track 10	Track 11	Track 5 Track 6 Track 7 Track 8 Track 9 Track 10 Track 11 Track 12 Track 13 Track 14 F	Track 13	Track 14	4 Poster/Inter-
onarchy	Regency /	4 Regency E	3 Regency C	Maui Suite	Maui Suite	Regency	Maui Suite	Maui Suite	Guest	Guest	Maui Suite Maui Suite Regency Maui Suite Maui Suite Guest Guest Maui Suite Guest Guest	Guest		Grand
		·	,	-	2	Boardroom	3	4	Room 350	4   Room 350   Room 351	S	Room 450	Room 450 Room 451 Promenade	Promenade
					f	<b>DPL</b> : 08:00-	-09:00 Mona	ThDPL: 08:00-09:00 Monarchy Ballroom	ε					
						Plenary	Plenary Talk: Tamer Basar	Basar						

	Sliding Strategies Mode for Human- Control I Automaton Resource Entity Deploy-
	New Mechanical Language- Constrain- Control Identifica- Polynomial SI Trends on Systems I Based ed Control I Applica- tion Geometric Descriptions of tions of tions of tions of Control II Applications of Control II Control II Tasks
	Identifica- tion
	Control Applica- tions I
	Constrained Control I
.20	Language- Based e Descrip- tions of Multi-Modal Control
ThA: 09:20-11:20	Mechanical Systems I
F	Direct New Mechanical Adaptive Trends on Systems I Control Geometric and Optimal Control II
	Direct Adaptive Control
	Languages , Logic and Discrete- Events Systems
	Paramet prograr ming ii Contro Systen Design
	Fundamental Limits on Communication and Control
	Graph Nonlinear Fundamen- Parametr Theoretic Systems III tal Limits program fethods in ming in Communi- Control
	Graph Theoretic Methods in Cooperative Control

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	Control Applica- tions
	Sliding Mode Control II
	Control of Fime Delay Systems I
	Identifica- Control of Sliding tion Time Delay Mode Algorithms Systems I Control II
	Control Applica- tions II
	Constrained Control
00	Power
ThM: 14:00-16:00	Mechanical Systems II
ThA	Optimiza- N tion Algorithms
	Modeling and Adaptation
	Petri Nets Modeling Optimiza- Mechanical Power Constrain- Control Identifica- Control of Siding Control and tion Systems II Systems ed Control Applica- tion Time Delay Mode Applica- Adaptation Algorithms Algorithms Systems II Algorithms Systems II tions II Algorithms Systems Control II tions
	Model Predictive Control
	Stability of Communi- cation Networks
	Nonlinear Stabilif Systems IV Comm catic Netwo
	Formation Control

ThNPL: 12:00-13:40 Monarchy Ballroom Plenary Panel: CSS Presidents

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	Advance in Plasm Control i Tokamak
	Advances in High Order Sliding Modes
	Control of Time Delay Systems II
	Identifica- tion and Estimation
	Stability of Robust Optimiza- Mechanical Learning in Constrain- Control Identifica- Control of Advances Advances Nonlinear Adaptive tion Systems Hooks Control Methods Applica- tions III Estimation Systems Algorithms Agorithms Agorithms Agorithms
	Constrain- ed Nonlinear Systems
120	Optimiza- Mechanical Learning in Cotion Systems III Control Nethods and Agorithms
ThP: 16:20-18:20	Mechanical Systems III
F	Robust Optimiza- Adaptive tion Control Methods and Algorithms
	Stability of Robust Nonlinear Adaptive Switched Control Systems
	Stability of Nonlinear Switched Systems
	Optimiza- tion of Stochastic Systems
	Control of Communi- cation Systems
	Coopera- Nonlinear Control of Optimiza- Stative and Systems Communition of No Operative Theory and Systems Systems Systems Applications  Cooperative Theory and Systems Systems Systems Applications
	Coopera- tive and Nonco- operative Systems under Constrain- ed Informa- tion

# CDC03 Technical Program Friday December 12, 2003

Poster/Inter- active (PI)	Grand		Discrete	Events and	Learning	)							
4 Track 5 Track 6 Track 7 Track 8 Track 9 Track 10 Track 11 Track 12 Track 13 Track 14 Poster/Inter-	Guest Guest Grand Room 450 Room 451 Promenade		Control Computa- Uncertain Stability of ISS and	Systems  Time-delay Lyapunov  Events and	Approach- Learning	esin	Nonlinear	Systems		_			
Track 13	Guest Maui Suite Guest		Stability of	Time-delay	Systems I								
Track 12	Maui Suite 5		Uncertain	Systems								:	
Track 11	_ 00		Computa-	tional	Methods	and Linear	Inequalities						
Track 10	Guest Room 350			Education tional									
Track 9	Maui Suite 4		Aircraft	Control							4-		
Track 8	Maui Suite 3	FrA: 08:40-10:40	Systems	Theoretic	Tools for	Dynamic	Vision.						
Track 7	ui Suite Regency Maui Suit	F	Stability of Learning Estimation   Systems								•		
Track 6	Maui Suite 2		Learning	and	Systems Optimizing	Based on	Experience	Sample	Path	Approach-	es: From	PA to	MDPs
Track 5	Maui Suite 1		Stability of	Switched	Systems								
Track 4	Regency C		Process	Control									
Track 3	Regency B		Fuzzy	Systems									
Track 1 Track 2 Track 3 Track	Monarchy Regency A Regency B Regency C Maui Suite Maui Suite Regency Maui Suite Mui Suite Guest Ballroom 3 4 Room 350		Positive Nonlinear Fuzzy Pro	Systems V									
Track 1	Monarchy Ballroom		Positive	Poly-	nomials in	Control							

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narcny Ballroo	nart Liung
FIUFL: 11:00-12:00 Monarchy Ballroom	Bode Lecture: Lennart Ljung
10F	ď

	Stability of Nonlinear Systems
	Visual Missile and Control in Computa- System Stability of Stability of Servo Servo Aircraft Manufac- tional Identificatio Time-delay Nonlinear Control GNC turing Methods n Systems II Systems for Systems
	System Identificatio n
	Computa- tional Methods for Systems
	issile and Control in Aircraft Manufac- GNC turing
:40	Missile and Aircraft GNC
FrM: 12:40-14:40	_
F	Estimation II
	Systems   Systems   II
	Model Switched Stochastic
	Model 8
	Fuzzy Systems II
	Linear Nontinear Fuzzy latrix In- Systems VI Systems II qualities
	Linear Matrix In- equalities

	Geometric Methods for Nonlinear Systems	
	Addel         Switched         Stochastic         Nonlinear         Robotics         Motor         Manufac-         Stability         Uncertainty Time-Delay Geometric           duction         Systems II         Systems II         Estimation         Systems         Finance of Discrete-         1D         for for fine           simation         time         Systems         Systems         Systems         Systems	
	Uncertainty in System ID	
	Stability and Control of Discrete- time Systems	
	Motor Manufac- Stability Control turing and and Control Systems Finance of Discrete- time Systems	
00	Motor Control Systems	
FrP: 15:00-17:00	Robotics	
Ē	Nonlinear	
	Model Switched Stochastic Nonlinear duction Systems II Systems II Estimation and imation	
	Systems II	
	Model Reduction and Estimation	
	Network Control	
	Nonlinear Systems VII	
	LMI/LPV	

Systems III Discrete- trons of Event Estimation and Markov Apocesses  Systems III Discrete- trons of Systems Control Biomedical Systems Robotics Application and Markov Aprocesses	Modeling Switched Stochastic Applica- Systems III Discrete- tions of Systems Event Estimation and Systems and Markov Processes	Neural Networks Optimiza- tion	I
Systems III Discrete-forms of Systems Systems Systems Systems Systems and Markov Processes		Neural Networks Optimiza- tion	Neural Networks Optimiza- tion
Systems III Discrete Systems III Discrete Ever System and Ma Process		Neural Networks Optimiza- tion	Neural Networks Optimiza- tion
		Neural Networks Optimiza- tion	Neural Networks Optimiza- tion

TuDPL	Monarchy Ballroom	10:00	
Plenary Talk: Vladimir Kucera Chair: Lewis, Frank L.	Plenary Session Univ. of Texas at Arlington	Observer Design for Sampled-Data	
•	Offiv. of Texas at Affiligion	Approximate Discrete-Time Models Arcak, Murat	(I), 49 Rensselaer Pol. Inst.
08:00 Feedback Control: the Origins, the N	filestones and the Trands*	Nesic, Dragan	Melbourne Univ.
Kucera, Vladimir	Czech Tech. Univ.	10:20	Welbourne Offiv.
TuA01	Monarchy Ballroom	Observability Conditions for the Ser Non-Minimum Phase Nonlinear Sys	
Cooperative Control for	Invited Session	Isidori, Alberto	Washington Univ.
Networked Uninhabited		Marconi, Lorenzo	Univ. di Bologna
Autonomous Vehicles I		Serrani, Andrea	The Ohio State Univ.
Chair: Passino, Kevin	Ohio State Univ.	10:40	
Co-Chair: Sparks, Andrew G.	Air Force Res. Lab.	Nonlinear Dynamic Output Feedba	ck Stabilization of
Organizer: Passino, Kevin	Ohio State Univ.	Electrostatically-Actuated MEMS (I	
Organizer: Sparks, Andrew G.	Air Force Res. Lab.	Maithripala, D. H. S.	Texas Tech. Univ.
09:20		Berg, Jordan M.	Texas Tech. Univ.
Hybrid System Design for Formation		Dayawansa, Wijesuriya P.	Texas Tech. Univ.
Zelinski, Shannon Koo, T. John	NASA Ames Res. Center Vanderbilt Univ.	11:00	
Sastry, Shankar	Univ. of California at Berkeley	A Note on Multistability and Monoto	
* '	C Of Camorina at Dorkerey	Angeli, David	Univ. of Firenze
09:40 Cooperative Real-Time Search and	Task Allocation in LIAV Teams	Sontag, Eduardo D.	Rutgers Univ.
(I), 7	TUSK ANOCANON IN DAY TEAMS	TuA03	Regency B
Jin, Yan	Univ. of Cincinnati	Wireless Networks:	Invited Session
Minai, Ali A.	Univ. of Cincinnati	Adaptation, Estimation, and	marca cession
Polycarpou, Marios M.	Univ. of Cincinnati	Control	
10:00		Chair: Krishnamurthy, Vikram	Univ. of British Columbia
Distributed Algorithms for Dynamic F	Reassignment (I), 13	Co-Chair: Malhame, Roland	Ec. Pol. De Montreal
Castanon, David A.	Boston Univ.	P.	
Wu, Cynara	Alphatech, Inc.	Organizer: Krishnamurthy,	Univ. of Melbourne
10:20		Vikram	
Sensor Fusion for Target Track Mair		09:20	
Based on Bayesian Filtering Method		Control of Mobile Communications	
Tang, Zhijun	The Ohio State Univ.	Channels Via Stability Methods (I),	
Ozguner, Umit	Ohio State Univ.	Buche, Robert Kushner, Harold J.	NC State Univ. Brown Univ.
10:40		·	BIOWII OIIIV.
Multiple UAV Cooperative Search un		09:40 Minimum Distortion Transmission o	of Gaussian Sources Over
Limited Range Communication Cons Beard, Randal W.	Brigham Young Univ.	Fading Channels (I), 80	il Gaussian Sources Over
McLain, Timothy W.	Brigham Young Univ.	Kashyap, Akshay	Univ. of Illinois at Urbana-
11:00	angilam roung amir	,	Champaign.
Cooperative Control Via Task Load	Balancing for Networked	Basar, Tamer	Univ. of Illinois at Urbana-
Uninhabited Autonomous Vehicles (			Champaign
Finke, Jorge	The Ohio State Univ.	Srikant, Rayadurgam	Univ. of Illinois at Urbana-
Passino, Kevin	The Ohio State Univ.		Champaign
Sparks, Andrew G.	Air Force Res. Lab.	10:00	
		Adaptive Discrete Stochastic Appro	oximation Algorithms for
TuA02	Regency A	Spreading Code Optimization in DS Krishnamurthy, Vikram	S/CDMA (I), 86 Univ. of British Columbia
Controllability, Observability and Output Feedback Design	Invited Session	Wang, Xiaodong	Columbia Univ.
		Yin, George	Wayne State Univ.
of Nonlinear Systems Chair: Astolfi, Alessandro	Imperial Coll.		Traylie State Offiv.
Co-Chair: Lin, Wei	Case Western Res. Univ.	10:20 QoS Provisioning for Wireless Ad F	Hoc Data Networks (IV 92
Organizer: Astolfi, Alessandro	Imperial Coll.	Comaniciu, Cristina	Stevens Inst. of Tech.
Organizer: Lin, Wei	Case Western Res. Univ.	Poor, H. Vincent	Princeton Univ.
Organizer: Serrani, Andrea	The Ohio State Univ.	10:40	
09:20		Individual and Mass Behaviour in L	arge Population Stochastic
Output Feedback Stabilization of a C		Wireless Power Control Problems:	
High-Order Nonlinear Systems (I), 3		Equilibrium Solutions (I), 98	
YANG, BO	Case Western Res. Univ.	Huang, Minyi	Mcgill Univ.
Lin, Wei	Case Western Res. Univ.	Caines, Peter E.	McGill Univ.
09:40	Para Para a superior de la compansión de la	Malhame, Roland P.	Ec. Pol. de Montreal
Nonsmooth Output Feedback Stabil	zation and Tracking of a Class	11:00	
of Nonlinear Systems (I), 43 Qian, Chunjiang	The Univ. of Texas at San	Analysis of an AIMD Based Collision	on Avoidance Protocol in
Gian, Chunjiang	ne Univ. of Texas at San Antonio	Wireless Data Networks (I), 104	Iniv of Magnachusette Amberra
Lin, Wei	Case Western Res. Univ.		Jniv. of Massachusetts, Amherst Jniv. of Massachusetts, Amherst
	2222 170000 11100. Offit.	Gong, Wei-Bo	Univ. of Massachusetts at
			Amherst
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Chair: Olivi, Martine Co-Chair: Pacheco Martinez	INRIA CINVESTAV - IPN	Singularly Impulsive or Generalize Lyapunov and Asymptotic Stability Kablar, Natasa A.	y, 173 Lola Inst. Belgrade, Yugosla
Jaime	.,	Nabiai, Natasa A.	Lota mot. Doigrado, Tagodia
09:20		TuA06	Maui Suite
	ion of Non Proper Compensators:	Stabilization of Networked	Regular Sess
The MIMO Case, 110	,	Control Systems	
Pacheco Martínez, Jaime	CINVESTAV - IPN	Chair: Liberzon, Daniel	Univ. of Illinois at Urbar champa
Bonilla, Moises E.	CINVESTAV-IPN UMR CNRS 6597	Co-Chair: Elia, Nicola	lowa State Ur
Malabre, Michel	OWIR CINES 0397		1544 5146 51
09:40	untural Variations in Lincor	09:20 Control Over Bandlimited Commu	inication Channels: Limitations
Almost Rejection of Internal Str Systems, 116	ucturai variations iri Linear	Stabilizability, 176	meation Charmers. Emitations
Bonilla, Moises E.	CINVESTAV-IPN	Dasgupta, Soura	Univ. of lo
Pacheco Martinez, Jaime	CINVESTAV - IPN	09:40	
Malabre, Michel	UMR CNRS 6597	Stabilizing a Nonlinear System wi	th Limited Information Feedba
10:00		182	
Schur Parametrizations and Ba		Liberzon, Daniel	Univ. of Illinois at Urba
Discrete-Time Stable All-Pass		•	Champa
Olivi, Martine	INRIA CMA	10:00	
Marmorat, Jean-Paul Hanzon, Bernard	Vrije Univ. Amsterdam	A Note on Stabilization Via Comn	
Peeters, Ralf	Maastricht Univ.	Presence of Input Constraints, 18 De Persis, Claudio	Univ. di Ro
10:20		•	Silv. di A
	Based on a Frequency Criterion,	10:20 Stabilizability of SISO Control Sys	etems under Constraints of
127		Channel Capacities, 193	soms under Constraints Of
Garcia, Daniel	Ec. Pol. Federale de Lausanne	Tsumura, Koji	Univ. of To
Karimi, Alireza	Ec. Pol. Federale de Lausanne	Maciejowski, Jan M.	Univ. of Cambr
Longchamp, Roland	Ec. Pol. Federale de Lausanne	10:40	٠
10:40		Robust Stabilization of Linear Uni	certain Systems Via Quantize
Comparison of PID Control and		Feedback, 199	
Ren, Zhengyun	Shanghai Jiaotong Univ. Shanghai Univ. of Engineering Tech.	Fu, Minyue	Univ. of Newca
Zhang, Hong Shao, Huihe	Shanghai Jiao Tong Univ.	11:00	
	Changilal trace roing comm	Stabilization of Networked Contro	ol Systems Over a Sharing Lin
11:00 A Novel Method of PID Tuning	for Integrating Processes 139	Using ALOHA, 204	Univ. of Notre Da
Xu, Jianghua	Shanghai Jiao Tong Univ.	Zhang, Wenyi	Univ. of Notice Da
Shao, Huihe	Shanghai Jiao Tong Univ.	TuA07	Regency Boardro
	· ·	Optimal Control I	Regular Ses
			Univ. of Strathc
TuA05	Maui Suite 1	Chair: Grimble, Michael John	
Hybrid Systems I	Regular Session	Co-Chair: Pereira, Fernando	Porto Univ. Inst. For System
Hybrid Systems I Chair: Rowe, Camile	Regular Session Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo	Porto Univ. Inst. For System
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene	Regular Session	Co-Chair: Pereira, Fernando Lobo 09:20	Porto Univ. Inst. For System Robo
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20	Regular Session Univ. of Cambridge Univ. of California, Berkeley	Co-Chair: Pereira, Fernando Lobo 09:20 Employing the Algebraic Riccati I	Porto Univ. Inst. For System Rob
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Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise Eindhoven Univ. of Tech.	Co-Chair: Pereira, Fernando Lobo 09:20 Employing the Algebraic Riccati L Finite-Horizon LQ Problem, 210 Ferrante, Augusto	Porto Univ. Inst. For System Rob  Equation for the Solution of the  Univ. degli Studi di Pad
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Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estin Rowe, Camile Maciejowski, Jan M. 10:00	Regular Session Univ. of Cambridge Univ. of California, Berkeley  nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech.  ation for Hybrid Systems, 149 Univ. of Cambridge Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Employing the Algebraic Riccati Employing the Algebraic Riccati Employing the Algebraic Riccati Employed Fernante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadichen, Yue	Porto Univ. Inst. For System Robi  Equation for the Solution of the Univ. degli Studi di Pac Univ. degli Studi di Bolo Univ. degli Studi di Bolo s Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U  ratic Optimal Control, 221 Univ. of California at Los Ang
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems U	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. vation for Hybrid Systems, 149 Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F.	Porto Univ. Inst. For System Robin R
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Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems U Koutsoukos, Xenofon 10:20	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. aution for Hybrid Systems, 149 Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ.	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20	Porto Univ. Inst. For System Robe  Equation for the Solution of the  Univ. degli Studi di Pad Univ. degli Studi di Bolo Univ. degli Studi di Bolo s Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U Univ. degli Studi di U Univ. of California at Los Ang Univ. of California at Los Ang
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-De	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. ation for Hybrid Systems, 149 Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ.	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Re	Porto Univ. Inst. For System Robe  Equation for the Solution of the  Univ. degli Studi di Pad Univ. degli Studi di Bolo Univ. degli Studi di Bolo s Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U Univ. degli Studi di U Univ. of California at Los Ang Univ. of California at Los Ang
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Dalts Application to CPU Process	Regular Session Univ. of Cambridge Univ. of Callfornia, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. ation for Hybrid Systems, 149 Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ.	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227	Porto Univ. Inst. For Syster Rob  Equation for the Solution of the Univ. degli Studi di Pau Univ. degli Studi di Bole Univ. degli Studi di Bole S. Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U Univ. degli Studi di U Univ. of California at Los Ang
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-De	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. ation for Hybrid Systems, 149 Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ.	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John	Porto Univ. Inst. For System Robi  Equation for the Solution of the  Univ. degli Studi di Pad  Univ. degli Studi di Bolo  Univ. degli Studi di Bolo  S. Linear Implementation, 215  Univ. degli Studi di U  Univ. degli Studi di U  univ. degli Studi di U  Univ. of California at Los Ang  Univ. of California at Los Ang  Univ. of California at Los Ang  Ustricted Structure Optimal Con  Robi  Rob
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Da Its Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi	Regular Session Univ. of Cambridge Univ. of California, Berkeley  nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech.  vation for Hybrid Systems, 149 Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Nature (100 Algebraic Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadichen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40	Porto Univ. Inst. For System Rob  Equation for the Solution of the  Univ. degli Studi di Pau Univ. degli Studi di Bole Univ. degli Studi di Bole S Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U Univ. degli Studi di U Univ. of California at Los Ang Univ. of Texas at A Univ. of California at Los Ang estricted Structure Optimal Cole  Univ. of Strathe
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems U Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Da Its Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi 10:40	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. vation for Hybrid Systems, 149 Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Employing the Algebraic Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadichen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40 Nondegenerate Necessary Conditional Riccati Employing the Riccati Riccati Employing the	Porto Univ. Inst. For System Rob Equation for the Solution of the Univ. degli Studi di Pau Univ. degli Studi di Bole Univ. degli Studi di Bole S Linear Implementation, 215 Univ. degli Studi di L Univ. degli Studi di L Univ. degli Studi di L Univ. of California at Los Ang Univ. of Texas at A Univ. of California at Los Ang Estricted Structure Optimal Con Univ. of Strathe
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems U Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Da Its Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi 10:40	Regular Session Univ. of Cambridge Univ. of California, Berkeley  nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech.  vation for Hybrid Systems, 149 Univ. of Cambridge	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati & Finite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadic Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40 Nondegenerate Necessary Cond Control Problems with State Con	Porto Univ. Inst. For Syster Rob  Equation for the Solution of the Univ. degli Studi di Par Univ. degli Studi di Bole Univ. degli Studi di Bole Si Linear Implementation, 215 Univ. degli Studi di L Univ. degli Studi di L Univ. degli Studi di L Univ. of California at Los Ang Univ. of Texas at A Univ. of California at Los Ang Univ. of California at Los Ang Univ. of Strathe Estricted Structure Optimal Con Univ. of Strathe Univ. of Optimal Impulsive Straints, 233
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems U Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Da Its Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi 10:40 An Algebraic Geometric Approa	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. ation for Hybrid Systems, 149 Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ. ata Piecewise Affine Systems and ing Control, 161 Tokyo Inst. of Tech. Tokyo Inst. of Tech. ach to the Identification of a Class of Univ. of California, Berkeley	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40 Nondegenerate Necessary Cond Control Problems with State Con Arutyunov, Aram V.	Porto Univ. Inst. For System Robin Robin Equation for the Solution of the Univ. degli Studi di Pad Univ. degli Studi di Bolo Univ. degli Studi di Bolo Bolo Bolo Bolo Bolo Bolo Bolo Bol
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Da Its Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi 10:40 An Algebraic Geometric Appro Linear Hybrid Systems, 167 Vidal, Rene Soatto, Stefano	Regular Session Univ. of Cambridge Univ. of Callfornia, Berkeley  nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech.  ation for Hybrid Systems, 149 Univ. of Cambridge Univ. of California, Berkeley Univ. of California, Los Angeles	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati & Finite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadic Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40 Nondegenerate Necessary Cond Control Problems with State Con	Porto Univ. Inst. For System Robin Equation for the Solution of the Univ. degli Studi di Pac Univ. degli Studi di Bolo Univ. degli Studi di Bolo Univ. degli Studi di Univ. of California at Los Ang Univ. of California at Los Ang Univ. of California at Los Ang Univ. of Stratho Univ. of Stratho Univ. of Stratho Univ. of Stratho Univ. Straints, 233 Russian Peoples Friendship In Moscow State In Porto Univ. Inst. For System
Hybrid Systems I Chair: Rowe, Camile Co-Chair: Vidal, Rene 09:20 Two Approaches to State Estin Affine Systems, 143 Juloski, Aleksandar Heemels, Maurice Boers, Yvo Verschure, Frank 09:40 Min-Max Moving Horizon Estim Rowe, Camile Maciejowski, Jan M. 10:00 Estimation of Hybrid Systems C Koutsoukos, Xenofon 10:20 Optimal Control of Sampled-Dalts Application to CPU Process Azuma, Shun-ichi Imura, Jun-ichi 10:40 An Algebraic Geometric Appro- Linear Hybrid Systems, 167 Vidal, Rene	Regular Session Univ. of Cambridge Univ. of California, Berkeley nation for a Class of Piecewise  Eindhoven Univ. of Tech. Eindhoven Univ. of Tech. Thomson-csf Signaal Eindhoven Univ. of Tech. ation for Hybrid Systems, 149 Univ. of Cambridge Using Discrete Sensors, 155 Vanderbilt Univ. ata Piecewise Affine Systems and ing Control, 161 Tokyo Inst. of Tech. Tokyo Inst. of Tech. ach to the Identification of a Class of Univ. of California, Berkeley	Co-Chair: Pereira, Fernando Lobo  09:20 Employing the Algebraic Riccati Efinite-Horizon LQ Problem, 210 Ferrante, Augusto Marro, Giovanni Ntogramatzidis, Lorenzo  09:40 Relatively Optimal Control and Its Blanchini, Franco Pellegrino, Felice Andrea  10:00 On Infinite-Time Nonlinear Quadi Chen, Yue Edgar, Thomas F. Manousiouthakis, Vasilios  10:20 Robustness of Full Order and Resystems, 227 Grimble, Michael John  10:40 Nondegenerate Necessary Cond Control Problems with State Con Arutyunov, Aram V. Karamzin, Dmitry	Porto Univ. Inst. For System Robo  Equation for the Solution of the Univ. degli Studi di Pac Univ. degli Studi di Bolo Univ. degli Studi di Bolo S. Linear Implementation, 215 Univ. degli Studi di U Univ. degli Studi di U Univ. degli Studi di U Univ. of California at Los Ang Univ. of Texas at Ai Univ. of California at Los Ang Estricted Structure Optimal Cor Univ. of Stratho

Control Problem, 239	Inst. for Problems in Mechanics	the Sinusoidal Tracking Performant Oloomi, Hossein M.	ce, 300 Purdue Univ. at Fort Wayne
Melikyan, Arik Hovakimyan, Naira	Virginia Inst. of Tech.	Shafai, Bahram	Northeastern Univ
Ikeda, Yutaka	Boeing Company	11:00	
uA08	Maul Suite 3	L2 Gain Analysis of Linear Parame Problem and Its Finite Dimensional	
lectromechanical Control	Regular Session	Ohta, Yoshito	Osaka Univ
ystems		Kunitake, Takashi	Sharp Corp
Chair: Vautier, Benjamin Jean	Univ. of Newcastle		Guest Room 350
Guillaume Co-Chair: Mukherjee, Ranjan	Michigan State Univ.	TuA10 Distributed Parameter Systems I	
9:20	3	Chair: Bewley, Thomas R.	UC San Diego
Switching Control Strategy for I Dependent Bias, 245	Magnetic Bearings with a State-	Co-Chair: Demetriou, Michael A 09:20	. Worcester Pol. Inst
Motee, Nader	Louisiana State Univ.	Set Point Boundary Control for a N	onlinear Distributed Parameter
de Queiroz, Marcio	Louisiana State Univ.	System, 312	147 - 1-7
9:40	10.0 test and Application to	Byrnes, Christopher I. Gilliam, David S.	Washington Univ Texas Tech. Univ
State-Dependent Sliding-Sector \ Swing-Up Control of Pendulum, 2		Isidori, Alberto	Washington Univ
Swing-Op Control of Peridulum, 2 Suzuki, Satoshi	Tokyo Denki Univ.	Shubov, Victor I.	Texas Tech. Univ
Furuta, Katsuhisa	Tokyo Denki Unversity	09:40	
Pan, Yaodong	National Inst. of Advanced Industrial Science and Tech.	A Naucausal Strategy for Feedback Flow Systems, 318	
	(AIST)	Cathalifaud, Patricia	UCSI
0:00	W Oakana Olah W. Amahada	Bewley, Thomas R.	UC San Dieg
	folling Sphere: Stability Analysis,	10:00 Robust Fault Tolerant Controller in	Parabolio Distributed
257 Das, Tuhin	Michigan State Univ.	Robust Fault Tolerant Controller in Parameter Systems with Actuator I	Faults, 324
Mukherjee, Ranjan	Michigan State Univ.	Demetriou, Michael A.	Worcester Pol. Ins
10:20		10:20	
	of Hemisphere Space by Digital	An Optimal Finite-Diemensional Me	odeling of Heat and Diffusion
mage Conversion, 263 Sudo, Yoshie	Tokyo Univ. of Tech.	Systems with Partially Known Eige	nstructure, 330 Okayama Uni
Hashimoto, Hiroshi	Tokyo Univ. of Tech.	lmai, Jun Ando, Yasuaki	Okayama Uni Okayama Uni
Ishii, Chiharu	Kogakuin Univ.	Konishi, Masami	Okayama Uni
0:40		10:40	
Avoiding Hysteresis in Vibration	Control Using Piezoelectric	A Way to Deal with Nonlinear Bour	
Laminates, 269 Vautier, B. J. G.	Univ. of Newcastle	Channel Optimal Control Problems Ouarit, Hicham	s, 336 Lab. Automatique De Grenob
Moheimani, S. O. R.	Univ. of Newcastle	Lefevre, Laurent	Esisar-inp
		Georges, Didier	ENSIEG - INP
TuA09 Robust Control I	Maui Suite 4 Regular Session	Begovich, Ofelia	Cinvestav GD
Chair: Shafai, Bahram	Northeastern Univ.	11:00	or Imaga Processing 242
Co-Chair: Ohta, Yoshito	Osaka Univ.	Abstract Spatial Hybrid Systems fo Mukhopadhyay, Supratik	or Image Processing, 342 UPEN
09:20		iviukiiopauriyay, Supratik	JI LIV
Dynamical Robust Backstepping	Using a Combined Sliding Modes	TuA11	Guest Room 35
and High-Gain Observer Approa	ch, 275 itional Inst. of Standards and Tech.	Output Feedback I	Regular Session
Gorman, Jason Na Jablokow, Kathryn	Pennsylvania State Univ.	Chair: Trofino, Alexandre	Federal Univ. of Santa Catarir Univ. of Toron
Cannon, David	Pennsylvania State Univ.	Co-Chair: Maggiore, Manfredi	Olily, of Total
09:40	•	09:20 Observer-Based IDA Control of Sy	nchronous Generators, 344
Robust Tracking Problem for Co Uncertain Systems, 282	ntinuous Time Stochastic	Maya-ortiz, Paul	Univ. Nacional Autonoma E Mexic
Yoon, Myung-gon Ugrinovskii, Valery	The Univ. of New South Wales Australian Defence Force Acad.	Espinosa-Perez, Gerardo	Univ. Nacional Autonoma o Mexic
10:00 Robust Control for Uncertain Sin	gular Systems with Disk Pole	09:40 Finite Time Control Via Output Fed	edback: A General Approach,
Contraints, 288	Accessed and their of Total	350	
Hu, Gang Yu, Jianmin	Guangdong Univ. of Tech. South China Univ. of Tech.	Amato, Francesco	Univ. degli Studi di Catanza
Xu, Jianmin	South China Only, or 1ech.	Ariola, Marco	Univ. degli Studi di Nap Federico
10:20 Robust Nonlinear Control of Trai 294	nsient Stability of Power Systems.,	Cosentino, Carlo	Univ. degli Studi di Nap Federico
Brahim, BEHAR	Lab. des Signaux et Systčms		, 236,165
Françoise, Lamnabhi- Lagarrigue	Lab. des Signaux et Systčms		
Tarek, Ahmed-Ali	Ec. Sup. des Etudes et Tech. d'Armements		

	k Control of a Class of Uncertain	TuA13 System Theoretic Methods in	Guest Room 450 Invited Session
Nonlinear Systems, 356		Quantum Control	SISSA
Coutinho, Daniel Ferreira	Pontificia Univ. Catolica do Rio	Chair: Altafini, Claudio Co-Chair: Khaneja, Navin	Harvard Univ.
Trofino, Alexandre	Grande do Sul Federal Univ. of Santa Catarina	Organizer: Altafini, Claudio	SISSA
Barbosa, Karina	Federal Univ. of Santa Catarina	Organizer: Khaneja, Navin	Harvard Univ.
10:20	, session since statement	09:20	
	ng with a Matching Condition, 362	Quantum Markovian Master Eq	uation Driven by Coherent
Consolini, Luca	Univ. of Parma	Controls: A Controllability Analy	
Maggiore, Manfredi	Univ. of Toronto	Altafini, Claudio	SISSA
10:40		09:40	
Output Feedback Variable Struct	ure Control of Nonlinear		-Level Quantum Systems (I), 416
Mechanical Systems, 368		Boscain, Ugo V.	SISSA-ISAS
Xian, Bin	Clemson Univ.	charlot, gregoire	SISSA-ISAS
de Queiroz, Marcio Dawson, Darren M.	Louisiana State Univ. Clemson Univ.	10:00	in Dimension and Cons
McIntyre, Michael	Clemson Univ.	Optimal Control of Coupled Spi Correlated Relaxation (I), 422	in Dynamics under Cross-
11:00	Cicinson Chiv.	Khaneja, Navin	Harvard Univ.
	eedback Controllers for a Class of	Glaser, Steffen	Tech. Univ. of Munich
Nonlinear Systems, 374	eedback Controllers for a Class of	10:20	
Coutinho, Daniel Ferreira	Pontificia Univ. Catolica do Rio	The Controllability of Infinite Qu	uantum Systems (I), 428
	Grande do Sul	Brockett, Roger	Harvard Univ.
Trofino, Alexandre	Federal Univ. of Santa Catarina	Rangan, Chitra	Univ. of Michigan
Barbosa, Karina	UNIPLAC	Bloch, Anthony Michael	Univ. of Michigan
TuA12	Maui Suite 5	10:40	
Filtering and Estimation	Regular Session	Lyapunov-Based Control of Qu	
Chair: Medvedev, Alexander	Uppsala Univ.	Grivopoulos, Symeon	
V.	opposite cities	Bamieh, Bassam	Univ. of California at Santa Barbara
Co-Chair: Heemels, Maurice	Eindhoven Univ. of Tech.	44.00	Daibala
09:20		11:00 Observability, Measurement an	nd Parameter Identification of
Linear H-Infinity Filter Design for	a Class of Uncertain Nonlinear	Quantum Mechanical Systems,	
Systems, 380		D'Alessandro, Domenico	Iowa State Univ.
Coutinho, Daniel Ferreira	Pontificia Univ. Catolica do Rio	Albertini, Francesca	Univ. Di Padova
Barbosa, Karina	Grande do Sul UFSC		
Trofino, Alexandre	Federal Univ. of Santa Catarina	TuA14	Guest Room 451
de Souza, Carlos E.	Lab. Nacional de Computação	Fault Detection Chair: Simani, Silvio	Regular Session Univ. of Ferrara
	Cientifica - LNCC	Co-Chair: Georges, Didier	ENSIEG - INPG
09:40		09:20	ENOIS - IN C
Robust Noncausal Filtering of Sp		Fault Diagnosis of NonLinear	Dynamic Processes Using
Einicke, Garry A.	CSIRO Australia	Identified Hybrid Models, 445	
10:00		Simani, Silvio	Univ. of Ferrara
State Estimation for Systems with		Patton, Ron J.	Univ. of Hull
Schinkel, Michael Heemels, Maurice	Univ. of Glasgow Eindhoven Univ. of Tech.	09:40	
Juloski, Aleksandar	Eindhoven Univ. of Tech.	Residual Design for Dynamic P	Processes Using De-Coupling
10:20	Emanoven only. or real.	Technique, 451	Unit of Dalama
State Matrix Kalman Filter, 393	•	Diversi, Roberto Simani, Silvio	Univ. of Bologna Univ. of Ferrara
Choukroun, Daniel	Tech Israel Inst. of Tech.		Cilly. Ot 1 Gifala
Weiss, Haim M.	Rafael	10:00 Robust Fault Diagnosis for Line	ear Descriptor Systems Using
Bar-Itzhack, Itzhack Y.	Tech Israel Inst. of Tech.	Proportional Integral Observers	
Oshman, Yaakov	Tech Israel Inst. of Tech.	Marx, Benoit	Lab. D'automatique De Grenoble
10:40		Koenig, D.	Inpg - Esisar
	Scheme in Recursive Parameter	Georges, Didier	ENSIEG - INPG
Estimation, 399 Medvedev, Alexander V.	Ummanla I luiv	10:20	
• •	Uppsala Univ.		ents in Intelligent Sensors for Fault
11:00	n for Noisy AB Drosses 405	Detection Based on Data-Drive	•
On Bias Compensation Estimatio Jia, Li-juan	n for Noisy AR Process, 405 Kyushu Univ.	Lughofer, Edwin	Johannes Kepler Univ. Linz
Kanae, Shunshoku	Kyushu Univ. Kyushu Univ.	Efendic, Hajrudin Del Re, Luigi	Johannes Kepler Univ. Linz Johannes Kepler Univ. Linz
Yang, Zi-jiang	Kyushu Univ.	Klement, Erich Peter	Johannes Kepler Univ. Linz
Wada, Kiyoshi	Kyushu Univ.	10:40	and the present a series and a series
	•		MI-Technique and Its Integration in
•			January and the mile granen (i)
		the Design of Fault Detection S	Systems, 469
			Univ. of Duisburg
		the Design of Fault Detection S Ding, Steven X. Zhang, Ping	Univ. of Duisburg Univ. of Duisburg
		the Design of Fault Detection S Ding, Steven X. Zhang, Ping Frank, Paul M.	Univ. of Duisburg Univ. of Duisburg Gerhard-Mercator-Univ. Duisburg
		the Design of Fault Detection S Ding, Steven X. Zhang, Ping Frank, Paul M.	Univ. of Duisburg Univ. of Duisburg

	letection Filters for Disturbance	A Hybrid System Model and Overlap	ping Decomposition for
Attenuation: An Invariant Zero Appr		Vehicle Flight Formation Control (I),	
Kim, Yongmin Park, Jaehong	Seoul National Univ. Seoul National Univ.	Chen, Qi Ozguner, Umit	The Ohio State (
TuAPI	Grand Promenade	16:00	
	Poster/Interactive Paper Session	Cooperative Scheduling of Tasks for	Networked Uninhabited
Chair: Abdallah, Chaouki T.	Univ. of New Mexico	Autonomous Vehicles (I), 522	The Ohio State I
•	Only, of their friends	Gil, Alvaro	The Ohio State L
09:20	One and Observation	Passino, Kevin	The Ohio State U Air Force Res.
Existence of Optimal Controls for a Systems on Banach Spaces, 480	General Class of Impulsive	Sparks, Andrew G.	Air Force Res.
Ahmed, Nasiruddin	Univ. of Ottawa	TuM02	Regen
Allinea, Nasilaaaiii	Oniv. or Ottawa	Dynamics and Control of	Invited Ses
Favoire Analysis and the Talenales	Malmaniat Dania 406	Nonlinear Systems	
Fourier Analysis and the Takenaka- Bultheel, Adhemar	-iviaimquist Basis, 486 K.U.Leuven	Chair: Bloch, Anthony M.	Univ. of Mich
•		Co-Chair: Zenkov, Dmitry	North Carolina State L
Carrette, Pierre	Shell Oil Company, Houston	Organizer: Bloch, Anthony M.	Univ. of Michi
		Organizer: Zenkov, Dmitry	North Carolina State L
Asymptotic Control of Pairs of Oscil		14:20	
Czarnecki, Marc-Olivier	Univ. Montpellier 2		neralized Double Procket
Cabot, Alexandre	Univ. de Limoges	Optimality of Double Bracket and Ge Flows (I), 528	neranzeu Double Dracket
		Bloch, Anthony M.	Univ. of Michi
Uncertain Dissipative Linear System	ns. Part i. Robust Analysis and	Iserles, Arieh	Univ. of Cambri
Certification*	-		Only, or Cambri
Barb, Florin Dan	Delft Univ. of Tech.	14:40	Tanadian af A. este etc.
Ben Tal, Aharon	Tech Israel Inst. of Tech.	Controlled Lagrangian Methods and	i racking of Accelerated
Nemirovski, Arkadi	Tech Israel Inst. of Tech.	Motions (I), 533	Nauth Canallina Otre 1
		Zenkov, Dmitry	North Carolina State U
TuAW	Spats Trattoria	Bloch, Anthony M.	Univ. of Michi
High School Students		Marsden, Jerrold E.	California Inst. of To
Workshop		15:00	
Chair: Pasik-Duncan,	Univ. of Kansas	Collision Avoidance for Multiple Agei	
Bozenna		Chang, Dong Eui	Univ. of Califo
		Shadden, Shawn	California Inst. of Te
TuNPL	Sunset Terrace	Marsden, Jerrold E.	California Inst. of Te
Plenary Panel: International	Plenary Panel	Olfati-Saber, Reza	California Inst. of Te
Funding Thrusts and		15:20	
Mechanisms		Asymptotic Stability of Rigid Body At	
Chair: Werbos, Paul J.	NSF	Shen, Jinglai	Univ. of Michi
		Sanyal, Amit	Univ. of Michi
TuM01	Monarchy Ballroom	McClamroch, N. Harris	Univ. of Michi
Cooperative Control for	Invited Session	15:40	
Networked Uninhabited		Coordinated Control of Networked M	echanical Systems with
Autonomous Vehicles II		Unstable Dynamics (I), 550	
Chair: Passino, Kevin	Ohio State Univ.	Nair, Sujit	Princeton L
Co-Chair: Sparks, Andrew G.	Air Force Res. Lab.	Leonard, Naomi Ehrich	Princeton U
Organizer: Passino, Kevin	Ohio State Univ.	Moreau, Luc	Eindhoven Univ. of Te
14:20		16:00	
Stability Properties of a Cooperative	∍ Receding Horizon Controller	Information Patterns and Hedging Bi	ockett's Theorem in
(I), 492		Controlling Vehicle Formations (I), 5	
Cassandras, Christos G.	Boston Univ.	Baillieul, John	Boston U
Li, Wei	Boston Univ.	Suri, Atul	Boston U
14:40		TuM03	Regeno
14:40 Control of Leader-Follower Formati	ons of Terrestrial UAVs (I), 498	IUMUS	PROPERTY OF THE RESIDENCE AND A SECRETARIAN AND A SECOND AND A SECOND ASSESSMENT OF THE PROPERTY OF THE PROPER
	ons of Terrestrial UAVs (I), 498 Ohio State Univ.	Control of Networks I	Regular Ses
Control of Leader-Follower Formati		Control of Networks I	
Control of Leader-Follower Formati Chen, Xingping	Ohio State Univ.	Control of Networks I Chair: Chiasson, John	Regular Ses Univ. of Tennes Pennsylvania State U
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay	Ohio State Univ. The Ohio State Univ.	Control of Networks I	Univ. of Tennes
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00	Ohio State Univ. The Ohio State Univ. Ohio State Univ.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.	Univ. of Tennes
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically N	Ohio State Univ. The Ohio State Univ. Ohio State Univ.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M. 14:20	Univ. of Tennes Pennsylvania State U
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically N Agents (I), 504	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Varying Formations of Dynamic	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M. 14:20 End-To-End Bandwidth Guarantees	Univ. of Tennes Pennsylvania State U through Fair Local Spectru
Control of Leader-Follower Formatic Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically \ Agents (I), 504 Gupta, Vijay	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Varying Formations of Dynamic California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M. 14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks,	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564
Control of Leader-Follower Formatic Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically N Agents (I), 504 Gupta, Vijay Hassibi, Babak	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Varying Formations of Dynamic California Inst. of Tech. California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564 Univ. of Pennsylv
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically \ Agents (I), 504 Gupta, Vijay Hassibi, Babak Murray, Richard M.	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Varying Formations of Dynamic California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati Tassiulas, Leandros	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564 Univ. of Pennsylv
Control of Leader-Follower Formati Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically N Agents (I), 504 Gupta, Vijay Hassibi, Babak Murray, Richard M.	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Ohio State Univ.  Varying Formations of Dynamic  California Inst. of Tech. California Inst. of Tech. California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati Tassiulas, Leandros  14:40	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564 Univ. of Pennsylv Univ. of Thes
Control of Leader-Follower Formatic Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically Nagents (I), 504 Gupta, Vijay Hassibi, Babak Murray, Richard M. 15:20 Adaptive Models of Pop up Threats	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Ohio State Univ.  Varying Formations of Dynamic  California Inst. of Tech. California Inst. of Tech. California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati Tassiulas, Leandros  14:40 Optimal Power Control in Wireless E	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564 Univ. of Pennsylv. Univ. of Thes
Control of Leader-Follower Formatic Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically Nagents (I), 504 Gupta, Vijay Hassibi, Babak Murray, Richard M. 15:20 Adaptive Models of Pop up Threats Denial (I), 510	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Ohio State Univ.  Varying Formations of Dynamic  California Inst. of Tech. California Inst. of Tech. California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati Tassiulas, Leandros  14:40 Optimal Power Control in Wireless E Based Utility Guarantees, 570	Univ. of Tennes Pennsylvania State L through Fair Local Spectru 564 Univ. of Pennsylv Univ. of Thes
Control of Leader-Follower Formatic Chen, Xingping Serrani, Andrea Ozbay, Hitay 15:00 Stability Analysis of Stochastically Nagents (I), 504 Gupta, Vijay Hassibi, Babak Murray, Richard M. 15:20 Adaptive Models of Pop up Threats	Ohio State Univ. The Ohio State Univ. Ohio State Univ. Ohio State Univ.  Varying Formations of Dynamic  California Inst. of Tech. California Inst. of Tech. California Inst. of Tech.	Control of Networks I Chair: Chiasson, John Co-Chair: Lagoa, Constantino M.  14:20 End-To-End Bandwidth Guarantees Share in Wireless Ad-Hoc Networks, Sarkar, Saswati Tassiulas, Leandros  14:40 Optimal Power Control in Wireless E	Univ. of Tennes Pennsylvania State U through Fair Local Spectru 564 Univ. of Pennsylva Univ. of Thes

	15:00 A Novel Approach to Traffic Engineering for Ad-Hoc Networks, 576	14:20 Finite Bisimulations of Controllable Linear Systems, 634
	Movsichoff, Bernardo Adrián Pennsylvania State Univ. Lagoa, Constantino M. Pennsylvania State Univ.	Tabuada, Paulo Univ. of Notre Dame Pappas, George J. Univ. of Pennsylvania
	15:20	14:40
	The Effect of Time Delays in the Stability of Load Balancing Algorithms for Parallel Computations, 582	A Logic-Based Hybrid Solver for Optimal Control of Hybrid Systems, 640
	Birdwell, J. Douglas Univ. of Tennessee, Knoxville	Bemporad, Alberto Univ. of Siena
	Chiasson, John Univ. of Tennessee, Knoxville	Giorgetti, Nicolo' Univ. of Siena
	Abdallah, Chaouki T. Univ. of New Mexico Tang, Zhong Univ. of Tennessee, Knoxville	15:00
	Alluri, Nivedita Andhra Univ. India	Viability, the Solution Set and Fixed Point Approximation of Hybrid Systems, 646
	Wang, Tse-Wei Univ. of Tennessee, Knoxville	Guay, Martin Queen's Univ.
	15:40	Labinaz, Gino Queen's Univ.
	Distributed Consensus Protocols for Coordinating Buyers, 588	15:20
	Bauso, Dario Univ. di Palermo Giarre, Laura Univ. Di Palermo	Regions of Stability for Limit Cycles of Piecewise Linear Systems,
	Giarre, Laura Univ. Di Palermo Pesenti, Raffaele Univ. of Palermo	651
	16:00	Goncalves, Jorge M. Caltech
	Controlling Internet Queue Dynamics Using Recursively Identified Models, 593	15:40 RRTs for Nonlinear, Discrete, and Hybrid Planning and Control, 657
	Gunnarsson, Frida Linkoping Univ.	Branicky, Michael S. Case Western Res. Univ.
	Gunnarsson, Fredrik Linkoping Univ.	Curtiss, Michael CWRU
-	Gustafsson, Fredrik Linkoping Univ.	Levine, Joshua CWRU
	TuM04 Regency C	Morgan, Stuart CWRU
•	Linear Systems II Regular Session	16:00 Overlity of Service Central in Sett Book Time Applications, 664
	Chair: Mestha, Lalit K. Xerox Corp.	Quality of Service Control in Soft Real-Time Applications, 664 Palopoli, Luigi Scuola Superiore Sant'anna
	Co-Chair: Owens, David H. The Univ. of Sheffield	Cucinotta, Tommaso ReTiS Lab.
	14:20	Bicchi, Antonio Univ. di Pisa
	Exploiting Symmetry for the Distributed Control of Spatially Interconnected Systems, 598	TuM06 Maui Suite 2
	Recht, Benjamin MIT	Networked Control Systems Regular Session
	D'Andrea, Raffaello Cornell Univ.	and Packet Losses
	14:40	Chair: Lemmon, Michael Univ. of Notre Dame
	Controllability and Optimization for Differential Linear Repetitive	Co-Chair: Tanner, Herbert Univ. of New Mexico
	Processes, 604  Dymkou, Siarhei  Univ. of Ballarat	14:20
	Rogers, Eric Univ. of Southampton	Optimal Dropout Compensation in Networked Control Systems, 670
	Dymkov, Michael National Acad. of Sciences, Belarus	Ling, Qiang Univ. of Notre Dame
	Galkowski, Krzysztof Univ. of Zielona Gora Owens, David H. The Univ. of Sheffield	Lemmon, Michael Univ. of Notre Dame
	Owens, David H. The Univ. of Sheffield 15:00	14:40
	Robust H-Inf Filter Design of Uncertain Descriptor Systems with	Stability of Networked Control Systems in the Presence of Packet
•	Discrete and Distributed Delays, 610	Losses, 676 Azimi-sadjadi, Babak Rensselaer Pol. Inst.
	Han, Qing-long Central Queensland Univ.	15:00
	Yue, Dong Nanjing Normal Univ.	Decentralized Spacing Control of a String of Multiple Vehicles Over
÷	15:20 Stabilization and Pole Placement with Respect to State	Lossy Datalinks, 682
	Constraints: A Robust Design Via LMI, 616	Teo, Rodney Stanford Univ.
7- 1	EL Faiz, Samira Univ. Cadi Ayyad	Stipanovic, Dusan M. Stanford Univ. Tomlin, Claire J. Stanford Univ.
	Ait Rami, Mustapha Univ. Cadi Ayyad	15:20
- 1 .	Benzaouia, Abdellah Univ. Cadi Ayyad	Wireless Communication Tradeoffs in Distributed Control, 688
	15:40	Liu, Xiangheng Stanford Univ.
4	Robust Strictly Positive Real Synthesis of Polynomial Segments for Discrete Time Systems, 622	Goldsmith, Andrea Stanford Univ.
	Yu, Wensheng Chinese Acad. of Sciences	15:40
_	Wang, Long Peking Univ.	Ethernet-Based Predictive Control of an Industrial Hydraulic Machine, 695
	xiang, yong Deakin Univ.	Tang, Poi Loon Univ. of British Columbia
	16:00	de Silva, Clarence W. Univ. of British Columbia
	H_{infty} Control of Discrete Linear Repetitive Processes, 628 Paszke, Wojciech Univ. of Zielona Gora	16:00
-	Galkowski, Krzysztof Univ. of Zielona Gora	Kalman Filtering with Intermittent Observations, 701
	Rogers, Eric Univ. of Southampton	Sinopoli, Bruno Univ. of California at Berkeley Schenato, Luca Univ. of California at Berkeley
-	Owens, David H. The Univ. of Sheffield	franceschetti, massimo Univ. california at berkeley
	TuM05 Maui Suite 1	Poolla, Kameshwar Univ. of California at Berkeley
	Hybrid Systems II Regular Session	Jordan, Michael Univ. of California at Berkeley
	Chair: Pappas, George J. Univ. of Pennsylvania	Sastry, Shankar Univ. of California at Berkeley
	Co-Chair: Branicky, Michael Case Western Res. Univ. S.	
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•	x	cxx
	<u>,</u>	

Optimal Control II Chair: Sadegh, Nader	Regular Session Georgia Inst. of Tech.	Decentralized Reconfigurable C with Application to a Segmented	d Telescope Test-Bed, 768
Co-Chair: kolmanovski, Vladimir	CINVESTAV	Abdullah, Ali A. Ioannou, Petros A.	Univ. of Southern California Univ. of Southern California
14:20	D /	T. 1800	Maui Suite
Optimal Controller for Third Degree	Polynomial System, 709 Autonomous Univ. of Nuevo	TuM09 Robust Control II	Regular Session
Basin, Michael V.	Leon	Chair: Yu, Li	Zhejiang Univ. of Tech
Alcorta Garcia, Maria	Autonomous Univ. of Nuevo	Co-Chair: Shafai, Bahram	Northeastern Univ
Aracelia	Leon	14:20	
14:40			pack Controllers with Variance and
An LQG Guidance Law with Bound	led Acceleration Command, 715	Disc Closed-Loop Pole Constra	
Hexner, Gyorgy	RAFAEL, Haifa ISRAEL	Yu, Li	Zhejiang Univ. of Tech
Shima, Tal	Rafael	Han, Qing-Long	Central Queesland Univ
Weiss, Haim M.	Rafael	He, Xiong-Xiong	Zhejiang Univ. of Tech
15:00	·	14:40	
Optimal Dynamic Scheduling in a M		Robust PID Controller Design for	or Plants with Structured and
Servers with Transient Overload, 7		Unstructured Uncertainty, 780	National Cheng Kung Univ
Chang, Junxia	Georgia Inst. of Tech.	Ho, Ming-Tzu Huang, Sheng-Tsai	National Cheng Kung Univ
Ayhan, Hayriye Dai, Jim	Georgia Inst. of Tech. Georgia Inst. of Tech.	<del>-</del> -	Haddial Cheng Rang Offic
Liu, Zhen	IBM TJ Watson Res. Center	15:00	Parameter Space Design of PID
Squillante, Mark S.	IBM TJ Watson Res. Center	Controllers, 786	Parameter Space Design of FID
Xia, Cathy	IBM TJ Watson Res. Center	Saeki, Masami	Hiroshima Univ
15:20		15:20	
Short Horizon Optimal Control of N	Ionlinear Systems, 728		to Engineering Applications, 792
Foley, Dawn	Georgia Inst. of Tech.	Iwasaki, Tetsuya	Univ. of Virgini
Sadegh, Nader	Georgia Inst. of Tech.	Hara, Shinji	The Univ. of Toky
15:40		15:40	•
Optimal Control of Linear Systems	with Random Time Delays in	Upper Bounds of Structured Sir	ngular Values for Mixed
Delta Domain, 734		Uncertainties, 798	
Hirano, Hiroyuki	Kanazawa Univ.	Lee, Jietae	Kyungpook National Univ
Azuma, Takehito	Kanazawa Univ.	Edgar, Thomas F.	Univ. of Texas at Austi
Fujita, Masayuki	Kanazawa Univ.	16:00	
16:00	0-1 ( ( 0) 706		ool for Robust Control Design Using
Characterization of the Minimal Tin Tlalolini, David	ne Solution of a Bioprocess, 736 CINVESTAV-IPN	the QFT Method, 803	<b>3</b> " 11 '
Mondié, Sabine	CINVESTAV-IPN	Nandakumar, Ramnath	City Univ City Univ
Kolmanovski, Vladimir	CINVESTAV	Halikias, George D. Zolotas, Argyrios	Imperial Coll. Londo
T. 1200	NAZVI CVILL O		
TuM08 Emerging Control	Maui Suite 3 Regular Session	TuM10	Guest Room 35
Applications	(Cagaial Oceasion	Distributed Parameter	Regular Session
Chair: Weyer, Erik	Univ. of Melbourne	Systems II Chair: Orlov, Yuri V.	CICESI
Co-Chair: Ioannou, Petros A.	Univ. of Southern California	Co-Chair: BARABANOV,	North Dakota State Univ. ND
14:20		Nikita E.	US/
Toward Feedback Stabilization of I	Faulty Software Systems: A	14:20	
Case Study, 738	,	· ·	od for Beam Equation with Delayed
Waydo, Stephen	California Inst. of Tech.		Modified Smith Predictors, 809
Dunbar, William B.	California Inst. of Tech.	Liang, Jinsong	Center for Self-Organizing an
Klavins, Eric	California Inst. of Tech.	<u>.</u>	Intelligent Systems Utah Stat
14:40			U
Model-Based Supervision of Valve		Chen, YangQuan	Utah State Univ
Bask, Michael	Lulea Univ. of Tech.	Guo, Bao-Zhu	Acad. of Mathematics an
Johansson, Andreas	Lulea Univ. of Tech.		System Science
15:00		14:40	otro Discharge Machining (ad-)
LQ Control of an Irrigation Channe Weyer Frik	Univ. of Melbourne	Vibration of Wires Used in Elec	ctro-Discharge Machining (edm),
Weyer, Erik	Only. Of Melbourne	Shahruz, Shahram M.	Berkeley Eng. Res. Ins
15:20	one of Multiple Age to with		Domoio, Eng. 103. Inc
Pursuit-Evasion Strategies for Tea	ins or wuitiple Agents with	15:00  Robust Stabilization of Infinite-	Dimensional Systems Via Finite-
Incomplete Information, 756 Antoniades, Adonis	UC Berkelev	Dimensional Discontinuous Ou	
Kim, H. Jin	Univ. of California at Berkeley	Orlov, Yuri V.	CICES
Sastry, Shankar	Univ. of California at Berkeley	Lou, Yiming	Univ. of California, Los Angele
	a or admorring at portrolly		
• •		Christofides, Panagiotis D.	Univ. of California at Los Angele
15:40	d Telescone Test-Red. 762	Christofides, Panagiotis D.	Univ. of California at Los Angeit
• •	d Telescope Test-Bed, 762 Univ. of Southern California	Christofides, Panagiotis D.	Univ. of California at Los Angele

45.00		44.46	
15:20 Riesz Basis Generation of a Se	erially Connected String System	14:40 Polynomial Extended Kalman Filt	ering for Discrete-Time Nonlinear
under Joint Damping Feedback		Stochastic Systems, 886	g =
Guo, Bao-Zhu	Acad. of Mathematics and	Germani, Alfredo	Univ. of L'Aquila
V:- V	System Sciences,	Manes, Costanzo	Univ. of L'Aquila
Xie, Yu	Acad. of Mathematics and System Sciences,	Palumbo, Pasquale	Istituto di Analisi dei Sistemi ed Informatica IASI-CNR
15:40	System Sciences,	15:00	montation indi-civit
Solution of H_{infty} Control Problem for Hybrid Periodic Infinite		A Modeling and Filtering Framewo	ork for Linear Differential-
Dimensional Systems and Gen		Algebraic Equations, 892	
BARABANÓV, Nikita E.	North Dakota State Univ. ND,	Schön, Thomas	Linköping Univ.
	USA	Gerdin, Markus	Linköpings Univ.
16:00		Glad, S. Torkel Gustafsson, Fredrik	Linkoping Univ. Linkoping Univ.
	oblem for Hybrid Periodic Infinite		Linkoping Only.
Dimensional Systems and Gen BARABANOV, Nikita E.	North Dakota State Univ. ND.	15:20 Filtering Equations in Infinite Dim	ensional Spaces with Mixed Type
BAIGIBANOV, MICHAEL.	USA	Observation, 898	chalonal opaces with white Type
		Florchinger, Patrick A.	Univ. of Metz
TuM11	Guest Room 351	15:40	
Output Feedback II	Regular Session	Regime Switching Stochastic App	roximation Algorithms with
Chair: Scherer, Carsten W. Co-Chair: Ariola, Marco	Delft Univ. of Tech. Univ. degli Studi di Napoli	Switched ODE Limit, 900	Marina Chata Llain
Co-Chair. Fillola, Marco	Federico II	Yin, George Krishnamurthy, Vikram	Wayne State Univ. Univ. of British Columbia
14:20	,	Ion, Cristina	Wayne State Univ.
	ate and Surface Roughness in Thin	16:00	•
Film Growth, 845		Robust Filtering for Uncertain Dis	crete-Time Systems: An
Lou, Yiming	Univ. of California, Los Angeles	Improved LMI Approach, 906	•
Christofides, Panagiotis D.	Univ. of California at Los Angeles	Xie, Lihua	Nanyang Tech. Univ.
14:40	a Bahwat Outsut Fasalt and Control	Lu, Lilei Zhang, David	Northeastern Univ. The Hong Kong Pol. Univ.
851	o Robust Output-Feedback Control,	Zhang, David Zhang, Huanshui	Hong Kong Pol. Univ.
Kanev, Stoyan	Delft Univ. of Tech.	2	
Scherer, Carsten W.	Delft Univ. of Tech.	TuM13	Guest Room 450
Verhaegen, Michel	Univ. of Twente	Predictive Control for Linear	Regular Session
De Schutter, Bart	Delft Univ. of Tech.	Systems	
			1 Inits of Covilla
15:00	More with Constraints and Their	Chair: Camacho, Eduardo F. Co-Chair: Grimble, Michael	Univ. of Sevilla Univ. of Strathclyde
Measurement Feedback Contro	ollers with Constraints and Their	Chair: Camacho, Eduardo F. Co-Chair: Grimble, Michael John	Univ. of Sevilla Univ. of Strathclyde
Measurement Feedback Contro Relation to the Solution of Ham		Co-Chair: Grimble, Michael	
Measurement Feedback Contro	nilton Jacobi Inequalities, 857	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive (	Univ. of Strathclyde
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba	nilton Jacobi Inequalities, 857 Univ. La Sapienza ack Control Design for Singularly	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive ( Approach, 912	Univ. of Strathclyde Control: A Polynomial-Time
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap	nilton Jacobi Inequalities, 857 Univ. La Sapienza nck Control Design for Singularly proach, 863	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive ( Approach, 912 Alamo, Teodoro	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap Assawinchaichote, Wudhich	nilton Jacobi Inequalities, 857 Univ. La Sapienza ack Control Design for Singularly proach, 863 univ. of Auckland	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive ( Approach, 912 Alamo, Teodoro Munoz de la Peña, David	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla Univ. de Sevilla
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap Assawinchaichote, Wudhich Nguang, Sing Kiong	nilton Jacobi Inequalities, 857 Univ. La Sapienza nck Control Design for Singularly proach, 863	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive ( Approach, 912 Alamo, Teodoro	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap Assawinchaichote, Wudhich Nguang, Sing Kiong 15:40	nilton Jacobi Inequalities, 857 Univ. La Sapienza ack Control Design for Singularly proach, 863 ai Univ. of Auckland Univ. of Auckland	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive ( Approach, 912 Alamo, Teodoro Munoz de la Pena, David Limon, Daniel	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla  Univ. de Sevilla  Univ. de Sevilla
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap Assawinchaichote, Wudhich Nguang, Sing Kiong 15:40 Optimal Regulation for Linear N	nilton Jacobi Inequalities, 857 Univ. La Sapienza ack Control Design for Singularly proach, 863 univ. of Auckland Univ. of Auckland	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive of Approach, 912 Alamo, Teodoro Muñoz de la Peña, David Limon, Daniel Camacho, Eduardo F. 14:40 Min Max MPC Based on a Graph	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla Univ. de Sevilla Univ. of Sevilla Problem, 917
Measurement Feedback Contro Relation to the Solution of Ham Battilotti, Stefano 15:20 Fuzzy H-Infinity Output Feedba Perturbed Systems: An LMI Ap Assawinchaichote, Wudhich Nguang, Sing Kiong 15:40 Optimal Regulation for Linear N Ambrosino, Giuseppe Ariola, Marco	nilton Jacobi Inequalities, 857 Univ. La Sapienza  ack Control Design for Singularly proach, 863 univ. of Auckland Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II	Co-Chair: Grimble, Michael John 14:20 Constrained Min-Max Predictive of Approach, 912 Alamo, Teodoro Muńoz de la Peńa, David Limon, Daniel Camacho, Eduardo F. 14:40 Min Max MPC Based on a Graph Alamo, Teodoro	Univ. of Strathclyde  Control: A Polynomial-Time  Univ. de Sevilla Univ. de Sevilla Univ. of Sevilla Problem, 917 Univ. de Sevilla
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Parrilo, Pablo A. Morari, Manfred	Swiss Federal Inst. of Tech. Swiss Federal Inst. of Tech.	ing, wei	City Univ. of Hong Kong
		TuP01	Monarchy Ballroom
TuM14	Guest Room 451	Cooperative Control of Multiple Autonomous Agents	Regular Session
Fault Detection and	Regular Session	Chair: Francis, Bruce	Univ. of Toronto
Accomodation I Chair: Staroswiecki, Marce	I Univ. des Sciences et Tech. Lille	Co-Chair: Feron, Eric	Massachusetts Inst. of Tech.
Co-Chair: De Persis, Claud		16:40	
·	Only, di Roma	Local Control Strategies for Groups	s of Mobile Autonomous Agents
14:20 Detecting Faults from Encode	d Information 047	1006	or wobile Autonomous Agents,
De Persis, Claudio	Univ. di Roma	Lin, Zhiyun	Univ. of Toronto
14:40	Oliv. Gi Nollia	Broucke, Mireille E.	Univ. of Toronto
<del>-</del>	er for Fault Detection and Isolation.,	Francis, Bruce	Univ. of Toronto
953	i for Fault Detection and isolation.,	17:00	
Akhenak, Abdelkader	Inst. national Pol. de lorraine	Agent-Localized Conditions for For	mation Maintenance, 1012
Chadli, Mohammed	CRAN-INPL-CNRS, UMR 7039	Ketema, Yohannes	Univ. of Minnesota
Maquin, Didier	CRAN-INPL	Balas, Gary J.	Univ. of Minnesota
Ragot, Jose	CRAN-INPL	17:20	
15:00		Modeling and Computation of Option	mal Task Assignment for
Actuator Faults and the Linear	· Quadratic Problem, 959	Cooperative Control, 1017	
Staroswiecki, Marcel	Univ. des Sciences et Tech. Lille	Kang, Wei	Naval Postgraduate School
15:20		Sparks, Andrew G.	Air Force Res. Lab.
	Tool for Diagnosis and Parametric	17:40	
	ynamical Nonlinear Systems, 966	On Some Communication Scheme	s for Distributed Pursuit-Evasion
Youssef, Bilal	ENSIEG - INPG	Games, 1023	David last of Took
Alamir, Mazen	ENSIEG - INPG	Speranzon, Alberto Johansson, Karl Henrik	Royal Inst. of Tech.
15:40		· ·	Royal Inst. of Tech.
Application of Probabilistic Ro	bustness Technique to the Fault	18:00	North and For Fife in the Alexander
Detection System Design, 972		Spatial Distribution of Two-Agent C	iusters for Efficient Navigation,
Ding, Steven X.	Univ. of Duisburg	1029 De Mot, Jan	Massachusetts Inst. of Tech.
Zhang, Ping	Univ. of Duisburg	Feron, Eric	Massachusetts Inst. of Tech.
Frank, Paul M.	Gerhard-Mercator-Univ. Duisburg	•	Wassachusetts Hist. Of Tech.
Ding, E.L.	Univ. of Applied Sciences Gelsenkirchen	18:20 A Distributed Algorithm for Energy-	Efficient Coordination of
40.00	Cosciikiionon	Multiple-UAV Systems, 1035	Emoletic Goordination of
16:00 Multivariable Central and Faile	re Accommodation in Eye-Head-	Frazzoli, Emilio	Univ. of Illinois at Urbana-
Torso Target Tracking, 978	re Accommodation in Eye-nead-		champaign
Chang, Bor-chin	Drexel Univ.	Ribichini, Gabriele	Univ. of Illinois at Urbana-
Hu, Chunlong	Drexel Univ.		Champaign
TuMPI	Grand Promenade	TuP02 Nonlinear Output Regulation	Regency A
SIAM Poster Papers II		and Stabilization	Invited Session
Chair: Abdallah, Chaouki T	. Univ. of New Mexico	Chair: Jiang, Zhong Ping	Pol. Univ.
14:20		Co-Chair: Huang, Jie	Chinese Univ. of Hong Kong
	ystems. Part II. Robust Synthesis*	Organizer: Jiang, Zhong Ping	Pol. Univ.
Barb, Florin Dan	Delft Univ. of Tech.	Organizer: Huang, Jie	Chinese Univ. of Hong Kong
Dan Tal Abassa	Tech Israel Inst. of Tech. Tech Israel Inst. of Tech.	16:40	
Ben Tal, Aharon		Adaptive Tracking and Disturbance	Rejection for Uncertain
Ben Tal, Aharon Nemirovski, Arkadi	recir islael list. of recir.		•
Nemirovski, Arkadi		Nonlinear Systems (I), 1041	
Nemirovski, Arkadi  Multiscale Singularly Perturbe	d Control Systems: Limit		Univ. di Roma Tor Vergata
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets	d Control Systems: Limit and Averaging, 984	Nonlinear Systems (I), 1041	Univ. di Roma Tor Vergata Univ. di Roma Tor Vergata
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir	d Control Systems: Limit and Averaging, 984 Univ. of South Australia	Nonlinear Systems (I), 1041 Tomei, Patrizio	
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets	d Control Systems: Limit and Averaging, 984	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global R	Univ. di Roma Tor Vergata
Nemirovski, Arkadi Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global R Feedback (I), 1047	Univ. di Roma Tor Vergata Legulation Via Nonlinear Output
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati	d Control Systems: Limit and Averaging, 984 Univ. of South Australia	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global R Feedback (I), 1047 Jiang, Zhong Ping	Univ. di Roma Tor Vergata Legulation Via Nonlinear Output Pol. Univ
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets of Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems*	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global R Feedback (I), 1047 Jiang, Zhong Ping Mareels, Iven	Univ. di Roma Tor Vergata Legulation Via Nonlinear Output Pol. Univ. The Univ. of Melbourne
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Ri Feedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J.	Univ. di Roma Tor Vergata Legulation Via Nonlinear Output Pol. Univ. The Univ. of Melbourne Univ. of Sydney
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Ri Feedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie	Univ. di Roma Tor Vergata Legulation Via Nonlinear Output Pol. Univ. The Univ. of Melbourne Univ. of Sydney
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa  Variational Inequalities for Co.	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Reedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie 17:20	Univ. di Roma Tor Vergata legulation Via Nonlinear Output Pol. Univ The Univ. of Melbourne Univ. of Sydney Chinese Univ. of Hong Kong
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets of Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Refeedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie 17:20 Remarks on Input to State Stabilize	Univ. di Roma Tor Vergata legulation Via Nonlinear Output Pol. Univ The Univ. of Melbourne Univ. of Sydney Chinese Univ. of Hong Kong
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa  Variational Inequalities for Co. Morimoto, Hiroaki	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz mbined Control and Stopping, 990 Ehime Univ.	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Refeedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie 17:20 Remarks on Input to State Stabiliza	Univ. di Roma Tor Vergata Pegulation Via Nonlinear Output Pol. Univ. The Univ. of Melbourne Univ. of Sydney Chinese Univ. of Hong Kong Pation (I), 1053 Louisiana State Univ.
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa  Variational Inequalities for Co. Morimoto, Hiroaki	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz mbined Control and Stopping, 990 Ehime Univ. mal Input Design with Respect to a	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global R Feedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie 17:20 Remarks on Input to State Stabiliza Malisoff, Michael Rifford, Ludovic	Univ. di Roma Tor Vergata legulation Via Nonlinear Output Pol. Univ The Univ. of Melbourne Univ. of Sydney Chinese Univ. of Hong Kong ation (I), 1053 Louisiana State Univ Univ. Claude Bernard - Lyon 1
Nemirovski, Arkadi  Multiscale Singularly Perturbe Occupational Measures Sets Gaitsgory, Vladimir Nguyen, Minh-Tuan  A New Approach of Stabilizati Systems* Guesmia, Aissa  Variational Inequalities for Co. Morimoto, Hiroaki	d Control Systems: Limit and Averaging, 984 Univ. of South Australia Univ. of South Australia on of Nondissipative Distributed Univ. de Metz mbined Control and Stopping, 990 Ehime Univ. mal Input Design with Respect to a	Nonlinear Systems (I), 1041 Tomei, Patrizio Marino, Riccardo 17:00 A Unifying Framework for Global Refeedback (I), 1047 Jiang, Zhong Ping Mareels, Iven Hill, David J. Huang, Jie 17:20 Remarks on Input to State Stabiliza	Univ. di Roma Tor Vergata Pegulation Via Nonlinear Output Pol. Univ. The Univ. of Melbourne Univ. of Sydney Chinese Univ. of Hong Kong

17:40		17:20	
	Control of a Class of Nonlinear	A Practical Linear Identification Me	
Systems (I), 1059	Address to the Control of the Contro	Representation of Time Invariant (	
Freidovich, Leonid	Michigan State Univ.	Watanabe, Ryo	Waseda Univ
Khalil, Hassan K.	Michigan State Univ.	Uchida, Kenko	Waseda Univ.
18:00		17:40	
Minimax Control of Nonlinear	Strict-Feedback Systems under	N-D Polynomial Matrix Structure w	vith System Applications, 1132
Stochastic Uncertainty Constra	aints (I), 1065	Pugh, A. Clive	Loughborough Univ.
Tang, Cheng	Univ. of Illinois at Urbana-	El-Nabrawy, Eman M.O.	Loughborough Univ.
	champaign	18:00	-
Basar, Tamer	Univ. of Illinois at Urbana-	2D Compartment of Linear System	ne*
	Champaign	Kaczorek, Tadeusz	Warsaw Tech. Univ.
18:20	. •	•	Walsaw Tech. Offiv.
	lvability of the Global Robust Output	18:20	
Regulation Problem (I), 1071	ivability of the Global Robust Output	Minimal or Maximal Realizations?,	
Chen, Zhiyong	Chinese Univ. of Hong Kong	Keel, Lee H.	Tennessee State Univ.
	Chinese Univ. of Hong Kong	Bhattacharyya, Shankar P.	Texas A & M Univ
Huang, Jie	Chinese Offiv. of Hong Kong		
TuP03	5	TuP05	Maui Suite 1
	Regency B	Hybrid Systems III	Regular Session
Control of Networks II	Regular Session	Chair: Di Benedetto, M.	Univ. of L'Aquila
Chair: Alpcan, Tansu	Univ. of Illinois at Urbana-	Domenica	
	champaign	Co-Chair: gurvits, Leonid	Los Alamos National Lab.
Co-Chair: Verriest, Erik I.	Georgia Inst. of Tech.	16:40	
16:40		On the Stability of Limit Cycles in I	Resonant DC-To-DC Power
Delay in State Feedback Conti	rol Over a Network, 1080	Converters, 1141	Nesonant DC-10-DC Fower
Verriest, Erik I.	Georgia Inst. of Tech.		Univ. Autonoma De Queretaro
17:00		Hernandez, Victor M.	cinvestav
	rolling of Combrellon Design 4006	Ramon, Silva	*****
	alized Controller Design, 1086	Sira-Ramirez, Hebertt J.	CINVESTAV-IPN
Sebe, Noboru	Kyushu Inst. of Tech.	17:00	
17:20		On the Stabilization of Linear Disc	rete-Time Hybrid Automata,
	End-To-End Congestion Control	1147	
Scheme for General Topology	Networks with Delay, 1092	Zoncu, Marco	Parades
Alpcan, Tansu	Univ. of Illinois at Urbana-	Balluchi, Andrea	Parades
	champaign	Sangiovanni-Vincentelli,	Univ. of California, Berkeley
Basar, Tamer	Univ. of Illinois at Urbana-	Alberto	·
	Champaign	Bicchi, Antonio	Univ. of Pisa
17:40		17:20	
	Stimation, and Control of Hidden	Computation of Observability Regi	ions for Discrete Time Hybrid
Markov Chains, 1098	Surfation, and Control of Flidgett	Systems, 1153	ons for Discrete-Time Hybrid
Baras, John S.	Univ. of Maryland	Ferrari-Trecate, Giancarlo	Inst. NATIONAL DE
Tan, Xiaobo	Univ. of Maryland	renali-frecate, Glancano	RECHERCHE EN
Xi, Wei	Univ. of Maryland		INFORMATIQUE ET EN
	Only. of Maryland		AUTOMATIQUE
18:00		Gati, Mehdi	REUNAULT S.A.S
	nel Assignments for TD-SCDMA	•	REGIVACET G.A.G
Systems, 1104		17:40	
Xiao, Yang	Northern Jiaotong Univ.	Observability for Hybrid Systems,	
Lu, Lingyun	Northern Jiaotong Univ.	Balluchi, Andrea	PARADES G.E.I.E.
Habermann, Joachim	Univ. of Applied Sciences	Benvenuti, Luca	Univ. di Roma
	Giessen-Friedberg	Di Benedetto, M. Domenica	Univ. of L'Aquila
18:20		Sangiovanni-vincentelli,	Univ. of California at Berkeley
Stability of Networked Control	Systems Based on Switched	Alberto	
Technique, 1110	•	18:00	
Liu, Yuzhong	Chinese Acad. of	What Is the Finiteness Conjecture	for Linear Continuous Time
,	Sciences;Shenyang Normal Univ.	Inclusions ?, 1165	The second secon
Yu, Haibin	Chinese Acad, of Sciences	gurvits, Leonid	Los Alamos National Lab.
1 4, 1 4.511	Chinese Aloud: of Colonocs	•	Los Manios National Lab.
TuP04	Regency C	18:20	
Linear Systems III	Regular Session	Robust H_infinity Output Feedbac	
Chair: Keel, Lee H.	Tennessee State Univ.	Data Systems Via Jump System A	• • •
Co-Chair: Pugh, A. Clive		Yoneyama, Jun	Aoyama Gakuin Univ.
	Loughborough Univ.		
16:40		TuP06	Maui_Suite 2
Tracking of Random Reference	es: Random Sensitivity Function and	Networked Control Systems	Regular Session
Tracking Quality Indicators, 11		with Limited Communication	
Eun, Yongsoon	Univ. of Michigan	Chair: Antsaklis, Panos J.	Univ. of Notre Dame
1/ /			
Kabamba, Pierre T.	Univ. of Michigan	Co-Chair: Fu, Minyue	Univ. of Newcastle
Meerkov, Semyon M.		Co-Chair: Fu, Minyue	Univ. of Newcastle
Meerkov, Semyon M.	Univ. of Michigan	Co-Chair: Fu, Minyue	Univ. of Newcastle
Meerkov, Semyon M. 17:00	Univ. of Michigan Univ. of Michigan	Co-Chair: Fu, Minyue	Univ. of Newcastle
Meerkov, Semyon M. 17:00 Direct Computation of PID Con	Univ. of Michigan Univ. of Michigan Introllers, 1120	Co-Chair: Fu, Minyue	Univ. of Newcastle
Meerkov, Semyon M. 17:00	Univ. of Michigan Univ. of Michigan	Co-Chair: Fu, Minyue	Univ. of Newcastle

Infimum Data Rates for Stabilising Ma			trol with Neuro-AVR of Single
1176	Links of Matherine	Machine Infinite-Bus Power Syste	
Nair, Girish N.	Univ. of Melbourne	Yazdanpanah, M. J.	Tehran (
Dey, Subhrakanti	Univ. of Melbourne	Jalili-Kharaajoo, <b>M</b> ahdi	Tehran I
Evans, Robin J.	Univ. of Melbourne		
17:00		TuP08	Maui St
Robust Stability and Disturbance Atte	nuation Analysis of a Class of	Water Vehicles	Regular Ses
Networked Control Systems, 1182		Chair: Do, Duc	The Univ. of Western Aus
Lin, Hai	Univ. of Notre Dame	Co-Chair: Pascoal, Antonio	Inst. Superior Te
Zhai, Guisheng Fa	culty of Systems Engineering	M.	
Antsaklis, Panos J.	Univ. of Notre Dame	16:40	
17:20		Global Waypoint Tracking Contro	l of Underactuated Ships und
Lp Stability of Networked Control Syst	ems 1188	Relaxed Assumptions, 1244	,
	of California at Santa Barbara	Do, Duc	The Univ. of Western Aus
Nesic, Dragan	Univ. of Melbourne	Pan, Jie	The Univ. of Western Aust
<del>-</del>	Citiv. St Micibourne	17:00	
17:40			naturated Shine with Off Diago
Optimal Control of Networked System		Global Tracking Control of Under	actuated Ships with On-Diago
Communication: A Combined Heuristi	c Search and Convex	Terms, 1250	The Univ. of Western Aus
Optimization Approach, 1194		Do, Duc	
Lu, Lilei	Northeastern Univ.	Pan, Jie	The Univ. of Western Aus
Xie, Lihua	Nanyang Tech. Univ.	17:40	
Fu, Minyue	Univ. of Newcastle	Nonlinear Path Following with Ap	
18:00		Autonomous Underwater Vehicle	
Minimizing Down-Link Traffic in Netwo	orked Control Systems Via	Lapierre, Lionel	ISR - IST Lisbon, Por
Optimal Control Techniques, 1200	-	Soetanto, Didik	ISR - IST Lisbon, Port
Quevedo, Daniel E.	The Univ. of Newcastle	Pascoal, Antonio	ISR - IST Lisbon, Por
Goodwin, Graham C.	Univ. of Newcastle	18:00	
Welsh, James	Univ. of Newcastle	Adaptive Setpoint Control for Auto	onomous Underwater Vehicle
18:20		1262	
Stability Analysis of Network-Based C	conerative Resource	Cheah, C.C.	Nanyang Tech. I
Allocation Strategies, 1206	opporative resource	Sun, Yeow Cheng	Nanyang Tech. I
Gil, Alvaro	The Ohio State Univ.	18:20	,
Passino, Kevin	The Ohio State Univ.		vimmina Biominatia Babat Fi
Passillo, Nevill	The Onlo State Only.	Basic Motion Control of a Free-St	willining biominietic Robot Fi
TuP07	Regency Boardroom	yu, junzhi	Inst. of Automation Chi
Optimal Control III	Regular Session	y w, joiners	Acad. of Scie
Chair: Roberts, Peter D.	City Univ. London		, , , , , , , , , , , , , , , , , , , ,
Co-Chair: Rantzer, Anders	Lund Inst. of Tech.	TuP09	Maui St
•		Robust Estimation	Regular Ses
16:40 Two Dimonologal Apolysis of a Gradi	ant Mathad in Europian Sansa	Chair: Qu, Zhihua	Univ. of Central FI
Two-Dimensional Analysis of a Gradio	и ичетов т пипстоп Space	Co-Chair: Thein, May-Win	Univ. of New Hamp
Optimal Control Algorithm, 1212	Challant Lander	· · · · · ·	Only. Of New Hallip
Roberts, Peter D.	City Univ. London	16:40	
17:00		Robust Estimation and Control U.	sing Command-To-State
Duality between Cost and Density in 0	Optimal Control, 1218	Mapping, 1274	
Rantzer, Anders	Lund Inst. of Tech.	Qu, Zhihua	Univ. of Central FI
Hedlund, Sven	Lund Inst. of Tech.	17:00	
17:20		Robust Filtering by Fictitious Nois	ses. 1280
Solutions of the Optimal Feedback Co	ontrol Problem Using	Zhang, Huanshui	Shenzhen Graduate Scho
Hamiltonian Dynamics and Generatin			
Park, Chandeok	y runcuons, 1222 Univ. of Michigan	Zhang, David	The Hong Kong Pol.
	Univ. of Michigan	Wang, Wei	Dalian Univ. of
Scheeree Daniel	Only, or wholigall	Xie, Lihua	Nanyang Tech.
Scheeres, Daniel		·	ranyang room
17:40			
17:40 A Differential Dynamic Games Approa		17:20	
17:40 A Differential Dynamic Games Approa Clark, John M.C.	Imperial Coll. London	Robust Filtering for Linear Discre	
17:40 A Differential Dynamic Games Approa		Robust Filtering for Linear Discre Uncertainties: A Krein Space Est	imation Approach, 1285
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B.	Imperial Coll. London	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon	imation Approach, 1285 Samsung Electro
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00	Imperial Coll. London Imperial Coll. London	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est	imation Approach, 1285 Samsung Electro Agency for Def
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima.	Imperial Coll. London Imperial Coll. London	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang	imation Approach, 1285 Samsung Electr Agency for Def Develop
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima. Motion Simulator, 1232	Imperial Coll. London Imperial Coll. London  Trajectory for the Eclipse-II	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung	imation Approach, 1285 Samsung Electr Agency for Def Develop Changwon National
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima. Motion Simulator, 1232 Cho, Young Man	Imperial Coll. London Imperial Coll. London  Trajectory for the Eclipse-II  Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung Park, Jin Bae	imation Approach, 1285 Samsung Electr Agency for Del Develop Changwon National Yonsei
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima. Motion Simulator, 1232 Cho, Young Man Kim, Ik Kyu	Imperial Coll. London Imperial Coll. London  Trajectory for the Eclipse-II  Seoul National Univ. Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung Park, Jin Bae Jung, Soo Yul	imation Approach, 1285 Samsung Electr Agency for Del Develop Changwon National Yonsei Samsung Electr
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima Motion Simulator, 1232 Cho, Young Man Kim, Ik Kyu Kim, Hwa Soo	Imperial Coll. London Imperial Coll. London  Trajectory for the Eclipse-II  Seoul National Univ. Seoul National Univ. Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung Park, Jin Bae	imation Approach, 1285 Samsung Electric Agency for Def Develop Changwon National Yonsei Samsung Electri
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima Motion Simulator, 1232 Cho, Young Man Kim, Ik Kyu Kim, Hwa Soo kam, Min Seok	Imperial Coll. London Imperial Coll. London  I Trajectory for the Eclipse-II  Seoul National Univ. Seoul National Univ. Seoul National Univ. Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung Park, Jin Bae Jung, Soo Yul	imation Approach, 1285 Samsung Electro Agency for Def Develop Changwon National Yonsei Samsung Electro
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima. Motion Simulator, 1232 Cho, Young Man Kim, Ik Kyu Kim, Hwa Soo kam, Min Seok Hur, Su Mi	Imperial Coll. London Imperial Coll. London  I Trajectory for the Eclipse-II  Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang  Yoon, Tae-Sung Park, Jin Bae Jung, Soo Yul Seo, Joong Eon 17:40	imation Approach, 1285 Samsung Electro Agency for Def Developi Changwon National I Yonsei I Samsung Electro Samsung Electro
17:40 A Differential Dynamic Games Approa Clark, John M.C. Vinter, Richard B. 18:00 Fast Design of the QP-Based Optima Motion Simulator, 1232 Cho, Young Man Kim, Ik Kyu Kim, Hwa Soo kam, Min Seok	Imperial Coll. London Imperial Coll. London  I Trajectory for the Eclipse-II  Seoul National Univ. Seoul National Univ. Seoul National Univ. Seoul National Univ.	Robust Filtering for Linear Discre Uncertainties: A Krein Space Est Lee, Tae Hoon Ra, Won-sang Yoon, Tae-Sung Park, Jin Bae Jung, Soo Yul Seo, Joong Eon	imation Approach, 1285 Samsung Electro Agency for Defo Developi Changwon National I Yonsei I Samsung Electro Samsung Electro

18:00		17:40	
	pace Disturbance Observer, 1297	An Algorithm for Linearization	of Discrete-Time Systems Via
Lee, Seung Hi	Samsung Adv. Inst. of Tech.	Restricted Dynamic Feedback	
Chung, Chung Choo	Hanyang Univ.	Lee, Hong-Gi	Chung-Ang Univ.
18:20		Arapostathis, Ari	The Univ. of Texas at Austin
	bserver System for Robust State	Marcus, Steven I.	Univ. of Maryland
Estimation of Multirate Systems		18:00	
Thein, May-Win	Univ. of New Hampshire		Nonlinear Input-Output Descrete-
-		Time Systems, 1368	
TuP10	Guest Room 350	Nomm, Sven	Inst. of Cybernetics at TTU
Distributed Parameter	Regular Session	18:20	
Systems III		On Discrete-Time Output Fee	dback Sliding Mode-Like Control for
Chair: Morris, Kirsten A.	Univ. of Waterloo	Nonminimum Phase Systems,	, 1374
Co-Chair: Jovanovic, Mihaik	Univ. of California, Santa Barbara	Lai, Nai One	Univ. of Leicester
16:40		Edwards, Christopher	Univ. of Leicester
Boundary Control of a Nonlinea		Spurgeon, Sarah K.	Univ. of Leicester
Dunbar, William B.	California Inst. of Tech.		
Petit, Nicolas	Ec. des Mines de Paris	TuP12	Maui Suite 5
Rouchon, Pierre	Ec. des Mines de Paris	Filtering II	Regular Session
Martin, Philippe	Ec. des Mines de Paris	Chair: Sun, Kunpeng	Univ. of California at Berkeley
17:00		Co-Chair: Shafai, Bahram	Northeastern Univ.
Accurate Approximation of Inva		16:40	
Abstract Boundary Control Syst			sign Via Convex Optimization, 1380
Cheng, Ada	Kettering Univ.	Sun, Kunpeng	Univ. of California at Berkeley
Morris, Kirsten A.	Univ. of Waterloo	Packard, Andrew K.	Univ. of California at Berkeley
17:20		17:00	
	Stabilization of Nonlinear Abstract		tended Kalman Filter Based State
Differential Equations, 1321			llinear Dynamic Systems, 1386
Zuyev, Alexander	Inst. of Applied Mathematics &	Zhai, Tongyan	Marquette Univ.
	Mechanics	Ruan, Huawei	Marquette Univ.
17:40		Yaz, Edwin	Marquette Univ.
Design of Surface Shape Contr	ol for Large Two-Dimensional	Yaz, Yvonne	Carthage Coll.
Array, 1327		17:20	
Stein, Gunter	Honeywell Inc.	Polynomial Filtering for Stoche	astic Systems with Markovian
Gorinevsky, Dimitry	Honeywell Inc.	Switching Coefficients, 1392	
18:00		Germani, Alfredo	Univ. of L'Aquila
	ack Distributed Control of Systems	Manes, Costanzo	Univ. of L'Aquila
on Lattices, 1333		Palumbo, Pasquale	Istituto di Analisi dei Sistemi ed Informatica IASI-CNR
Jovanovic, Mihailo	Univ. of California, Santa Barbara		IIIIOIIIIatica IASI-CIVIC
Bamieh, Bassam	Univ. of California at Santa	17:40	
	Barbara	Unit Circle, 1398	ochastic Realization with Zeros on the
18:20		Ferrante, Augusto	Univ. Degli Studi Padova
	cy Responses for a Class of Infinite	Picci, Giorgio	Univ. di Padova
Dimensional Systems, 1339 Jovanovic, Mihailo	Links of California Couts Darbors	Pinzoni, Stefano	Inst. di Ingegneria Gestionale
Bamieh, Bassam	Univ. of California, Santa Barbara Univ. of California at Santa	18:00	,
Daimen, Dassam	Barbara		Diffusion Systems with Delayed
	Daibaia	Observations, 1404	Dillusion Systems with Delayed
TuP11	Guest Room 351	Calzolari, Antonella	Univ. di Roma-Tor Vergata
Discrete-Time Nonlinear	Regular Session	Florchinger, Patrick A.	Univ. of Metz
Systems		Nappo, Giovanna	Univ. di Roma
Chair: Piccoli, Benedetto	I.A.CC.N.R.	18:20	
Co-Chair: Arapostathis, Ari	The Univ. of Texas at Austin		Time-Discretised State Estimation
16:40		Via Clark Transformations, 14	
Quantization of the Rolling Body	v Problem with Application to	Malcolm, William P.	The Univ. of Adelaide
Motion Planning, 1345	, , , os.om man Application to	Elliott, Robert J.	Univ. of Calgary
Piccoli, Benedetto	I.A.CC.N.R.	van der Hoek, John	Univ. of Adelaide
Chitour, Yacine	Lab. D'analyse Numerique		
Marigo, Alessia	I.A.CC.N.R.	TuP13	Guest Room 450
17:00		Predictive Control for	Regular Session
	crete-Time Hamiltonian Systems,	Nonlinear Systems	
1351		Chair: Parisini, Thomas	Univ. of Trieste
Vaidya, Umesh	Univ. of California Santa Barbara	Co-Chair: Allgower, Frank	Univ. of Stuttgart
Mezic, Igor	Univ. of California, Santa Barbara	16:40	
17:20		Nominally Robust Model Pred	lictive Control with State Constraints,
	crete-Time Control Systems, 1357	1413	
Hamzi, Boumediene	Univ. of California at Davis	Grimm, Gene	Univ. of California at Santa Barbara
Tall, Issa Amadou	Univ. of California, Davis	Messina, Michael J.	Univ. of California at Santa Barbara
	·	Teel, Andrew R.	Univ. of California at Santa Barbara
		Tuna, Sezai E.	Univ. of California at Santa Barbara

17:00		TuPPI	Grand Promenade
Stability of Nonlinear Mode	I Predictive Control in the Presence of	SIAM Poster Papers III Po	ster/Interactive Paper Session Univ. of New Mexico
Errors Due to Numerical Or		Chair: Abdallah, Chaouki T.	Univ. of New Mexico
Diehl, Moritz	Univ. of Heidelberg	16:40	
Findeisen, Rolf	Univ. of Stuttgart Univ. of Stuttgart	Zero-Sum Semí-Markov Games*	Pol. Wrocławska
Allgower, Frank Bock, Georg	Univ. of Heidelberg	Jaskiewicz, Anna	POI. WIOCIAWSKA
Schloeder, Johannes	Univ. of Heidelberg	CALL THE CONTRACT OF THE	Live as Contains Madula
•	on. or richabong	Immersion of Nonlinear Systems into	Linear Systems Modulo
17:20 Stability Conditions for Obs	server Based Output Feedback	Output Injection, 1476 Jouan, Philippe	Univ. de Rouen
	r Model Predictive Control, 1425	зоцап, гліірре	Oliv. de Nodeli
Findeisen, Rolf	Univ. of Stuttgart	Spreading Control with Speed Cons	rainte 1482
Imsland, Lars	Norwegian Univ. of Science and Tech.	Aubin, Jean-Pierre	Univ. Paris Ix - Dauphine
Allgower, Frank	Univ. of Stuttgart	Kassara, Khalid	Univ. of Casablanca 1
Foss, Bjarne A.	Norwegian Univ. of Science & Tech.		
17:40		Controllability of the Semilinear Para	bolic Equation Governed by a
	le Model Based Control Scheme for	Multiplicative Control in the Reaction	Term: A Qualitative
Nonlinear Systems, 1431		Approach, 1487	
Previdi, Fabio	Univ. of Bergamo	Khapalov, Alexander	Washington State Univ.
Sacone, Simona	Univ. of Genova		
Parisini, Thomas	Univ. of Trieste	Maximum Principle of Optimal Contr	ol for Degnerate Quasi-Linear
18:00	stanting the Origin ( to 15 )	Elliptic Equations*	-
	ducing the Computational Burden of a	Lou, Hongwei	Fudan Univ.
MPC Min Max Controller, 1 Alamo, Teodoro	1433 Univ. de Sevilla		
Muńoz de la Peńa. Dav		An Optimal Control Problem Govern	ed by Quasi-Linear Variational
Camacho, Eduardo F.	Univ. of Sevilla	Inequalities*	
18:20	3,,,,,	Lou, Hongwei	Fudan Univ.
Approximations of Closed-	Loon Minimay MPC 1438		
Löfberg, Johan	ETH, Zürich	Stabilization of LPV Systems: State and Duality, 1492	Feedback, State Estimation,
TuP14	Guest Room 451	Blanchini, Franco	Univ. degli Studi di Udine
Fault Detection and	Regular Session	Miani, Stefano	Univ. degli Studi di Udine
Accomodation II			
Chair: Dion, Jean-Miche	el URA CNRS	TuES1	Maui Suite 3
Co-Chair: Ding, Steven	X. Lausitz Univ. of Applied Sciences	Honeywell Industry Sponsor Session	Evening Session
16:40	ania in Linnay Chrystywad Cyntama with		
Disturbances, 1443	osis in Linear Structured Systems with	TuES2	Maui Suite 4
Commault, Christian.	Lab. d'Automatique de Grenoble	National Instruments Industry	Evening Session
Dion, Jean-Michel	Lab. d'Automatique de Grenoble	Sponsor Session	
17:00		WeDPI	Monarchy Ballroom
	es in the Frequency Domain, 1449	WeDPL Plenary Talk: Katsuhita Furuta	Plenary Session
Fong, Kin Fui			
Loh, Ai-Poh			
	National Univ. of Singapore National Univ. of Singapore	Chair: Abdallah, Chaouki T.	Univ. of New Mexico
	National Univ. of Singapore	Chair: Abdallah, Chaouki T. 08:00	Univ. of New Mexico
17:20	National Univ. of Singapore National Univ. of Singapore	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super N	Univ. of New Mexico
17:20	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super M Adaptive Mechatronics, 1498	Univ. of New Mexico
17:20 Sliding Mode Observers fo Actuator and Sensor Fault Tan, Chee Pin	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455 Monash Univ. Malaysia	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super N	Univ. of New Mexico
17:20 Sliding Mode Observers fo Actuator and Sensor Fault	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super M Adaptive Mechatronics, 1498	Univ. of New Mexico
17:20 Sliding Mode Observers fo Actuator and Sensor Fault Tan, Chee Pin	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455 Monash Univ. Malaysia	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super N Adaptive Mechatronics, 1498 Furuta, Katsuhisa	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous ss, 1455 Monash Univ. Malaysia Univ. of Leicester H_2/H_inf Setting, 1461	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super N Adaptive Mechatronics, 1498 Furuta, Katsuhisa WeA01	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous ss, 1455 Monash Univ. Malaysia Univ. of Leicester H_2/H_inf Setting, 1461	Chair: Abdallah, Chaouki T. 08:00 Control of Pendulum: From Super N Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control	Univ. of New Mexico lechano-Systems to Human Tokyo Denki Unversity Monarchy Ballroom Regular Session
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad- K. N. Toosi Univ. of Tech.	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E.	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamn Javad Nikoukhah, Ramine	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad- K. N. Toosi Univ. of Tech.  INRIA, Rocquencourt	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto  Univ. of Maryland
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad- K. N. Toosi Univ. of Tech.	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad- K. N. Toosi Univ. of Tech.  INRIA, Rocquencourt Uinv. of Wisconsin-Platteville	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto  Univ. of Maryland  em, 1508  Yale Univ.  Yale Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designation	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad- K. N. Toosi Univ. of Tech.  INRIA, Rocquencourt	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto  Univ. of Maryland  em, 1508  Yale Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designation	National Univ. of Singapore National Univ. of Singapore Proceed Reconstruction of Simultaneous Sts. 1455  Monash Univ. Malaysia Univ. of Leicester Which Head Reconstruction of Simultaneous Sts. 1455  Monash Univ. Malaysia Univ. of Leicester Which Reconstruction of Tech.  INRIA, Rocquencourt Uinv. of Wisconsin-Platteville Sign for LTI Systems with Time Delays,	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki University  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designation	National Univ. of Singapore National Univ. of Singapore Proceedings of Reconstruction of Simultaneous National Univ. Malaysia Univ. of Leicester National Univ. of Tech. INRIA, Rocquencourt Uinv. of Wisconsin-Platteville National Univ. Of Wisconsin-Platteville National Univ. Of Wisconsin-Platteville National Univ. Of Singapore National Univ. of Leicester National Univ. of Leicester National Univ. of Leicester National Univ. of Univ. of Tech. National Univ. of Univ. of Tech. National Univ. of Wisconsin-Platteville National Univ. of Univ.	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Role	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki University  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designation, Maiying Ding, Steven X.	National Univ. of Singapore National Univ. of Singapore National Univ. of Singapore National Univ. of Singapore National Univ. Malaysia Univ. of Leicester NH_2/H_inf Setting, 1461 NRIA, Rocquencourt Uinv. of Wisconsin-Platteville Nign for LTI Systems with Time Delays, Shandong Univ. Univ. of Duisburg	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Rol. 1514	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamn Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Desi 1467 Zhong, Maiying Ding, Steven X. Lam, James	National Univ. of Singapore National Univ. of Singapore Par Reconstruction of Simultaneous Sis, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad-  INRIA, Rocquencourt Uinv. of Wisconsin-Platteville Sign for LTI Systems with Time Delays, Univ. of Duisburg Univ. of Hong Kong	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Rol 1514 Rodriguez-Angeles, Alejandro	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.  pots Via Estimated Feedback,  Mexican Petroleum Inst.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designation of Sensor Maiying Ding, Steven X. Lam, James Zhang, Chenghui	National Univ. of Singapore National Univ. of Singapore National Univ. of Singapore National Univ. of Singapore National Univ. Malaysia Univ. of Leicester NH_2/H_inf Setting, 1461 NRIA, Rocquencourt Uinv. of Wisconsin-Platteville Nign for LTI Systems with Time Delays, Shandong Univ. Univ. of Duisburg	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super N. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Rol 1514 Rodriguez-Angeles, Alejandro Nijmeijer, Hendrik	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Desi 1467 Zhong, Maiying Ding, Steven X. Lam, James Zhang, Chenghui 18:20	National Univ. of Singapore National Univ. of Singapore or Reconstruction of Simultaneous is, 1455  Monash Univ. Malaysia Univ. of Leicester  IH_2/H_inf Setting, 1461 nad-  INRIA, Rocquencourt Uinv. of Wisconsin-Platteville ign for LTI Systems with Time Delays,  Shandong Univ. Univ. of Duisburg Univ. of Hong Kong Shandong Univ.	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super IV Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Proble Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Cooperative Synchronization of Rol 1514 Rodriguez-Angeles, Alejandro Nijmeijer, Hendrik  10:00	Univ. of New Mexico  dechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.  pots Via Estimated Feedback,  Mexican Petroleum Inst. Eindhoven Univ. of Tech.
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designates of Tabong, Maiying Ding, Steven X. Lam, James Zhang, Chenghui 18:20 A Self-Repairing Control Stephen Steven Stephen Steven Stephen Steven Stephen Steven Stephen Stephe	National Univ. of Singapore National Univ. of Singapore Par Reconstruction of Simultaneous Sis, 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 nad-  INRIA, Rocquencourt Uinv. of Wisconsin-Platteville Sign for LTI Systems with Time Delays, Univ. of Duisburg Univ. of Hong Kong	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super M. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Problet Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Rol 1514 Rodriguez-Angeles, Alejandro Nijmeijer, Hendrik  10:00 Control of a Team of Car-Like Robo	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom  Regular Session  Univ. of Toronto  Univ. of Maryland  em, 1508  Yale Univ.  Yale Univ.  Yale Univ.  Australian National Univ.  bots Via Estimated Feedback,  Mexican Petroleum Inst. Eindhoven Univ. of Tech.
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17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designates of Tabong, Maiying Ding, Steven X. Lam, James Zhang, Chenghui 18:20 A Self-Repairing Control Stephen Steven Stephen Steven Stephen Steven Stephen Steven Stephen Stephe	National Univ. of Singapore National Univ. of Singapore Par Reconstruction of Simultaneous Sts. 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 INRIA, Rocquencourt Uinv. of Wisconsin-Platteville Sign for LTI Systems with Time Delays, Shandong Univ. Univ. of Duisburg Univ. of Hong Kong Shandong Univ. System for Plants with Faulty Actuators,	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super IV Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Probletin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Role 1514 Rodriguez-Angeles, Alejandro Nijmeijer, Hendrik  10:00 Control of a Team of Car-Like Robot Belta, Calin Pereira, Guilherme A. S.	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.  oots Via Estimated Feedback, Mexican Petroleum Inst. Eindhoven Univ. of Tech.  its Using Abstractions, 1520 Univ. of Pennsylvania Univ. Federal de Minas Gerais
17:20 Sliding Mode Observers for Actuator and Sensor Fault Tan, Chee Pin Edwards, Christopher 17:40 Fault Detection in a Mixed Khosrwojerdi, Mohamm Javad Nikoukhah, Ramine Safari-Shad, Nader 18:00 Fault Detection Filter Designate Detection Filter Designate Detection Filter Designate Detection Steven X. Lam, James Zhang, Chenghui 18:20 A Self-Repairing Control Stat73	National Univ. of Singapore National Univ. of Singapore Par Reconstruction of Simultaneous Sts. 1455  Monash Univ. Malaysia Univ. of Leicester  H_2/H_inf Setting, 1461 INRIA, Rocquencourt Uinv. of Wisconsin-Platteville Sign for LTI Systems with Time Delays, Shandong Univ. Univ. of Duisburg Univ. of Hong Kong Shandong Univ. System for Plants with Faulty Actuators,	Chair: Abdallah, Chaouki T.  08:00 Control of Pendulum: From Super M. Adaptive Mechatronics, 1498 Furuta, Katsuhisa  WeA01 Cooperative Control Chair: Broucke, Mireille E. Co-Chair: Baras, John S.  09:20 The Multi-Agent Rendezvous Problet Lin, Jie Morse, A. Stephen Anderson, Brian D.O.  09:40 Coopeartive Synchronization of Role 1514 Rodriguez-Angeles, Alejandro Nijmeijer, Hendrik  10:00 Control of a Team of Car-Like Robol Belta, Calin	Univ. of New Mexico  lechano-Systems to Human  Tokyo Denki Unversity  Monarchy Ballroom Regular Session Univ. of Toronto Univ. of Maryland  em, 1508  Yale Univ. Yale Univ. Australian National Univ.  oots Via Estimated Feedback, Mexican Petroleum Inst. Eindhoven Univ. of Tech.  lts Using Abstractions, 1520 Univ. of Pennsylvania

10:20		10:00	
A Framework for Networked Motion	Control 1526	Emergence of Critical Rates in Mul	tiple Access Network Control
	Fac. Engenharia Univ. Do Porto	Schemes., 1592	upio riccoca recirrorit contror
	Porto Univ. Inst. For Systems & Robotics	Barany, Ernest J. Krupa, Maciej	New Mexico State Univ. New Mexico State Univ.
10:40	,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,,	10:20	
Decentralized Control of Autonomous Baras, John S.	us Vehicles, 1532 Univ. of Maryland	Stochastic Control Techniques for Multicast, 1598	Throughput Optimal Wireless
Tan, Xiaobo	Univ. of Maryland	Chaporkar, Prasanna	Student
Hovareshti, Pedram	Univ. of Maryland	Sarkar, Saswati	Univ. of Pennsylvania
11:00		10:40	•
Reconfiguration of Identical Vehicles	s in 3D. 1538	New Scheduling Policies for Multic	lass Queueing Networks:
Broucke, Mireille E.	Univ. of Toronto	Applications to Peer-To-Peer System Paschalidis, Ioannis Ch.	
WeA02 Trends in Advanced Nonlinear	Regency A Invited Session	Su, Chang Caramanis, Michael C.	Boston Univ. Boston Univ.
Control	Del Heir	11:00	
Chair: Jiang, Zhong Ping	Pol. Univ.	Robust Packet Scheduling in Wirel	
Co-Chair: Astolfi, Alessandro Organizer: Jiang, Zhong Ping	Imperial Coll. Pol. Univ.	Fu, Zhenghua	UCLA
Organizer: Jiang, Zhong Ping Organizer: Astolfi, Alessandro	Imperial Coll.	MENG, XIAOQIAO	Univ. of California, Los Angeles
	impenar coll.	Yang, Hao Lu, Songwu	UCLA
09:20 On Global Output Feedback Stabiliz Systems (I), 1544	ation of Uncertain Nonlinear	Lu, Songwu	Univ. of Illinois at Urbana- Champaign
Praly, Laurent Jiang, Zhong Ping	Ec. des Mines Pol. Univ.	WeA04 Behavioral System Theory	Regency C Invited Session
	ı ol. Oliv.	Chair: Rapisarda, Paolo	Univ. of Maastricht
09:40 Output-Input Stability and Feedback Nonlinear Control Systems (I), 1550		Co-Chair: Polderman, Jan Willem	Univ. of Twente
Liberzon, Daniel	Univ. of Illinois at Urbana-	Organizer: Rapisarda, Paolo	Univ. of Maastricht
2.00.2011, 20.1101	Champaign	09:20	
10:00		On Dissipative SISO Systems: A B	ehavioral Approach (I), 1616
A Matrosov Theorem with an Applic	ation to Model Reference	Pendharkar, Ishan	Indian Inst. of Tech. Bombay,
Adaptive Control Via Approximate D			India.
Nesic, Dragan	Univ. of Melbourne	Pillai, Harish	Indian Inst. of Tech. Bombay
Teel, Andrew R.	Univ. of California at Santa	09:40	_
	Barbara	A Behavioral Framework for Reed-	Solomon Decodina through
10:20		Multiplicative Bivariate Interpolation	
Global Complete Observability and	Output-To-State Stability Imply	Kuijper, Margreta	Univ. of Melbourne
the Existence of a Globally Converg		Polderman, Jan Willem	Univ. of Twente
Astolfi, Alessandro	Imperial Coll.	10:00	
Praly, Laurent	Ec. des Mines	A Note on the Driving Variable Rea	alization of Behaviors (I), 1627
10:40		Valcher, Maria Elena	Univ. Di Padova
Stabilization of Periodic Orbits in a V	Vedge Billiard (I), 1568	10:20	
Sepulchre, Rodolphe J.	Univ. de Liege	Balanced State Representations from	om Higher-Order Differential
Gerard, Manuel	Univ. de Liege	Equation Models (I), 1633	
11:00		Willems, Jan C.	Univ. of Leuven
Transforming a Single-Input System	to a P-Normal Form Via	Rapisarda, Paolo	Univ. of Maastricht
Feedback (I), 1574		10:40	
Respondek, Witold		The Canonical Controller and Its R	
	Appliquees	Willems, Jan C.	Univ. of Leuven, Belgium
WoA03	D-11-20-D	Belur, Madhu	Univ. of Groningen, NL
WeA03	Regency B	Trentelman, Harry L.	Univ. of Groningen, NL
Communication Networks:	Regular Session	Julius, Agung	Univ. of Twente, NL
Scheduling and Quality of Service		11:00	
Chair: Sarkar, Saswati	Univ. of Pennsylvania	Some Remarks on the Dissipativity	r от Uncontrollable Systems (I),
Co-Chair: Mascolo, Saverio	Pol. di Bari	1645 Camlibel, Kanat	Tilburg Univ.
09:20	. 31. 41 241	Belur, Madhu	Univ. of Groningen
os.20 Sensitivity of Optimal Quality of Sen	vice to Bandwidth and Buffer	Willems, Jan C.	Univ. of Leuven
Prices, 1580	.so to bandwidth and bandi		5, 5. <u>254</u> 4611
Jin, Nan	Univ. of California, Irvine	WeA05	Maui Suite 1
Jordan, Scott	Univ. of California, Irvine	Stability of Hybrid Systems	Regular Session
09:40	•	Chair: Lygeros, John	Univ. of Patras
A Control Theoretic Approach for Su	pporting Quality of Service in	Co-Chair: Camlibel, Kanat	Tilburg Univ.
IEEE 802.11e WLANs with HCF, 15			
Grieco, Luigi Alfredo	Pol. Di Bari		
Boggia, Gennaro	Pol. di Bari		
Mascolo, Saverio	Pol. di Bari		
Camarda, Pietro	Pol. di Bari		
Camarda, Pietro	Pol. di Bari		

09:20		11:00	
Stability and Controllability of Bil			r a Parameter Affine Linearizable
Complementarity Systems, 1651		System, 1711	Cabaal of Flactuical Facinessian
Camlibel, Kanat Heemels, Maurice	Tilburg Univ. Eindhoven Univ. of Tech.	Yu, Kyung Tak	School of Electrical Engineering, Seoul National Univ.
Schumacher, Hans	Tilburg Univ.	Jo, Nam H.	Soongsil Univ.
09:40	Thousand a series	Seo, Jin H.	Seoul National Univ.
New Results on the Quadratic S	tabilization of Switched Linear		
Systems, 1657	tabinzation of Gwitched Einear	WeA07	Regency Boardroom
Ji, Zhijian	Peking Univ.	Optimal Control IV	Regular Session
Wang, Long	Peking Univ.	Chair: Yu, Jen-te	Rockwell Scientific
Xie, Guangming	Peking Univ.	Co-Chair: Liu, Kang-Zhi	Chiba Univ.
10:00		09:20	
Generalized Practical Stability A	nalysis of Discontinuous		size Scaling Problem in Sequential
Dynamical Systems, 1663		Algorithms for Computing Optin 1717	nal Static Output Feedback Gains,.
Zhai, Guisheng	Wakayama Univ.	Yu, Jen-te	Rockwell Scientific
Michel, Anthony N.	Univ. of Notre Dame		Nockwell Scientific
10:20		09:40 A Simple Derivation of ARE Sol	lutions to the Standard H inf
	us Dynamical Systems Determined	Control Problem Based on LMI	
by Semigroups, 1669	Univ. of Notre Dame	Liu, Kang-Zhi	Chiba Univ.
Michel, Anthony N. Sun, Ye	Univ. of Notre Dame	He, Rong	Chiba Univ.
•	Cliv. Of Notic Bullic	10:00	
10:40	portain Hybrid Systems with	Time-Optimal Control of a Swin	a 1729
Approximate Stabilisation of Un- Controllable Transitions, 1675	certain Hybrid Systems with	Kulkarni, Jayant	Cornell Univ.
Gao, Yan	School of Management, Univ. of	10:20	
<b>200,</b> 100	Shanghai for Science and Tech.		ntinuous Shortest-Path: Application
Lygeros, John	Univ. of Cambridge	to Minimum-Risk Path Planning	
Quincampoix, Marc	Univ. de Bretagne Occidentalle	Hespanha, Joao P.	
Seube, Nicolas	ENSIETA	Kim, Jongrae	Univ. of California, Santa Barbara
W- 40C	Maril Criba 2	10:40	
WeA06 Adaptive Output Feedback	Maui Suite 2 Regular Session		onal Optimization Problems, 1741
Systems	Regulai Gession	Salapaka, Srinivasa	Massachusetts Inst. of Tech.
Chair: Tao, Gang	Univ. of Virginia	Khalak, Asif	Alpahtech, Inc.
Co-Chair: Pagilla, Prabhakar		Dahleh, Munther A	Massachusetts Inst. of Tech.
R.		11:00	navilan Otata Affina Function 4747
09:20		Kogiso, Kiminao	cewise State Affine Function, 1747 Osaka Univ.
Adaptive Output Feedback Actu	ator Failure Compensation for a	Hirata, Kenji	Osaka Univ.
Class of State-Dependent Nonli		· ····································	
Tang, Xidong	Univ. of Virginia	WeA08	Maui Suite 3
Tao, Gang	Univ. of Virginia	Automotive and Vehicle	Regular Session
Joshi, Suresh M.	NASA Langley Res. Ctr.	Control	
09:40		Chair: Peterson, Katherine	Univ. of Michigan
	er Design for a Class of Nonlinear	Co-Chair: Ye, Zhengmao	Wayne State Univ.
Systems, 1687 Zhu, Yongliang	Oklahoma State Univ.	09:20	
Pagilla, Prabhakar R.	Oklahoma State Univ.	Rendering the Electromechanic	cal Valve Actuator Globally
10:00	Grandina Glato Gim.	Asymptotically Stable, 1753	I lake of Michigan
	Frequency Selective Feedback,	Peterson, Katherine Stefanopoulou, Anna G.	Univ. of Michigan Univ. of Michigan
1693	Trequency delective recuback,	• •	Only. Of Wildingan
Tan, Alfred CH	Univ. of Southampton	09:40	f Evolution for a Simplified
Meurers, Thomas	Univ. of Southampton	Polytopic Controller Design and Nonlinear Engine Vehicle Dyna	
Veres, Sandor	School of Engineering Sciences	Uthaichana, Kasemsak	Purdue Univ.
Aglietti, Guglielmo	Univ. of Southampton	DeCarlo, Raymond A.	Purdue Univ.
Rogers, Eric	Univ. of Southampton	Corless, Martin J.	Purdue Univ.
10:20		Hopka, Michael	The Ohio State Univ.
	Feedback Control Via Input/Output	10:00	•
Inversion, 1699	Dont of ACE Virginia Took		llowing Control of Wheeled Robots,
Hovakimyan, Naira Lavretsky, Eugene	Dept of AOE, Virginia Tech. The Boeing Co.	1765	
Calise, Anthony J.	Georgia Inst. of Tech.	Soetanto, Didik	ISR-IST Lisbon, Portugal
Sattigeri, Ramachandra	Georgia Inst. of Tech.	Lapierre, Lionel	ISR-IST Lisbon, Portugal
10:40		Pascoal, Antonio	ISR-IST Lisbon, Portugal
Output Feedback Control of an	Uncertain System Using an		•
Adaptive Observer, 1705			
Yang, Bong-jun	Georgia Inst. of Tech.		
Hovakimyan, Naira	Virginia Tech.		
Calise, Anthony J.	Georgia Inst. of Tech.		

10:20		10:00	
Torque Generation Modeling for		A Classification of All Solutions of t	
Falcone, Paolo De Gennaro, Maria Carmela	Univ. degli Studi del Sannio Univ. degli Studi del Sannio	for Infinite-Dimensional Systems, 1 Iftime, Orest V.	Univ. of Groningen
Fiengo, Giovanni	Univ. degli Studi del Sannio	Curtain, Ruth F.	Univ. of Groningen
Santini, Stefania	Univ. di Napoli Federico II	Zwart, Hans J.	Univ. of Twente
Glielmo, Luigi	Univ. degli Studi del Sannio	10:20	
Langthaler, Peter	Univ. of Linz Johannes Kepler	Adjoint Analysis and Control Oppor	rtunities in a 2D .let 1842
10:40		Cerviño, Laura I.	UC San Diego
Limit Systems and Attractivity for	Time-Varving Systems with	Bewley, Thomas R.	UC San Diego
Applications to Nonholonome Sy	stems, 1777	10:40	
Lee, Ti-Chung	Ming Hsin Univ. of Science and	On Steady Solutions of a PDE Mod	del of Compressor Stall, 1848
•	Tech.	Hagen, Gregory	United Tech. Res. Center
11:00	•	Mehta, Prashant G.	United Tech. Res. Center
	Aftertreatment and Fuel Economy	11:00	
of GDI Engine Systems, 1783		Spectral Factorization by Symmetr	ic Extraction for a Vibrating
Ye, Zhengmao	Wayne State Univ.	String with Low Damping, 1854	J
Li, Liguang	Shanghai Jiao Tong Univ.	Callier, Frank M.	Univ. of Namur (FUNDP)
		Winkin, Joseph J.	Univ. of Namur (FUNDP)
WeA09	Maui Suite 4		
Linear Robust Control	Regular Session Univ. of Waterloo	WeA11	Guest Room 351
Chair: Miller, Daniel E.	North Carolina State Univ.	Computational and Numerical	Invited Session
Co-Chair: Smith, Ralph C.	North Carolina State Only.	Issues in Systems and Control	Dies Univ
09:20	inerate Time Cons. 1790	Chair: Antoulas, Athanasios C.	Rice Univ.
Mixed H_2/H_inf Control: The Di Muradore, Riccardo	screte-Time Case, 1789 Univ. of Padova	Co-Chair: Varga, Andras	German Aerospace Center
Picci, Giorgio	Univ. di Padova	Organizer: Antoulas,	Rice Univ.
	Jiiv. di i ddova	Athanasios C.	
09:40	Defermence in Continuous Time	Organizer: Varga, Andras	German Aerospace Center
	Performance in Continuous-Time	09:20	
Periodic Systems, 1795 Zhou, Jun	Kyoto Univ.	On Computing the L2-Induced Nor	rm of Finite-Horizon Systems (I)
Hagiwara, Tomomichi	Kyoto Univ.	1860	in or i and i ronzon cycleme (i),
Araki, Mituhiko	Kyoto Univ.	Bamieh, Bassam	Univ. of California at Santa
10:00			Barbara
= = =	agnetostrictive Transducer, 1801	09:40	
Smith, Ralph C.	North Carolina State Univ.	Dynamical Systems for Principal a	nd Minor Component Analysis
Nealis, James	North Carolina State Univ.	(I). 1863	
10:20		Manton, Jonathan H.	Univ. of Melbourne
	for a Compact Set of Plants, 1807	Helmke, Uwe R.	Univ. of Wuerzburg
Miller, Daniel E.	Univ. of Waterloo	Mareels, Iven	The Univ. of Melbourne
10:40		10:00	
	Stability in Non-Sequential MIMO	Balanced Model Reduction of Pas	
QFT, 1813		Sorensen, Dan	Rice Univ.
Kerr, Murray	The Univ. of Queensland	10:20	
Jayasuriya, Suhada	Texas A&M Univ.	An H2 Error Expression for the La	
11:00		Gugercin, Serkan	Virginia Tech.
Analysis and Synthesis of Model	Reference ILQ Servo System	Antoulas, Athanasios C.	Rice Univ.
Using Robust L_infinity Performa	ance Measure for a Fixed Input,	10:40	
1818		Reliable Algorithms for Computing	Minimal Dynamic Covers (I),
Kunimatsu, Sadaaki	Osaka Univ.	1873	
Fujii, Takao	Osaka Univ.	Varga, Andras	German Aerospace Center
M- 440	Coast Brow 250	11:00	
WeA10	Guest Room 350	Recursive Blocked Algorithms and	
Distributed Parameter	Regular Session	Solving Sylvester-Type Equations	
Systems IV Chair: Hagen, Gregory	United Tech. Res. Center	Jonsson, Isak	Umei Univ.
Co-Chair: Bewley, Thomas R		Klgström, Bo	Umel Univ.
• •	. CC Can Diego	WeA12	Maui Suite 5
09:20 Equivalent Characterization of Ir	overient Subspeces of HAS and	Chaotic Systems	Regular Session
Applications to the Optimal Sens		Chair: Morgul, Omer	Bilkent Univ.
Kashima, Kenji	Kyoto Univ.	Co-Chair: Tian, Yu-Ping	Southeast Univ.
Yamamoto, Yutaka	Kyoto Univ.	09:20	
09:40		Stabilizing Periodic Solutions of C	haotic Systems, 1879
	ndau Equation by Linear Boundary	Zhu, Jiandong	Dept. of Automatic Control,
Control, 1830			Southeast Univ.
Aamo, Ole Morten	NTNU	Tian, Yu-Ping	Southeast Univ.
Smyshlyaev, Andrey	Univ. of California at San Diego	09:40	
Krstic, Miroslav	Univ. of California at San Diego	Detecting Unstable Periodic Orbits	s in Switched Arrival Systems,
		1884	
		Tian, Yu-Ping	Southeast Univ.

10:00 A Stability Result for Delayed Feed	hack Controllere 1990	09:40	or Foult Dota-ti for T
Morgul, Omer	Bilkent Univ.	Parametric Uncertainty in Senso Jet Engine, 1950	
10:20 Model Based Anticontrol of Discret	e Time Systems, 1895	Johansson, Andreas Norlander, Torbjorn	Lulea Univ. of <sup>-</sup> Volvo Aero (
Morgul, Omer 10:40	Bilkent Univ.	10:00 Nonlinear PCA Combining Princ	rinal Curves and RRE-Network
10:40 Performance Evaluations of Quant	ized Stabilizers 1907	Process Monitoring, 1956	apar Guives and NDF-NetWORK
Feriormance Evaluations of Quant Fagnani, Fabio	Pol. Di Torino	Mohamed-faouzi, Harkat	CRAN-
Zampieri, Sandro	Univ. di Padova	Mourot, Gilles	Inst. National Pol. De Lon
11:00	Silly. di I adova	Ragot, Jose	CRAN-I
Cryptography by Discrete-Time Hy	nerchantic Systems 1902	10:20	
Belmouhoub, Inam	ENSEA	Estimating Focus and Radial Di.	stances, and Fault Residuals fr
Djemai, Mohammed	ENSEA	CD Player Sensor Signals by U.	se of a Kalman Estimator, 1962
Barbot, Jean Pierre	ENSEA	Odgaard, Peter Fogh	Aalborg t
		Stoustrup, Jakob	Aalborg t
WeA13	Guest Room 450	Andersen, Palle	Aalborg I
Randomized Algorithms for	Invited Session	Mikkelsen, Henrik	Bang & Olu
Analysis and Synthesis of		10:40	,
Robust Control Systems	<del></del>	Robust Model-Based Fault Dete	
Chair: Dabbene, Fabrizio	Pol. di Torino	Tseng, H. Eric	Ford Motor Comp
Co-Chair: Calafiore,	Pol. di Torino	Xu, Li	Ford Motor Comp
Giuseppe	IEIIT OND DAL -#17	11:00	•
Organizer: Dabbene, Fabrizio Organizer: Calafiore.	IEIIT-CNR Pol. di Torino Pol. di Torino	Iterative LMI Approach for Robu	st Fault Detection Observer
Giuseppe	POI. OI TOTINO	Design, 1974	- 1
09:20		Wang, Haibo	School of Electrical & Electr Engineering, Nanyang Tech.
Randomized Algorithms in Robust		Wang, Jian Liang	Nanyang Tech. l
Tempo, Roberto	Pol. di Torino	Liu, Jian	Honeywell Avionics
Dabbene, Fabrizio	Pol. di Torino	Lana James	Singap
Calafiore, Giuseppe	Pol. di Torino	Lam, James	Univ. of Hong K
09:40		WeAPI	Grand Promer
Robust Output-Feedback Integral I	MPC: A Probabilistic Approach	SIAM Poster Papers IV	Poster/Interactive Paper Ses
(1), 1914	D 101111 CT 1	Chair: Abdallah, Chaouki T.	Univ. of New Me
Kanev, Stoyan Verhaegen, Michel	Delft Univ. of Tech.	•	Sinv. or New Me
<del>-</del> •	Univ. of Twente	09:20 Riesz Basis Property of Evolution	on Equations in Hilbert Secses
10:00 Brokabilistia Danisa of a Bakust St	ata Fandhaat Oostoll 5	Application to a Coupled String	
Probabilistic Design of a Robust St on Parameter-Dependent Lyapuno	ale-reedback Controller Based	Xu, Gen-Qi	<i>⊑qua⊪on</i> Shanxi l
Oishi, Yasuaki	The Univ. of Tokyo	Guo, Bao-Zhu	Acad. of Mathematics
10:20	THE OHIV. OF TORYO	. =	System Scien
10:20 Fast Universal Algorithms for Robu	introne Analysis (II) 1006		•
Chen, Xiniia	Stness Analysis (I), 1926 Louisiana State Univ.	Algorithms for the Solution of Op	otimization Problems with Two
Zhou, Kemin	Lousiana State Univ.	Numerical Precision Parameters	5, 1980
Aravena, Jorgina L.	Louisiana State Univ.	Polak, Elijah	Univ. of Califo
10:40	Louisiana otate Only.	Pironneau, Olivier	Univ. Par
10:40 On the Conditioning of Robustness	Problems (I) 1932	•	
	Problems (I), 1932 Ioscow Inst. of Control Sciences	The Solution of the H,/H; Probl	lem by Direct Methods*
Barmish, B. Ross	Univ. of Wisconsin		Pontificia Univ. Catolica Do
, —	Cinv. Of VVISCORSIII		De Jar
11:00 Probabilistia Babuat Cantrallas Bas	inn. Duck chie Man 1897	Ades, Roberto	2004
Probabilistic Robust Controller Des	ign: Probable Near Minimax		
Value and Randomized Algorithms		Optimal Shape Control for the N	lavier Stokes Equations 1986
Fujisaki, Yasumasa Kozawa, Yasuaki	Kobe Univ.	Bui, An Ton	Univ. of British Colur
Nozawa, Tasuaki	Kobe Univ.		Cinv. of Diffish Colds
WeA14	Guest Room 451	On the Observability and Detect	ability of Continuous Time Mon
Fault Detection and	Regular Session	Jump Linear Systems, 1994	ability of Continuous-Time Mar.
Accomodation III	i rogulai Gessioii	Costa, Eduardo F.	Unic
Chair: tseng, eric	Ford Motor Company	Do Val, Joao B.R.	UNICA
Co-Chair: Johansson,	Lulea Univ. of Tech.		Civion
Andreas		WeAW	S
09:20		Women in Control Workshop	
Fault Detection Filter Applied to Str	uctural Health Monitoring 1944	Chair: Pasik-Duncan,	Univ. of Kar
Liberatore, Sauro	Univ. of California, Los Angeles (UCLA)	Bozenna	J J. Kai
Speyer, Jason L. U	niv. of California at Los Angeles	WeNPL	Sunset Ter
Hsu, Andy	graduate student	Plenary Panel: History of	Plenary P
•	9.3.200.000.0000	Control	
		Chair: Abramovitch, Daniel Y	A - ilo nt
		Chan. Abiamoviton, Damer 1	'. Agilent

	Agilent Lab.	Nonlinear Systems, 2071	O
M-104		Rodrigues, Luis	Concordia Univ
WeM01 Multiple Vehicle Coordinated	Monarchy Ballroom Regular Session	How, Jonathan P.	Massachusetts Inst. of Tech
Control	Regulai Session	16:00	and of Mandinger Contamo 2077
Chair: Pappas, George J.	Univ. of Pennsylvania	Stability of Receding Horizon Contr Costa, Eduardo F.	roi of ivorilinear systems, 2077 Unicam
Co-Chair: Beard, Randal W.	Brigham Young Univ.	Do Val, Joao B.R.	UNICAMI
14:20	-		
Stable Flocking of Mobile Agents, Pa	art I: Fixed Topology, 2010	WeM03	Regency I
Tanner, Herbert	Univ. of New Mexico	Pricing and Optimization of	Regular Session
Jadbabaie, Ali	Univ. of Pennsylvania	Communication Networks	
Pappas, George J.	Univ. of Pennsylvania	Chair: Meyn, Sean	Univ. of Illinoi
14:40		Co-Chair: Michailidis, George	The Univ. of Michiga
Stable Flocking of Mobile Agents, Pa		14:20	. 0000
Tanner, Herbert	Univ. of New Mexico	Dynamic Optimization Flow Contro	univ. of Illinois at Urbana
Jadbabaie, Ali Pappas, George J.	Univ. of Pennsylvania Univ. of Pennsylvania	lmer, Orhan Cagri	Champaig
=	Only. Or i emisylvania	Basar, Tamer	Univ. of Illinois at Urbana
15:00 Flooking with Obstacle Avaidance: C	Connection with Limited	Basar, ramor	Champaig
Flocking with Obstacle Avoidance: C Communication in Mobile Networks.		14:40	- · · · · · · · · · · · · · · · · · · ·
Olfati-Saber, Reza	California Inst. of Tech.	Pricing and Rate Adaptation in a N	on-Coonerative Environment
Murray, Richard M.	California Inst. of Tech.	2088	c cooperative Livinoiningin,
15:20		Wu, Xinran	Univ. of California, San Dieg
15.20 Synchronization of Information in Dis	tributed Multiple Vehicle	Marbach, Peter	Univ. of Toront
Coordinated Control, 2029		15:00	
Beard, Randal W.	Brigham Young Univ.	Dynamics of Ancillary Service Price	es in Power Distribution
Stepanyan, Vahram	Student	Systems, 2094	
15:40		Meyn, Sean	Univ. of Illinoi
A Framework for Conflict Resolution	in Air Traffic Management,	Cho, In-Koo	Univ. of Illinoi
2035	<del>-</del> ·	15:20	
Resmerita, Stefan	Tech Israel Inst. of Tech.	An Approach to Rate Allocation in	
Heymann, Michael	Tech. Israel Inst. of Tech.	Stoenescu, Tudor	Univ. of Michiga
Meyer, George	NASA Ames Res. Center	Liu, Mingyan_	Univ. of Michiga
16:00		Teneketzis, Demosthenis	Univ. of Michiga
Swarm Aggregations Using Artificial	Potentials and Sliding Mode	15:40	
Control, 2041	AARR Link	Optimal Allocation in a Queueing S	System with Shared Resources,
Gazi, Veysel	Atilim Univ.	2106	The Hair of Michiga
WeM02	Regency A	Michailidis, George	The Univ. of Michiga
Nonlinear Systems I	Regular Session	16:00	Congostion Como: The Single
Chair: Shafai, Bahram	Northeastern Univ.	Network Resource Allocation and a Link Case, 2112	a Congestion Game. The Single
Co-Chair: Bullo, Francesco	Univ. of Illinois at Urbana-	Johari, Ramesh	MI
	Champaign	Tsitsiklis, John	MI
14:20			
Stabilization for a Class of Non-Affine	Systems Via Reduced-Order	WeM04	Regency (
Dynamic Output Feedback, 2047		Nanotechnology: Control	Invited Session
Lu, Guoping	Nantong Inst. of Tech.	Needs and Related	
Zheng, Yufan	Univ. of Melbourne	Perspectives (I)	Iowa State Univ
14:40		Chair: Salapaka, Murti V. Co-Chair: Baheti, Kishan	National Science Foundatio
A Sufficient Condition for Locally Cor		Organizer: Salapaka, Murti V.	lowa State Univ
Manifold for General Non Linear Sys	,	Organizer: Baheti, Kishan	National Science Foundatio
Consolini, Luca Tosques, Mario	Univ. of Parma	•	Tuttonal Colonos Foundatio
• •	Univ. of Parma	14:20 Keynote Talk: Nanoscale Science	and Engineering at NSE*
15:00.	- d Oordrall	Baheti, Kishan	National Science Foundatio
Bumpless Transfer between Advance Applications to Power Plant Control		14:40	Transmar Colonics : Carragine
Applications to Power Plant Control, Bendtsen, Jan Dimon	Aalborg Univ.	Teleoperated and Automatic Nano	manipulation Systems Using
Stoustrup, Jakob	Aalborg Univ. Aalborg Univ.	Atomic Force Microscope Probes (	
Trangbaek, Klaus	Aalborg Univ.	Sitti, Metin	Carnegie Mellon Univ
15:20	· · · · · · · · · · · · · · · · · · ·	15:00	
Control of Center Manifolds, 2065		The Intersection of Controls and Pi	hysics in Atomic Force
Hamzi, Boumediene	Univ. of California at Davis	Microscopy (I), 2124	., 5.55
·	Naval Postgraduate School	Cleveland, Jason	Asylum Re
Kang, Wei			,
Kang, Wei Krener, Arthur J	Univ. of California at Davis	15:20	
		15:20 Control Challenges in Micro Fluidio	: Systems and Nanoscale
		15:20 Control Challenges in Micro Fluidio Transport Phenomena (I), 2126	: Systems and Nanoscale

15:00 15:40 Multiestimation Scheme for Robust Adaptive Stabilization of An Observer Based Sample Detection Scheme for Atomic Force Microscopy (I), 2132 Discrete Systems, 2186 Sebastian, Abu Iowa State Univ. Alonso Quesada, Santiago Univ. del País Vasco Univ. del Pais Vasco Sahoo, Deepak R. Iowa State Univ. de la Sen, Manuel Salapaka, Murti V. Iowa State Univ. Bilbao-Guillerna, Aitor Univ. del País Vasco Univ. Del Pais Vasco. Garrido, Aitor J. 16:00 15:20 Nanotechnology Meets Biology (I)\* Hoh, Jan Johns Hopkins School of On Adaptive Observers for State Affine Systems and Application to Medicine Synchronous Machines, 2192 Besancon, Gildas WeM05 FIME-UANL Maui Suite 1 De Leon-Morales, Jesus **Optimal Timing Control of** Invited Session Huerta-guevara, Oscar Univ. Autonoma De Nuevo Leon **Hybrid Systems** Chair: Egerstedt, Magnus Georgia Inst. of Tech. Adaptive Fuzzy Neural Control of Mean Arterial Pressure through Co-Chair: Wardi, Yorai Georgia Inst. of Tech. Sodium Nitroprusside Infusion, 2198 Organizer: Egerstedt, Georgia Inst. of Tech. Nanyang Tech. Univ. Gao, Yang Magnus Nanyang Tech. Univ. Er, Meng Joo Organizer: Wardi, Yorai Georgia Inst. of Tech. 16:00 14:20 Simultaneous Precision Positioning and Vibration Suppression of Optimal Control of Switching Times in Switched Dynamical Smart Structures Adaptive Control Methods and Comparisons, Systems (I), 2138 2204 Egerstedt, Magnus Georgia Inst. of Tech. Univ. of Hawaii at Manoa Ma. Kougen Georgia Inst. of Tech. Wardi, Yorai Ghasemi-Nejhad, Mehrdad N. Univ. of Hawaii at Manoa Florent, Delmotte phd student WeM07 Regency Boardroom Regular Session On the Optimal Control of Hybrid Systems: Analysis and Zonal Optimal Control V Naval Postgraduate School Algorithms for Trajectory and Schedule Optimization (I), 2144 Chair: Fahroo, Fariba Mcgill Univ. Montreal. Co-Chair: Milman, Ruth Univ. of Toronto Shaikh, Shahid Caines, Peter E. McGill Univ. Montreal 14:20 15:00 A Unified Computational Framework for Real-Time Optimal Hedging Point Policies for Multi State Failure Prone Manufacturing Control, 2210 Systems (I), 2150 Ross, I. Michael Naval Postgraduate School Branca, Carlo Univ. di Roma Tor Vergata Fahroo, Fahroo Naval Postgraduate School Univ. di Roma Tor Vergata Martinelli, Francesco 14:40 Evaluation of a New Algorithm for Model Predictive Control Based Regularization Method for Optimally Switched and Impulsive on Non-Feasible Search Directions Using Premature Termination, Systems with Biomedical Applications (I), 2156 2216 Verriest, Erik I. Georgia Inst. of Tech. Milman, Ruth Univ. of Toronto Davison, Edward J. Univ. of Toronto 15:00 Receding Horizon Optimal Control for Some Stochastic Hybrid Systems (I), 2162 An Optimal Control Problem for Automatic Air Collision Avoidance, Cassandras, Christos G. Boston Univ. 2222 Mookherjee, Reetabrata Boston Univ. lkeda, Yutaka **Boeing Company** Kay, Jacob Bihrle Applied Res. Inc. A Linear Programming Approach to Time Optimal Control of 15:20 CLF-Based Nonlinear Control with Polytopic Input Constraints, Integrator Switched Systems with State Constraints (I), 2168 Xu, Xuping Penn State Erie 2228 Antsaklis, Panos J. Univ. of Notre Dame Curtis, Jess Air Force Res. Lab. 15:40 WeM06 Maui Suite 2 Control Law for Market-Based Semi-Active Tuned Liquid Column Applications of Adaptive Regular Session Dampers, 2234 Control Li, Hong-Nan Dalian Univ. of Tech. Chair: Gao, Yang Nanyang Tech. Univ. Co-Chair: Ma, Kougen Univ. of Hawaii at Manoa Parameter Estimation for Non-Linear Continuous-Time Systems in 14:20 a Bounded Error Context, 2240 Adaptive Fuzzy Sliding Mode Control for Robotic Manipulators, Raissi, Tarek Univ. Paris XII Univ. Paris XII Ramdani, Nacim Woo, Peng-Yung Northern Illinois Univ. Univ. Paris XII Candau, Yves Northern Illinois Univ. Guo, Yuzheng WeM08 Maui Suite 3 14:40 Regular Session Relay Feedback Tuning of Robust PID Controllers with Iso-**Automotive Vehicle Control** Damping Property, 2180 Chair: Di Bernardo, Mario Univ. of Sannio

Co-Chair: Shiriaev, Anton

Odense Univ.

Utah State Univ.

Utah State Univ. Utah State Univ.

Chen, YangQuan

Hu, ChuanHua

Moore, Kevin L.

14:20		15:40	
A New Nonlinear Observer for Friction, 2246	Tire/Road Distributed Contact	Synthesis of Sampled-Data H In Generalized Hold, 2302	finity Servo Controller with
Canudas de Wit, Carlos	Lab. of Automatic Control of	Fujioka, Hisaya	Kyoto Univ.
Camada do VIII, Cambo	Grenoble, CNRS	Hara, Shinji	The Univ. of Tokyo
Petersen, Morten Lind	Univ. of Southern Denmark	16:00	•
Shiriaev, Anton	Odense Univ.	Low Order Sampled-Data H_inf	Control. 2308
14:40		Christiansson, Anna-Karin	Univ. of Trollhattan/Uddevalla
MCS Adaptive Control of Vehic	le Dynamics: An Application of	Lennartson, Bengt	Chalmers Univ. of Tech.
Bifurcation Techniques to Conti		,	
Catino, Bruno	Univ. degli Studi di Napoli	WeM10	Guest Room 350
	Federico II	Control and Control-Oriented	Invited Session
Santini, Stefania	Univ. di Napoli Federico II	Modelling in Distributed	
Di Bernardo, Mario	Univ. of Sannio	Combustion and Flow	
15:00		Chair: Tadmor, Gilead	Northeastern Univ.
	e Vehicle Suspensions Employing	Co-Chair: Banaszuk, Andrzej	
Inerters, 2258		Organizer: Tadmor, Gilead	Northeastern Univ.
Smith, Malcolm C.	Univ. of Cambridge	Organizer: Banaszuk,	United Tech. Res. Center
Wang, Fu-Cheng	National Taiwan Univ.	Andrzej	
15:20		14:20	
	thods and Control Strategies for	A Multiscale Measure for Mixing	
Semi-Active Suspension System		Mathew, George Mezic, Igor	Univ. of California, Santa Barbara Univ. of California, Santa Barbara
Savaresi, Sergio M.	Pol. Di Milano	Petzold, Linda	Univ. of California Santa Barbara
Bittanti, Sergio	Pol. di Milano		Citiv. Of California Canta Datoara
Silani, Enrico porciani, nicola	Pol. di Milano Ferrari	14:40	I Flow I Init Turbulance in Diana
	i eitaii	Modeling and Control of Minimal Couette Flow (I), 2322	Flow Unit Turbulence in Plane
15:40	Vibration with MR-Dampers, 2270	Smith, Troy R.	Princeton Univ.
Wang, En Rong	Concordia Univ.	Moehlis, Jeff	Princeton Univ.
Ma, Xiao Qing	Concordia Univ.	Holmes, Philip J.	Princeton Univ.
Rakheja, Subhash	Concordia Univ.	15:00	
Su, Chun-Yi	Concordia Univ.	A Backward-Facing Step Combu	ıstor: Reduced-Order Modelina
16:00		and Control (I), 2328	
	ntial Brake Control System Using	Park, Sungbae	Massachusetts Inst. of Tech.
the Analytical Redundancy Tech		Wachsman, Adam	Massachusetts Inst. of Tech.
Hahn, Jin-Oh	Korea Air Force Acad.	Yi, Tongxun	Massachusetts Inst. of Tech.
You, Seung-Han	Seoul National Univ.	Wee, Daehyun	Massachusetts Inst. of Tech.
Cho, Young Man	Seoul National Univ.	Annaswamy, Anuradha	Massachusetts Inst. of Tech.
Kang, Soojoon	Korea Air Force Acad.	Ghoniem, Ahmed F.	Massachusetts Inst. of Tech.
Lee, Kyo II	Seoul National Univ.	15:20	
WeM09	Maui Suite 4	Control, Observation and Energy	Regulation of Wake Flow
H-Infinity Control	Regular Session	Instabilities (I), 2334	North anatom Chin
Chair: Bhattacharyya,	Texas A & M Univ.	Tadmor, Gilead Noack, Bernd R	Northeastern Univ. Tech. Univ. Berlin
Shankar P.	TOXAS A G IVI OTILY.	Dillmann, Andreas	Tech. Univ. Berlin
Co-Chair: Christiansson,	Univ. of Trollhattan/Uddevalla	Gerhard, Johannes	Tech. Univ. Berlin
Anna-Karin		Pastoor, Mark	Tech, Univ. Berlin
14:20	· · · · · · · · · · · · · · · · · · ·	King, Rudibert	Tech. Univ. Berlin
H-Inf Design with First Order Co	ontrollers, 2282	Morzynski, Marek	Poznan Univ. of Tech.
Tantaris, Richard	Tennessee State Univ.	15:40	
Keel, Lee H.	Tennessee State Univ.	Fuel Control of a Ducted Bluffbo	ody Flame (I), 2340
Bhattacharyya, Shankar P.	Texas A & M Univ.	Mehta, Prashant G.	United Tech. Res. Center
14:40	the first of the second second	Banaszuk, Andrzej	United Tech. Res. Center
Transient Response Shaping in	H Infinity Control by Eigenstructure	Soteriou, Marios	United Tech. Res. Center
Assignment to Convex Regions	, 2288	Mezic, Igor	Univ. of California, Santa Barbara
Satoh, Atsushi	Nara Inst. of Science And Tech.	16:00	
Okubo, Junro	Nara Inst. of Science And Tech.	A Linear Model for Control of The	ermoacoustic Instabilities on
Sugimoto, Kenji	Nara Inst. of Science and Tech.	Annular Domain (I), 2346	
15:00		Banaszuk, Andrzej	United Tech. Res. Center
Active H_2 and H_inf Shunt Col	ntrol of Electromagnetic	Hagen, Gregory	United Tech. Res. Center
Transducers., 2294		Mehta, Prashant G. Oppelstrup, Jesper	United Tech. Res. Center KTH
Fleming, Andrew	The Univ. of Newcastle	Oppeistrup, Jespei	КІП
Behrens, Sam	The Univ. of Newcastle	WeM11	Guest Room 351
Moheimani, S. O. Reza	The Univ. of Newcastle	Computational Method for	Regular Session
15:20	A Demoisite Maria Coope	System Properties	
H_infinity Entropy and the Law		Chair: Bhaya, Amit	Univ. Federal Do Rio De Janeiro
Zhang, Hui Sun, Youxian	Zhejiang Univ. Zhejiang Univ.	Co-Chair: Varga, Andras	German Aerospace Center
Juli, Touxiall	Zilejiang Only.		

	•		
14:20	of Subanasa Computation with	WeM13 Statistical Learning Methods	Guest Room 450 Invited Session
A Newton Algorithm for Invariar Large Basins of Attraction, 235	2	in Optimization, Control and	mvileu Session
Absil, Pierre-Antoine	Univ. de Liege	System Identification	
Sepulchre, Rodolphe J.	Univ. de Liege	Chair: Calafiore, Giuseppe	Pol. di Torino
Van Dooren, Paul Mahony, R.	Univ. Catholique de Louvain Australian National Univ.	Co-Chair: Dabbene, Fabrizio Organizer: Calafiore,	Pol. di Torino Pol. di Torino
14:40	Australian National Only.	Giuseppe	i oi. di totillo
	tial Pole Assignment in Vibrating	Organizer: Dabbene, Fabrizio	Pol. di Torino
Structures with Aerodynamics E		14:20	
Datta, Biswa	NIU	On Tractable Approximations of Rand	domly Perturbed Convex
Lin, Wen-Wei	National Tsing Hua Univ.	Constraints (I), 2419	
Wang, Jenn-Nan	National Taiwan Univ.	Nemirovski, Arkadi	Tech. Israel
15:00		14:40	
A New Approach to the Shifted	QR Algorithm for the Hermitian	Robust Convex Programs: Randomize	ed Solutions and Applications
Eigenvalue Problem, 2364	E I . 1	in Control (I), 2423 Calafiore, Giuseppe	Dal di Tarina
Nikpour, Maziar Manton, Jonathan H.	Univ. of Melbourne Univ. of Melbourne	Campi, M. C.	Pol. di Torino Univ. di Brescia
Mareels, Iven M. Y.	Univ. of Melbourne	15:00	Only, of Diescla
•	Only, or Melbourne	Samoling Random Transfer Functions	(1) 2420
15:20 Strongly Stable Algorithm for Co	omputing Periodic System Zeros,	Lagoa, Constantino M:	Pennsylvania State Univ.
2368	omputing renodic System Zeros,	Li, Xiang	Pennsylvania State Univ.
Varga, Andras	German Aerospace Center	Mazzaro, María Cecilia	Pennsylvania State Univ.
15:40		Sznaier, Mario	Penn State Univ.
	l Systems with Feedback Control,	15:20	
2374	- 2, 2.2 r country control,	Quasi-Monte Carlo Methods in Robus	t Control Design (I), 2435
Bhaya, Amit	Univ. Federal do Río De Janeiro	Hokayem, Peter	Univ. of New Mexico
Kaszkurewicz, Eugenius	Univ. Federal do Rio de Janeiro	Abdallah, Chaouki T.	Univ. of New Mexico
16:00		Dorato, Peter	Univ. of New Mexico
LAPACK-Based Condition and	Error Estimators for Kalman Filter	15:40	
Design, 2381		On Constraint Sampling in the Linear	
Petkov, Petko Hr.	Tech. Univ. of Sofia	Approximate Dynamic Programming (	•
Konstantinov, Mihail M.	Univ. of Architecture & Civil	de Farias, Daniela	MIT
Christov Nisolai D	Engineering Tech. Univ. of Sofia	Van Roy, Benjamin	Stanford Univ.
Christov, Nicolai D.	rech. Univ. of Solia	16:00  Brobabilistic Babyet Control Decima	f Dahmanial Vantas Fields
WeM12	Maui Suite 5	Probabilistic Robust Control Design of 2447	i Polynomiai Vector Fields,
<b>Control of Nonlinear Systems</b>		wang, qian	Penn. state Univ.
Chair: Bhat, Sanjay P.	Indian Inst. of Tech Bombay		
Co-Chair: Smith, Adam	Boston Univ.	WeM14	Guest Room 451
14:20		Fault-Tolerant Systems	Regular Session
Controllability of Spacecraft Atti	tude under Magnetic Actuation,	Chair: Gray, W. Steven	Old Dominion Univ.
2383	Indian Inst. of Teah. Deaths	Co-Chair: Gonzalez, Oscar R.	Old Dominion Univ.
Bhat, Sanjay P. Dham, Ajit Singh	Indian Inst. of Tech Bombay Indian Air Force	* **	
• •	Indian All Force	14:20	TD Design 0452
14:40	- Suotomo in Dronnes of	Controller Reconfiguration Based on L Niemann, Henrik	Tech. Univ. of Denmark
Semiglobal Regulation of Linea Measurements Constraint, 2389		Stoustrup, Jakob	Aalborg Univ.
Marconi, Lorenzo	Univ. di Bologna	14:40	, who or
15:00	Sint. di Bologita	Controller Failure Time Analysis for S	vmmetric H-Infinity Control
	ed Rotary Inverted Pendulum by	Systems, 2459	Jamagulo Frankliky Condol
Nonlinear Controller, 2395	os . Islary involted Fellouium by	Zhai, Guisheng	Wakayama Univ.
Yan, Qiguo	FlyingTiger Tech. Inc.	Lin, Hai	Univ. of Notre Dame
15:20	ygg	Antsaklis, Panos J.	Univ. of Notre Dame
How Feedback Can Tune a Bifu	ırcation Parameter towards Its	15:00	
Unknown Critical Bifurcation Va		Closed-Loop Performance Measures	for Flight Controllers Subject
Moreau, Luc	Eindhoven Univ.	to Neutron-Induced Upsets, 2465	-
Sontag, Eduardo D.	Rutgers Univ.	Gray, W. Steven	Old Dominion Univ.
Arcak, Murat	Rensselaer Pol. Inst.	Zhang, Hong	Old Dominion Univ.
15:40		Gonzalez, Oscar R.	Old Dominion Univ.
Vortex Methods for the Control		15:20	
Smith, Adam	Boston Univ.	Gain Margin Issues of the Two-Stage	and Single-Stage LQ
Baillieul, John	Boston Univ.	Reliable Controls, 2471	To Huga Inst of Task
16:00		Hsieh, Chien-Shu Shieh, Jenn-Jong	Ta Hwa Inst. of Tech. Ta Hwa Inst. of Tech.
	for Perturbated Singular Systems,	15:40	ra i wa mst. Ur rech.
2413 Lu, Guoping	Nantona Inst. of Tach	Safety Integrity Analysis Framework fo	or a Controller According to
Ho, Daniel W. C.	Nantong Inst. of Tech. City Univ. of Hong Kong	IEC 61508, 2477	or a controller According to
Yeung, L.F.	City Univ. of Hong Kong		yo Univ. of Mercantile Marine
	and a man distributed its and		

16:00		18:00	
Stability and Performance of the Sto	chastic Fault Tolerant Control	Cooperative Negotiation Strateg	ıv in Multi-Agent System. 2549
Systems, 2484		Tian, Yajie	Advanced Telecommunications
Cheng, Chuwang	East China Normal Univ.		Res. Inst. International
Zhao, Qing	Univ. of Alberta	Liu, Yuan	Kyoto Univ.
Tao, Feng	Univ. of Alberta	Shimohara, Katsunori	Advanced Telecommunications
		•	Res. Inst. International
WeMPI	Grand Promenade	Sawaragi, Tetsuo	Kyoto Univ.
Linear Systems and Control Po	oster/Interactive Paper Session	18:20	
Education		A Pursuit Strategy for Wheeled-	Vehicle Formations 2555
Chair: Djaferis, Theodore E.	Univ. of Massachusetts	Marshall, Joshua A.	Univ. of Toronto
14:20		Broucke, Mireille E.	Univ. of Toronto
Partial Stability Preserving Maps and	d Stabilization, 2490	Francis, Bruce A.	Univ. of Toronto
Diaferis, Theodore E.	Univ. of Massachusetts	•	
•		WeP02	Regency A
Analytical Design of a Two-Degree-0	Of-Freedom Controller for	Nonlinear Systems II	Regular Session
Interval Plants, 2496	or recommendation	Chair: Middleton, Rick	Univ. of Newcastle
Zhang, Weidong	Shanghai Jiaotong Univ.	Co-Chair: Dower, Peter M.	The Univ. of Melbourne
znang, vrotong	changilar diactoring Chir.	16:40	
Improved Boundard Stability Babusi	too oo faa liinaaa Oosataaa oo iith	Conjectures and Counterexamp	les on Ontimal I -2 Disturbance
Improved Bounds of Stability Robust	iness for Linear Systems with	Attenuation in Nonlinear System	
Structured Perturbation, 2498	Civil Aviation Univ. of China	Middleton, Rick	Centre for Integrated Dynamics
liu, changyou	Civil Aviation Only, of China	,	and Control. The Univ. of Ne
		Lau, Katrina	Centre for Integrated Dynamics
A Review of Time-Delay Estimation			and Control, The Univ. of Ne
Björklund, Svante	Linköpings Univ.	Braslavsky, Julio H.	Centre for Integrated Dynamics
Ljung, Lennart	Linköping Univ.		and Control, The Univ. of Ne
		17:00	
Fun Control Experiments with Matlat		On Quantized Control and Geor	metric Ontimization, 2567
Bodson, Marc	Univ. of Utah	Bullo, Francesco	Univ. of Illinois at Urbana-
		Build, 1 (all 00000	Champaign
Web-Based Environment for Collabo	rative Remote	Liberzon, Daniel	Univ. of Illinois at Urbana-
Experimentation, 2514			Champaign
Roehrig, Christof	Univ. of Hagen	17:20	, <b>,3</b>
Bischoff, Andreas	Univ. of Hagen		d for Approximation of a Class of
		Mixed L-2 / L-Infinity Value Fund	
Bounded Controller Design of an AB	R Explicit Rate Algorithm for	Dower, Peter M.	Univ. of Melbourne
ATM Switches, 2519		McEneaney, William M.	UC San Diego
Tarbouriech, Sophie	LAAS-CNRS	17:40	
Ariola, Marco	Univ. degli Studi di Napoli	Estimation of Signals in an Inter	connection of LTI Systems and
e e e	Federico II	Unknown Static Maps, 2579	connection of ETT Systems and
Abdallah, Chaouki T.	Univ. of New Mexico	Wemhoff, Eric	Univ. of California at Berkeley
		Packard, Andrew K.	Univ. of California at Berkeley
WeP01	Monarchy Ballroom	18:00	· · · · · · · · · · · · · · · · · · ·
Multiple Agent Systems	Regular Session	Controllability of Hamiltonian Sy	stems with Drift: Action-Angle
Chair: Gazi, Veysel	Atilim Univ.	Variables and Ergodic Partition,	
Co-Chair: Marshall, Joshua	Univ. of Toronto	Mezic, Igor	Univ. of California, Santa Barbara
<b>A.</b>	en de la companya de	• •	oniv. or oamorna, oarna barbara
16:40		18:20	numinal Systems for a Class of
Escaping Capture by Multiple, Intellig		A Characterization of Strongly In Non-Lipschitz Multifunctions, 25	
Cooperative Pursuers Amidst Statior	nary Clutter, 2525	Wolenski. Peter R.	Louisiana State Univ.
Masoud, Ahmad	KFUPM	Rios, Vinicio R.	Graduate Student
17:00		Kios, Viriloio IX.	Graduate Student
Formation Control of a Multi-Agent S	system Using Decentralized	WeP03	Regency B
Nonlinear Servomechanism, 2531	•	Stochastic Network Models	Regular Session
Gazi, Veysel	Atilim Univ.	Chair: Meyn, Sean	Univ. of Illinois
17:20		Co-Chair: Hayat, Majeed	Univ. of New Mexico
Conflict Resolution in Multi-Agent Sy	stems 2537		Offile. Of New Mexico
Resmerita, Stefan	Tech Israel Inst. of Tech.	16:40	
Heymann, Michael	Tech. Israel Inst. of Tech.		Decision and Analysis in Network
17:40		Intrusion Detection, 2595	niv of Illinois at Libana abannain
Tr.40 Multiple Agent Team Theoretic Decis	sion-Making for Searching		niv. of Illinois at Urbana-champaign
Vultiple Agent Team Theoretic Decis Unknown Environments, 2543	son-waking to Scaluling .		niv. of Illinois at Urbana-Champaign
Rajnarayan, Dev Gorur	Stanford Univ.	17:00	
Ghose, Debasish	Indian Inst. of Science		proach to the Robust Power Control
Chose, Debasisti	mulan hist. Of Science	Problem, 2601	
		Zhang, Huanshui	Hong Kong Pol. Univ.
		Wong, Wing Shing	Chinese Univ. of Hong Kong
	•	Ge, Weiyan	Chinese Univ. of Hong Kong
	÷	Caines, Peter E.	McGill Univ. Montreal

17:20 Stochastic Models of Proportion	nally Fair Congestion Controllers,	WeP05 Discrete-Event Systems	Maui Suite 1 Regular Session
2606		Chair: Lafortune, Stephane	Univ. of Michigan
Deb, Supratim	Univ. of Illinois at Urbana- Champaign	Co-Chair: Takai, Shigemasa 16:40	Wakayama Univ.
Srikant, Rayadurgam	Univ. of Illinois at Urbana- Champaign	Safe Diagnosability of Discrete Event Paoli. Andrea	Systems, 2658 Univ. of Bologna
47.40	Onampaign.	Lafortune, Stephane	Univ. of Michigan
17:40	Frankration in Observatio	•	Only. Of Michigan
Value Functions and Performa	nce Evaluation in Stochastic	17:00	
Network Models, 2612	Tata look of Foundamental Dec	Immediate Observability of Discrete E	
Borkar, Vivek S.	Tata Inst. of Fundamental Res. Univ. of Illinois	Application to User-Interface Design,	
Meyn, Sean	Univ. of litinois	Oishi, Meeko	Stanford Univ.
18:00		Hwang, Inseok	Stanford Univ.
	ocesses Characterized by Time-	Tomlin, Claire J.	Stanford Univ.
Varying Time Delays, 2618		17:20	
Parlos, Alexander G.	Texas A&M Univ.	The Control and Verification of Simila	
Ye, Dan	Texas A&M Univ.	Broadcast Network Environment, 267	
18:20		Rohloff, Kurt	The Univ. of Michigan
Analysis of Abstract Simulation	Via Stochastic Differential Equation	Lafortune, Stephane	Univ. of Michigan
Models, 2620	,	17:40	
Wu, Yujing	Univ. of Massachusetts at	On Multi-Agent Product Systems: Gra	aph MA Products and Partially
	Amherst	Observed MA Products, 2680	,
Gong, Wei-Bo	Univ. of Massachusetts at	Romanovski, lakov	Queen's Univ.
<del>-</del>	Amherst	Caines, Peter E.	McGill Univ.
Towsley, Don	Univ. of Massachusetts at	18:00	
	Amherst	Supervisor Synthesis for a Class of C	Concurrent Discrete Event
W-D04	5	Systems, 2686	
WeP04	Regency C	Takai, Shigemasa	Wakayama Univ.
Nanotechnology: Control Needs and Related	Invited Session	Ushio, Toshimitsu	Osaka Univ.
Perspectives (II)		18:20	
Chair: Salapaka, Murti V.	lowa State Univ.	Ensuring the Conformance of Reactive	ve Discrete-Event Systems
Co-Chair: Baheti, Kishan	National Science Foundation	Using Supervisory Control, 2692	_
Organizer: Salapaka, Murti		Jeron, Thierry	INRIA
Organizer: Baheti, Kishan	National Science Foundation	Marchand, Herve	Irisa/inria Rennes
•	Mational Ocience   Oundation	rusu, vlad	Irisa/inria Rennes
16:40	antinu of the tarnels in Diago	Tschaen, Valery	IRISA
Iterative Feedforward Compen	sation of Hysteresis in Piezo		
Iterative Feedforward Compen- Positioners (I), 2626	•	WeP06	Maui Suite 2
Iterative Feedforward Compen- Positioners (I), 2626 Leang, Kam K.	Univ. of Washington	WeP06 Adaptive Control Applications	Maui Suite 2 Regular Session
Iterative Feedforward Compen Positioners (I), 2626 Leang, Kam K. Devasia, Santosh	•	WeP06 Adaptive Control Applications Chair: Astolfi, Alessandro	Maui Suite 2 Regular Session Imperial Coll.
Iterative Feedforward Compen Positioners (I), 2626 Leang, Kam K. Devasia, Santosh 17:00	Univ. of Washington Univ. of Washington	WeP06 Adaptive Control Applications	Maui Suite 2 Regular Session
Iterative Feedforward Compen Positioners (I), 2626 Leang, Kam K. Devasia, Santosh 17:00 Closed-Loop Identification of a	Univ. of Washington Univ. of Washington  Micro-Sensor (I), 2632	WeP06 Adaptive Control Applications Chair: Astolfi, Alessandro	Maui Suite 2 Regular Session Imperial Coll.
Iterative Feedforward Compen Positioners (I), 2626 Leang, Kam K. Devasia, Santosh 17:00 Closed-Loop Identification of a Chen, Yen-cheng	Univ. of Washington Univ. of Washington  Micro-Sensor (I), 2632 Univ. of California at Los Angeles	WeP06 Adaptive Control Applications Chair: Astolfi, Alessandro Co-Chair: Ortega, Romeo	Maui Suite 2 Regular Session Imperial Coll. LSS-SUPELEC
Iterative Feedforward Compen Positioners (I), 2626 Leang, Kam K. Devasia, Santosh 17:00 Closed-Loop Identification of a Chen, Yen-cheng Hui, Jason K.	Univ. of Washington Univ. of Washington  Micro-Sensor (I), 2632 Univ. of California at Los Angeles The Aerospace Corp.	WeP06 Adaptive Control Applications Chair: Astolfi, Alessandro Co-Chair: Ortega, Romeo 16:40	Maui Suite 2 Regular Session Imperial Coll. LSS-SUPELEC
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Iterative Feedforward Compenion Positioners (I), 2626 Leang, Kam K. Devasia, Santosh 17:00 Closed-Loop Identification of a Chen, Yen-cheng Hui, Jason K. M'Closkey, Robert 17:20 Model Development for Piezod Smith, Ralph C. Hatch, Andrew De, Tathagata 17:40 Control of Nanopositioning Devalapaka, Srinivasa Sebastian, Abu 18:00 Using Nonlinear Dynamics for and Nano-Scale Devices (I), 20 Turner, Kimberly Baskaran, Rajashree Zhang, Wenhua 18:20 Nano-Precision Control of Micri 2652 Maithripala, D. H. S. Gale, Richard Holtz, Mark	Univ. of Washington Univ. of Washington  Micro-Sensor (I), 2632 Univ. of California at Los Angeles The Aerospace Corp. Univ. of California at Los Angeles Peramic Nanopositioners (I), 2638 North Carolina State Univ. North Carolina State Univ. North Carolina State Univ. Nowa State Univ. Nowa State Univ.  Vices (I), 2644 Massachusetts Inst. of Tech. Nowa State Univ.  Performance Enhancement in Micro 6500 Univ. of California, Santa Barbara Tomirrors Using Output Feedback (I), Texas Tech. Univ. Texas Tech. Univ. Texas Tech. Univ.	WeP06 Adaptive Control Applications Chair: Astolfi, Alessandro Co-Chair: Ortega, Romeo 16:40 Gap Metric Robustness of Adaptive ( Nonlinear Systems, 2698 Bian, Wenming French, Mark 17:00 Globally Convergent Adaptive Tracki Velocity with Inertia Identification and Linearization, 2704 Sanyal, Amit Chellappa, Madhusudhan Valk, Jean Luc Shen, Jinglai Ahmed, Jasim Bernstein, Dennis S. 17:20 Adaptive Altitude Control for a Small Stand, 2710 Dzul, Alejandro Lozano, Rogelio Castillo, Pedro 17:40 Direct Adaptive Control for a Class on Nonlinear Systems Using Neural Net	Maui Suite 2 Regular Session Imperial Coll. LSS-SUPELEC Controllers for a Class of Univ. of Southampton Univ. of Southampton of Spacecraft Angular of Adaptive Feedback Univ. of Michigan Univ. of Michigan - Ann Arbor Eindhoven Univ. of Tech. Univ. of Michigan Senior Systems Engineer Univ. of Michigan Helicopter in a Vertical Flying Inst. Tecnológico de la Laguna Univ. de Tech. de Compiegne

18:00		17:20	
	ol of Spacecraft in the Presence of	Identification and Control for Futu	
Gravity Gradient, 2722	Del di Milene	Hesseling, Rogier Jelke	Tech. Univ. Eindhoven Eindhoven Univ. of Tech.
Lovera, Marco	Pol. di Milano	Steinbuch, Maarten	
Astolfi, Alessandro	Imperial Coll.	Veldpaus, Frans	Eindhoven Univ. of Tech. BMW AG
18:20		Klisch, Thomas	BIVIVV AG
	with Transient Overparametrization,	17:40	
2728		Extended LTI Anti-Windup Contr	ol with Actuator Magnitude and
Hsu, Liu	COPPE - Federal Univ. of Rio de	Rate Saturations, 2786	N. d. Const Otata II.d.
	Janeiro	Wu, Fen	North Carolina State Univ.
Costa, Ramon R.	COPPE - Federal Univ. of Rio de	Soto, Marco	North Carolina State Univ.
lessi Abrass Kaii	Janeiro COPPE/UFRJ	18:00	
Imai, Alvaro Koji	COPPE/UPRI	Constrained Parallel Global Option	misation for Boundary Layer
WeP07	Regency Boardroom	Transition Control, 2792	
New Trends on Geometric an		Rogers, Eric	Univ. of Southampton
Optimal Control I	u minou ocasion	Tutty, Owen Nelson, Phil	Univ. of Southampton Univ. of Southampton
Chair: Boscain, Ugo V.	SISSA-ISAS	Veres, Galina	Univ. of Southampton
Co-Chair: Piccoli, Benedetto			Only, of Southampton
Organizer: Boscain, Ugo V.	SISSA-ISAS	18:20	
Organizer: Piccoli, Benedett		Dynamics and Control of an Elas	
16:40		Central Gravitational Field, 2798	
Controllability by Low Modes Fo	orcing of the Navier-Stokes	Sanyal, Amit	Univ. of Michigan
Equation with Periodic Data (I).		Shen, Jinglai McClamroch, N. Harris	Univ. of Michigan Univ. of Michigan
Agrachev, Andrey A.	SISSA, Trieste, Italy & Steklov	Micciannoch, N. Harris	Only, or wicingan
7 ( <b>3</b> (4 ) (1 ) (1 ) (1 )	Mathem. Inst. Moscow, Russia	WeP09	Maui Suite 4
Sarychev, Andrey V.	DiMaD, Univ. of Florence, Italy	Markov Processes	Regular Session
17:00		Chair: Schwartz, Charles	Northwestern Univ.
	o(3)-Left-Invariant Control System	Co-Chair: Benzaouia,	Faculty of Science Semialia,
on a Sphere (I), 2740	stor Lon invariant control cystem	Abdellah	Univ. Cadi Ayyad
Boscain, Ugo V.	SISSA-ISAS	16:40	
Chitour, Yacine	Lab. D'analyse Numerique	Control of Jump Linear Systems	Having Sami Markov Sajavra
17:20	,	Times, 2804	riaving Semi-warkov Sojoum
On Sufficient Optimality Conditi	ons for a Singular Extremal (I)	Schwartz, Charles	Northwestern Univ.
2746	one for a difficult Extremal (1),	Haddad, Abraham H.	Northwestern Univ.
Stefani, Gianna	Univ. Di Firenze	17:00	Trongmostom Gint.
17:40		Regulator Problem for Discrete-1	Fime Dolov Svotema with
Underwater Vehicles: A Surpris	ing Non Time Ontimal Bath (I)	Markovian Jumping Parameters	and Constrained Control 2806
2750	ing Non Time-Optimal Faul (1),	Daraoui, N.	Univ. Cadi Ayyad
Chyba, Monique	Univ. of Hawaii	Benzaouia, Abdellah	Univ. Cadi Ayyad
18:00	om or idea	Boukas, El-Kebir	Ec. Pol. de Montréal
	rly Perturbed Systems (I), 2756	17:20	
Artstein, Zvi	The Weizmann Inst.	A Mode-Independent H-Infinity F	ilter Design for Discrete-Time
18:20	THE PROPERTY MICE	Markovian Jump Linear Systems	
Optimal Control for a Bilinear M	adal with Pagrating Agent in	de Souza, Carlos E.	Lab. Nacional de Computação
Cancer Chemotherapy (I), 2762			Cientifica - LNCC
Ledzewicz, Urszula	Southern Illinois Univ. at	17:40	
Leuzewicz, Orszula	Edwardsville	Application of Dynamic Programi	ming in Genetic Pegulatory
Schattler, Heinz M.	Washington Univ.	Networks, 2817	ming in Genetic Regulatory
	vvaoimigion omv.	Datta, Aniruddha	Texas A & M Univ.
WeP08	Maui Suite 3	Choudhary, Ashish	Texas A&M Univ.
Automotive and Aerospace	Regular Session	Dougherty, Edward	Texas A&M Univ.
Systems		Bittner, Michael	TGEN
Chair: Hesseling, Rogier	Tech, Univ, Eindhoven	18:00	The second secon
Jelke	\$		eximation Algorithms for Adaptive
Co-Chair: Soto, Marco	North Carolina State Univ.		ying Markov Decision Processes,
16:40		2823	
	e Speed Limits to Suppress Shock	Vázquez-Abad, Felisa J.	Univ. of Montreal
Waves, 2768		Krishnamurthy, Vikram	Univ. of British Columbia
Hegyi, Andreas	Delft Univ. of Tech.	18:20	
De Schutter, Bart	Delft Univ. of Tech.		cheme for Estimating the Number
Hellendoorn, Hans	Delft Univ. of Tech.	of Active Flows, 2829	
17:00	•	Yi, Sungwon	Pennsylvania State Univ.
A Macroscopic Traffic Flow Mod	del for Integrated Control of	Deng, Xidong	Pennsylvania State Univ.
Freeway and Urban Traffic Netv		Kesidis, George	Pennsylvania State Univ.
van den Berg, Monique	Delft Univ. of Tech.	Das, Chita	Pennsylvania State Univ.
Hegyi, Andreas	Delft Univ. of Tech.		<u>.</u> .
De Schutter, Bart	Delft Univ. of Tech.		•
Hellendoorn, Hans	Delft Univ. of Tech.	-	· -

tructured and Distributed	Invited Session	18:20 A Deflated Implicitly Restarted Lar	nczos Algorithm for Model
Chair: Voulgaris, Petros G.	Univ. of Illinois at Urbana- Champaign	Reduction, 2902 Papakos, Vasilios Jaimoukha, Imad M.	Imperial Coll. Londo Imperial Coll. Londo
Co-Chair: D'Andrea, Raffaello	Cornell Univ.	Jaimoukiia, iiiiad W.	mperiar Con. Londo
Organizer: Voulgaris, Petros G.	Univ. of Illinois at Urbana- Champaign	WeP12 Non-Holonomic Systems and	Maui Suite Regular Sessio
6:40		Robotics	
istributed Control of Heterogeneo Iver an Arbitrary Graph (I), 2835	us Systems Interconnected	Chair: Kyriakopoulos, Kostas J.	National Tech. Univ. of Ather
Langbort, Cedric D'Andrea, Raffaello	Cornell Univ. Cornell Univ.	Co-Chair: Sastry, Shankar	Univ. of California at Berkele
7:00		16:40 How Should a Snake Turn on Ice:	A Case Study of the Asymptotic
tructured Frequency Weighted Mo Li, Li	Univ. of California, Los Angeles	Isoholonomic Problem, 2908 Hu, Jianghai	Univ. of California at Berkele
Paganini, Fernando	Univ. of California, Los Angeles	Simic, Slobodan Sastry, Shankar	Univ. of California at Berkele Univ. of California at Berkele
7:20 Quantization and Coding for Decen Yuksel, Serdar	ntralized LTI Systems (I), 2847 Univ. of Illinois at Urbana-	17:00 Oscillatory Signals with Nonlinear	
Basar, Tamer	Champaign Univ. of Illinois at Urbana-	Nonholonomic Systems, 2914 Morgansen, Kristi A.	Univ. of Washingto
Jasan, value	Champaign	17:20	5g.
7:40 Stabilization of Nested Systems wit	th Uncertain Subsystem	Robust Control of Mobile Robots Unfinity Compensation Method, 29	
Communication Channels (I), 2853	,	Yazdanpanah, M. J. karimiankhosrowshahi, G.	Tehran Uni
Yadav, Vikas Voulgaris, Petros G.	lowa State Univ. Univ. of Illinois at Urbana-	17:40	AMIRKABIR Uni
Salapaka, Murti V.	Champaign Iowa State Univ.	Closed Loop Motion Planning and Uncertain Environments, 2926	Control for Mobile Robots in
8:00		Loizou, Savvas	National Tech. Univ. of Ather
lecessity of the Small Gain Theore	em for Multidimensional	Tanner, Herbert	Univ. of New Mexic
Systems (I), 2859 Chandra, Ramu	Cornell Univ.	Kumar, Vijay Kyriakopoulos, Kostas J.	Univ. of Pennsylvan National Tech. Univ. of Ather
D'Andrea, Raffaello	Cornell Univ.	18:00	radional room only, or rains
8:20		Dynamic Modeling and Tracking C	Control of a Nonholonomic
Decentralized Control of Unstable		Wheeled Mobile Manipulator with	
nvariant Information Constraints (I, Rotkowitz, Michael	), 2865 Stanford Univ.	Cheng, Meng-Pi	National Chung Hsing Un Taichung , Taiwan, R.O.
Lall, Sanjay	Stanford Univ.	Tsai, Ching-Chih	National Chung-Hsing Uni
VeP11 Computational Methods	Guest Room 351 Regular Session	18:20 Entropy-Based Environment Explo	oration and Stochastic Optimal
Chair: Galati, David	Univ. of Pittsburgh	Control, 2938 Baglietto, Marco	Univ. of Genov
Co-Chair: Misra, Pradeep	Wright State Univ.	Paolucci, Massimo	Univ. di Geno
6:40		Scardovi, Luca	Univ. of Geno
A Fast Algorithm for Unit Level Tea Game Environment, 2872		Zoppoli, Riccardo	Univ. of Geno
Galati, David Liu, Yong	Univ. of Pittsburgh Univ. of Pittsburgh	WeP13 Statistical Learning Methods	Guest Room 45 Regular Session
Simaan, Marwan A.	Univ. of Pittsburgh	Chair: Blom, Henk A.P.	National Aerospace Lab. NL
7:00	•	Co-Chair: Lee, Ji-Woong	Univ. of Illinois at Urban Champai
Partial Pivoting in the Computation Sparse Systems, 2878	of Krylov Subspaces of Large	16:40	Champais
Hodel, Alan S.	Auburn Univ.	Generalization Ability of a Class o	f Empirical Risk Minimization
Misra, Pradeep 17:20	Wright State Univ.	Algorithms and the Support Vecto Lee, Ji-Woong	r Regression Method, 2942 Univ. of Illinois at Urban
7 .20 Barrier Certificates for Nonlinear M	lodel Validation, 2884	· ·	Champai
Prajna, Stephen 7:40	California Inst. of Tech.	Khargonekar, Pramod P. 17:00	Univ. of Florid
Adapting the Direction of the Searc		Bandit Problems with Arbitrary Sid	
Continuous-Time Nonlinear System Nounou, Hazem	ns, 2890 United Arab Emirates Univ.	Wang, Chih-chun Kulkarni, Sanjeev R.	Princeton Un Princeton Un
8:00 On Numerical Differentiation Algori	ithms for Nonlinear Estimation,	Poor, H. Vincent 17:20	Princeton Un
896 Braci, Mohamed	Univ. Paris Sud	An Approach to Intelligent Web Pi Markov Model, 2954	re-Fetching Based on Hidden
Diop, Sette	CNRS	Jin, Xin Xu, Huanging	Donghua Un Shanghai Jiao Tong Un
	,	· · · · · · · · · · · · · · · · ·	
	. xi	lix	
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		Combact Education Min. Automor	maria Dahadiaa (II) 2044
17:40		Control Education Via Autonoi Bushnell, Linda G.	Univ. of Washington
	roach for No-Wait Flow-Line Batch	Crick, Andy P.	Univ. of Washington
Scheduling with Limited Batch Si Wang, Xiao-Rong	zes, 2959 Zhejiang Univ.	Orion, Amoy 1	Offit, of tradimington
Wu, Tie-Jun	Zhejiang Univ. Zhejiang Univ.	Web Based Interactive Simula	tion of Autonomous Vehicles
	Zilojiang Oniv.	Manoeuvres (I), 3018	tion of Autonomous venicles
18:00	Cargada by Jaint Cambinations of	Kolodko, Julian	Griffith Univ.
Tracking Multiple Maneuvering T IMM and PDA, 2965	argets by Joint Combinations of	George, Abraham Kaithayil	
Blom, Henk A.P.	National Aerospace Lab. NLR	Blazevic, Stjepan	Griffith Univ.
Bloem, Edwin A.	National Aerospace Lab. NLR	Wang, Nanbin	Griffith Univ.
Biodin, Zowii 7 t.	reasonal reloopade Lab. HER	Vlacic, Ljubo	Griffith Univ.
WeP14	Guest Room 451		
Sliding Mode Control of Linear	Regular Session	Computational Stochastic Con	trol: Basic Foundations, Complexity
System	<u> </u>	and Techniques (I), 3024	
Chair: Ferrara, Antonella	Univ. of Pavia	Hanson, Floyd B.	Univ. of Illinois at Chicago
Co-Chair: Hirschorn, Ronald	Queen's Univ.		
16:40	•	Cancer Treatment and Control	
Geometric Sliding Mode Control:	The Linear and Linearised	Westman, John J.	Miami Univ. of Ohio
Theory, 2971		•	
Hirschorn, Ronald	Queen's Univ.		evels: From K-12 through PhD and
Lewis, Andrew D.	Queen's Univ.	Beyond (I), 3036	
17:00		Pasik-Duncan, Bozenna	Univ. of Kansas
Constrained Optimization Via Slid	ding Modes in Dynamic Linear	Duncan, Tyrone E.	Univ. of Kansas
Systems, 2977	Hate of Bank	WeES1	<u> </u>
Ferrara, Antonella	Univ. of Pavia	Wecol Xerox Industry Sponsor	Regency A
Utkin, Vadim I.	Ohio State Univ.	Session	Evening Session
17:20	and Ottobara March On Contra	Gession	
A Practical Method for the Design		WeES2	Maui Suite 4
Using Linear Matrix Inequalities, Edwards, Christopher	Univ. of Leicester	The MathWorks Industry	Evening Session
17:40	Only. of Leicester	Sponsor Session	
Mini-Max Integral Sliding Mode C	Control for Multimodal Linear		· · · · · · · · · · · · · · · · · · ·
Uncertain Systems, 2988	Onli Of TOT Wallimoder Linear	WeES3	Monarchy Ballroom
Poznyak, Alexander S.	CINVESTAV-IPN	Keynote Talk: J. Bryzek,	Evening Session
Fridman, Leonid M.	National Autonomous Univ. of	Control Issues of MEMS	
	Mexico	Chair: Lewis, Frank L.	Univ. of Texas at Arlington
	OIND/COTAL/	19:00	
Bejarano Rodriguez,	CINVESTAV		
Bejarano Rodriguez, Francisco Javier	CINVESTAV	Control Issues of MEMs, 3039	
	CINVESTAV	Control Issues of MEMs, 3039 Bryzek, Janusz	BN Ventures
Francisco Javier 18:00 Variable Structure Output Feedba	ack Control for Linear System with	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric	BN Ventures Honeywell
Francisco Javier 18:00 Variable Structure Output Feedbathe Uncertain Output Matrix, 299	ack Control for Linear System with	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony	BN Ventures Honeywell Agile Microsystems
Francisco Javier 18:00 Variable Structure Output Feedba the Uncertain Output Matrix, 299- xiang, ji	ack Control for Linear System with 4 Zhejiang Univ. Yuquan Campus	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David	BN Ventures Honeywell Agile Microsystems Agile Microsystems
Francisco Javier 18:00 Variable Structure Output Feedba the Uncertain Output Matrix, 299- xiang, ji Su, HongYe	ack Control for Linear System with 4 Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony	BN Ventures Honeywell Agile Microsystems
Francisco Javier 18:00  Variable Structure Output Feedbathe Uncertain Output Matrix, 299- xiang, ji Su, HongYe Chu, Jian	ack Control for Linear System with 4 Zhejiang Univ. Yuquan Campus	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks
Francisco Javier 18:00 Variable Structure Output Feedbathe Uncertain Output Matrix, 299-xiang, ji Su, HongYe Chu, Jian 18:20	ack Control for Linear System with 4 Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek ThDPL	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks Monarchy Ballroom
Francisco Javier 18:00 Variable Structure Output Feedbathe Uncertain Output Matrix, 299-xiang, ji Su, HongYe Chu, Jian 18:20 Sliding Mode-Delta Modulation C	ack Control for Linear System with  Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Control of a ``buck, 2999	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks
Francisco Javier 18:00 Variable Structure Output Feedbathe Uncertain Output Matrix, 299-xiang, ji Su, HongYe Chu, Jian 18:20	ack Control for Linear System with 4 Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek ThDPL Plenary Talk: Tamer Basar	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks  Monarchy Ballroom Plenary Session
Francisco Javier 18:00  Variable Structure Output Feedbathe Uncertain Output Matrix, 299-xiang, ji Su, HongYe Chu, Jian 18:20  Sliding Mode-Delta Modulation C Sira-Ramirez, Hebertt J.	ack Control for Linear System with  Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus control of a ``buck, 2999 CINVESTAV-IPN	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek  ThDPL Plenary Talk: Tamer Basar Chair: Parisini, Thomas 08:00	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks  Monarchy Ballroom Plenary Session
Francisco Javier 18:00  Variable Structure Output Feedbathe Uncertain Output Matrix, 299- xiang, ji Su, HongYe Chu, Jian 18:20  Sliding Mode-Delta Modulation C Sira-Ramirez, Hebertt J.	ack Control for Linear System with  Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Control of a `buck, 2999 CINVESTAV-IPN  Grand Promenade	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek  ThDPL Plenary Talk: Tamer Basar Chair: Parisini, Thomas 08:00 Controlling the Internet: A Sun	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks  Monarchy Ballroom Plenary Session Univ. of Trieste
Francisco Javier  18:00  Variable Structure Output Feedbathe Uncertain Output Matrix, 299-xiang, ji Su, HongYe Chu, Jian  18:20  Sliding Mode-Delta Modulation C Sira-Ramirez, Hebertt J.  WePPI On Control Education: An	ack Control for Linear System with  Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus control of a ``buck, 2999 CINVESTAV-IPN	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek  ThDPL Plenary Talk: Tamer Basar Chair: Parisini, Thomas 08:00 Controlling the Internet: A Sun Liu, Shao Basar, Tamer	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks  Monarchy Ballroom Plenary Session Univ. of Trieste  vey and Some New Results, 3048 Univ. of Illinois at Urbana-Champaign
Francisco Javier 18:00  Variable Structure Output Feedbathe Uncertain Output Matrix, 299- xiang, ji Su, HongYe Chu, Jian 18:20  Sliding Mode-Delta Modulation C Sira-Ramirez, Hebertt J.	ack Control for Linear System with  Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Zhejiang Univ. Yuquan Campus Control of a `buck, 2999 CINVESTAV-IPN  Grand Promenade	Control Issues of MEMs, 3039 Bryzek, Janusz Abbott, Eric Flannery, Anthony Cagle, David Maitan, Jacek  ThDPL Plenary Talk: Tamer Basar Chair: Parisini, Thomas 08:00 Controlling the Internet: A Sun Liu, Shao Basar, Tamer	BN Ventures Honeywell Agile Microsystems Agile Microsystems Transperent Networks  Monarchy Ballroom Plenary Session Univ. of Trieste  vey and Some New Results, 3048
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10:00		09:20	Et in Organis to the Board of the
Leaderless Coordination Via Bidire Dependent Communication, 3070		(DFCB) Control (I), 3130	Finite Communication Bandwidth
Moreau, Luc 10:20	Eindhoven Univ.	Li, Keyong Baillieul, John	Boston Univ. Boston Univ.
Coordinated Collective Motion of C Robots: Analysis of Vicsek's Mode		09:40 Upper Bounds to Transport Ca	pacity of Wireless Networks (I),
Savkin, Andrey V.	Univ. of New South Wales	3136	Univ. of Illinois
10:40 Stability Analysis of Interconnected Matrix Feedback, 3078	d Nonlinear Systems under	Jovicic, Aleksandar Kulkarni, Sanjeev R. Viswanath, Pramod	Princeton Univ. Univ. of Illinois
Cremean, Lars B. Murray, Richard M.	California Inst. of Tech. California Inst. of Tech.	10:00 Some Scaling Properties of Lar	rge Distributed Control Systems (I),
11:00		3142 Tatikonda, Sekhar	Yale Univ.
Dissipation Inequalities for Distribu	ited Systems on Graphs, 3084 Stanford Univ.	10:20	raie Oniv.
Lall, Sanjay	Stanford Univ.	Noisy Data-Rate Limited Estima Simsek, Tunc	ation: Renewal Codes (I), 3148 Univ. of California at Berkeley
ThA02	Regency A	Varaiya, Pravin P.	Univ. of California at Berkeley
Nonlinear Systems III	Regular Session	10:40	
Chair: Grizzle, Jessy W. Co-Chair: Leonessa, Alexander	Univ. of Michigan Unív. of Central Florida	A Control Theoretic Approach t Venkatesh, S.R. Voulgaris, Petros G.	o Channel Equalization (I), 3155 Boston Univ. Univ. of Illinois at Urbana-
09:20		vougans, renos G.	Champaign
Event-Based PI Control of an Und Grizzle, Jessy W.	eractuated Biped Walker, 3091 Univ. of Michigan	Hadjicostis, Christoforos	Univ. of Illinois at Urbana- Champaign
Westervelt, Eric R.	The Ohio State Univ.	11:00	
Canudas de Wit, Carlos	ENSIEG-INPG		mmunication Schemes (I), 3161
09:40 Adaptive Nonlinear Tracking Cont.	rol of an I Inderactuated	Elia, Nicola	lowa State Univ.
Nonminimum Phase Model of a M		ThA04	Regency C
Boundedness, 3097	error and and are all an	Parametric Programming in	Invited Session
yannick, Morel Leonessa, Alexander	Florida Atlantic Univ. Univ. of Central Florida	Control System Design Chair: Kerrigan, Eric C.	Univ. of Cambridge
10:00	onv. or ocimal riolida	Co-Chair: Bemporad, Albert	
Low-Observable Nonlinear Traject Air Vehicles, 3103	tory Generation for Unmanned	Organizer: Kerrigan, Eric C. Organizer: Johansen, Tor	Norweigian Univ. of Science &
Misovec, Kathleen	Alphatech, Inc.	Arne	Tech.
Inanc, Tamer Wohletz, Jerry	California Inst. of Tech. Alphatech, Inc.	09:20 Multiparametric Nonlinear Integ	ver Programming and Explicit
Murray, Richard M.	California Inst. of Tech.	Quantized Optimal Control (I),	
10:20		Bemporad, Alberto	Univ. of Siena
Control of Underactuated Mechan		09:40	at in O and at in Danish was in a (i)
Higher-Order Averaging Theory, 3 Vela, Patricio A.	California Inst. of Tech.	Furtner Results on Multiparame	etric Quadratic Programming (I),
Burdick, Joel W.	California Inst. of Tech.		Norwegian Univ. of Science & Tech.
10:40			Norwegian Univ. of Science & Tech. Univ. of Siena
Planar Propulsion through the Mai 3118	nipulation of Circulatory Flows,	Bemporad, Alberto 10:00	Only. of Signa
Kelly, Scott D.	Univ. of Illinois at Urbana- Champaign	Complexity Reduction of Recedence Grieder, Pascal	ding Horizon Control, 3179 ETH , Zurich
Hukkeri, Ramadev B.	Univ. of Illinois at Urbana- Champaign	Morari, Manfred	Swiss Federal Inst. of Tech.
11:00		10:20 Approximate Convex Multipara	metric Programming (I) 3185
Nonlinear Block Integral Sliding M	ode Control: Application to	Bemporad, Alberto	Univ. of Siena
Induction Motor Control., 3124 Rios Gastelum, Omar	Cinvestav Unidad Guadalajara	Filippi, Carlo 10:40	Univ. Degli Studi Di Padova
Guadalupe Castillo-Toledo, Bernardino	Cinvestav Unidad Guadalajara	Infinite Time Optimal Control of	f Hybrid Systems with a Linear
Loukianov, Alexander G.	Cinvestav Unidad Guadalajara	Performance Index (I), 3191 Baotic, Mato	ETH - Swiss Federal Inst. of Tech.
ThA03 Fundamental Limits on	Regency B Invited Session	Christophersen, Frank J. Morari, Manfred	ETH - Swiss Federal Inst. of Tech. Swiss Federal Inst. of Tech.
Communication and Control Chair: Mitter, Sanjoy K.	Massachusetts Inst. of Tech.	11:00 An Algorithm for Multi-Paramet Optimisation (I), 3197	tric Mixed Integer Semidefinite
Co-Chair: Tatikonda, Sekhar Organizer: Elia, Nicola	Yale Univ. Iowa State Univ.	Rowe, Camile	Univ. of Cambridge
Organizer: Elia, Nicola Organizer: Tatikonda, Sekhar	Yale Univ.	Maciejowski, Jan M.	Univ. of Cambridge

ThA05 Languages, Logic and	Maui Suite 1 Regular Session	11:00	or ar a second
Discrete-Events Systems		Adaptive Control Design for n-Th Or Parameterized Systems with Triang	der Nonlinearly Multiplicative ular Structure and Application
Chair: Ray, Asok Co-Chair: Kumar, Ratnesh	Pennsylvania State Univ.	3268	
•	Iowa State Univ.	Yokoi, Kiyoshi	SIC
09:20 Normalized Cascade Structures and Stat	to Foodbook Control Louis	Hung, Nguyen Van Qui Tuan, Hoang Duong	Toyota Tech. Ins
Normalized Cascade Structures and Stat Synthesis, 3203 Dong, Lida		Hosoe, Shigeyuki	Toyota Tech. Ins Nagoya Uni
Wu, Weimin	Zhejiang Univ. Zhejiang Univ.	ThA07	Regency Boardrooi
Su, Hongye	Zhejiang Univ.	New Trends on Geometric and	Invited Session
Chu, Jian	Zhejiang Univ.	Optimal Control II	
9:40	, ,	Chair: Boscain, Ugo V.	SISSA-ISA
Robust Optimal Control of Regular Langu	uages with Event Cost	Co-Chair: Piccoli, Benedetto	I.A.CC.N.F
Incertainties, 3209	3	Organizer: Boscain, Ugo V.	SISSA-ISA
	e Pennsylvania State Univ.	Organizer: Piccoli, Benedetto	I.A.CC.N.F
Lagoa, Constantino M.	Pennsylvania State Univ.	09:20	
Ray, Asok 0:00	Pennsylvania State Univ.	From Geometric Optimization and N Distributed Coordination Algorithms	lonsmooth Analysis to (I), 3274
inite-State Machine Embeddings for Nor Detection and Identification, 3215	n-Concurrent Error	Cortes, Jorge	Univ. of Illinois at Urbana Champaig
	Univ. of Illinois at Urbana- Champaign	Bullo, Francesco	Univ. of Illinois at Urbana Champaig
0:20	pa.g.	09:40	• -
Diagnosis of Repeated Failures for Discre inear-Time Temporal Logic Specification		Sensitivity Analysis of Optimal Cont Controls (I), 3281	rol Problems with Bang-Bang
Jiang, Shengbing  Kumar, Ratnesh	General Motors Corp.  lowa State Univ.	Maurer, Helmut Kim, Jang-Ho Robert	Univ. Münste Univ. Münste
0:40	and other	10:00	
Solution for Combinational and Asynch	ronous Sequential Logic	Cooperative Controls for Car-Like R	obot Coordination (I), 3287
roblems by Means of Logic Variable, 32	227	Piccoli, Benedetto	I.A.CC.N.
Elizondo-González, César	UANL	Marigo, Alessia	I.A.CC.N.I
1:00	e*	Vergni, Davide	I.A.CC.N.I
Signed Real Measure of Regular Langua		10:20	
Surana, Amit The Ray, Asok	Pennsylvania State Univ. Pennsylvania State Univ.	Uniquenes Results for the Value Ful Construction Methods (I), 3293	• •
hA06		Sussmann, Hector J.	Rutgers Uni
irect Adaptive Control		10:40 A Light Weight Rotary Double Pend	ulum: Maximizing the Domain
Chair: Ortega, Romeo Co-Chair: Hung, Nguyen Van	LSS-SUPELEC Toyota Tech. Inst.	of Attraction (I), 3299 Brockett, Roger	Harvard Univ
Qui	Toyota Tech. mst.	Li, Hongyi	Harvard Uni
9:20		11:00	, i.i. vai a 0111
nmersion and Invariance Model Referen arameterizations for the Problem, 3239	ce Adaptive Control: New	Generic Bifurcations of Control-Affin Their Properties (I), 3305	e Systems in the Plane and
Ortega, Romeo	LSS-SUPELEC	Jakubczyk, Bronislaw	Pol. Acad. of Science
Astolfi, Alessandro	Imperial Coll.	Respondek, Witold	Inst. National des Science
Hsu, Liu COPPE	E - Federal Univ. of Rio de Janeiro	•	Appliquee
9:40		ThA08	Maui Suite
pordinated Decentralized Output-Feedb		Mechanical Systems I	Regular Session
IMO Subsystems with Delayed Commu	,	Chair: Tornambe, Antonio Co-Chair: Egeland, Olav N	Univ. Di Roma Tor Vergat orwegian Univ. of Sci. & Tecl
Mirkin, Boris Gutman, Per-Olof	Tech.	· · · · · · · · · · · · · · · · · · ·	orwegian only, or ser, & rec
•	Tech.	09:20 Control of a Simple Mechanism Sub	iont to Unilatoral Comptent
):00 Rifelsified Medel Reference Adentive Co	atrol Haine the Fill and	Control of a Simple Mechanism Sub 3311	ect to Unitateral Constraints,
nfalsified Model Reference Adaptive Co	ritroi Using the Ellipsoid	Galeani, Sergio	Univ. di Roma Tor Vergat
lgorithm, 3250	Inst Militar de Engenharia	Menini, Laura	Univ. di Roma 1 or Verdat
gorithm, 3250 Cabral, Fabricio B.	Inst. Militar de Engenharia niv. of Southern California	Menini, Laura Tornambe, Antonio	
gorithm, 3250 Cabral, Fabricio B. I Safonov, Michael G. Ur	inst. Militar de Engenharia niv. of Southern California	Tornambe, Antonio	
gorithm, 3250 Cabral, Fabricio B. I Safonov, Michael G. Ui 0:20 odel Reference Adaptive Control Using	niv. of Southern California		Univ. di Roma Tor Vergat  Control, 3313
Igorithm, 3250 Cabral, Fabricio B. Safonov, Michael G. Ui 0:20 Iodel Reference Adaptive Control Using witching, 3256 Paul, Ayanendu Univ. of Souther	niv. of Southern California  Multiple Controllers & rn California, Los Angeles	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios	Univ. di Roma Tor Vergal  Control, 3313  Univ. of Marylan
Igorithm, 3250 Cabral, Fabricio B. I Safonov, Michael G. Ui 0:20 Iodel Reference Adaptive Control Using witching, 3256 Paul, Ayanendu Univ. of Souther Safonov, Michael G. Ui	niv. of Southern California  Multiple Controllers &	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios 10:00	Univ. di Roma Tor Vergat Control, 3313 Univ. of Marylan Univ. of Marylan
lgorithm, 3250 Cabral, Fabricio B. I Safonov, Michael G. Ur 0:20 ordel Reference Adaptive Control Using witching, 3256 Paul, Ayanendu Univ. of Southel Safonov, Michael G. Ur 0:40	niv. of Southern California  Multiple Controllers & rn California, Los Angeles niv. of Southern California	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios	Univ. di Roma Tor Vergat  Control, 3313  Univ. of Marylan  Univ. of Marylan  epper Motors, 3319
Igorithm, 3250 Cabral, Fabricio B. Safonov, Michael G. Ur 0:20 Iodel Reference Adaptive Control Using witching, 3256 Paul, Ayanendu Univ. of Southel Safonov, Michael G. Ur 0:40 In Adaptive Observer for Dynamical Ship	niv. of Southern California  Multiple Controllers & rn California, Los Angeles niv. of Southern California	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios 10:00 Spontaneous Speed Reversals in Si	Univ. di Roma Tor Vergat Control, 3313 Univ. of Marylan Univ. of Marylan repper Motors, 3319 Univ. of Uta
Igorithm, 3250 Cabral, Fabricio B. Safonov, Michael G. Ur 0:20 Iodel Reference Adaptive Control Using witching, 3256 Paul, Ayanendu Univ. of Southel Safonov, Michael G. Ur 0:40 In Adaptive Observer for Dynamical Ship	niv. of Southern California  Multiple Controllers & rn California, Los Angeles niv. of Southern California	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios 10:00 Spontaneous Speed Reversals in St Bodson, Marc	Univ. di Roma Tor Vergat Control, 3313 Univ. of Marylan Univ. of Marylan epper Motors, 3319 Univ. of Uta L-3 Communication
Algorithm, 3250 Cabral, Fabricio B. I Safonov, Michael G. Ur 0:20 Andel Reference Adaptive Control Using Switching, 3256 Paul, Ayanendu Univ. of Souther Safonov, Michael G. Ur 0:40 An Adaptive Observer for Dynamical Ship Vectorial Observer Backstepping, 3262	niv. of Southern California  Multiple Controllers &  rn California, Los Angeles niv. of Southern California  Position Control Using	Tornambe, Antonio 09:40 Stochastic Language-Based Motion Andersson, Sean Hristu-Varsakelis, Dimitrios 10:00 Spontaneous Speed Reversals in St Bodson, Marc Sato, Jeffrey	Univ. of Marylan Univ. of Marylan

10:20 Tracking and Observer Design fo			
Tracking and Observer Design for		09:40	
	r a Motorized Euler-Bernoulli	Controllability of Direction-Depe	
Beam, 3325	Name of Original And	Rosenqvist, Fredrik	Chalmers Univ. of Tech.
Nguyen, Tu Duc	Norwegian Univ. of Science And Tech.	Karlstrom, Anders	Chalmers Univ. of Tech.
Egeland, Olav	Norwegian Univ. of Sci. & Tech.	10:00	
10:40	reciwegian ciniv. of con. a recin.	Decentralized Motion Control of Multiple Holonomic Agents under Input Constraints, 3390	
10.40 Extended Generalized Impedance	a Control for Padundant	Dimarogonas, Dimos	National Tech. Univ. of Athens
Exterided Gerieralized Impedance Manipulators, 3331	Control for Redundant	Zavlanos, Michalis	National Tech. Univ. of Athens
Pholsiri, Chalongrath	Robotics Res. Group, Univ. of	Loizou, Savvas	National Tech. Univ. of Athens
· · · · · · · · · · · · · · · · · · ·	Texas at Austin	Kyriakopoulos, Kostas J.	National Tech. Univ. of Athens
Rabindran, Dinesh	Robotics Res. Group, Univ. of	10:20	
	Texas at Austin		Rotary Motion of Devil Stick, 3396
Pryor, Mitch	Robotics Res. Group, Univ. of	Kawaida, Yasuyuki	FUJITSU Ltd.
	Texas at Austin	Nakaura, Shigeki	Tokyo Inst. of Tech.
Kapoor, Chetan	Robotics Res. Group, Univ. of	Ohata, Ryusuke	Tokyo Inst. of Tech.
	Texas at Austin	Sampei, Mitsuji	Tokyo Inst. of Tech.
11:00		10:40	
Revisiting Problems Associated with Structural Properties of Robots with Applications to Controller Design, 3337			ent for Descriptor Linear Systems:
Ailon, Amit	Ben Gurion Univ. of The Negev	A Complete Parametric Approa	
Berman, Nadav	Ben Gurion Univ. of The Negev	Duan, Guang-Ren	Harbin Inst. of Tech.
Arogeti, Shai	Ben Gurion Univ. of the Negev	Wang, Guo-sheng	Harbin Inst. of Tech.
300., 01		11:00	
ThA09	Maui Suite 4	Quadratically Constrained Attitu	ide Control Via Semidefinite
Language-Based Descriptions	Invited Session	Programming, 3408	Hate agrades to
of Multi-Modal Control Tasks		Kim, Yoonsoo	Univ. of Washington Univ. of Washington
Chair: Hristu-Varsakelis,	Univ. of Maryland	Mesbahi, Mehran	Only, or washington
Dimitris		ThA11	Guest Room 351
Co-Chair: Egerstedt, Magnus	Georgia Inst. of Tech.	Control Applications I	
Organizer: Hristu-Varsakelis,	Univ. of Maryland	Chair: Rai, Sudhendu	Xerox Corp.
Dimitris Organizer: Egerstedt,	Coordin Inst. of Took	Co-Chair: Mestha, Lalit K.	Xerox Corp.
Magnus	Georgia Inst. of Tech.	09:20	•
-		Track-Following Control of Hard	d Disk Drives Using Multi-Rate
09:20 Encoding Steering Control with S	umbolo (I) 2242	Sampled-Data H-Infinity Contro	
Encoding Steering Control with S Bicchi, Antonio	Univ. di Pisa	Hirata, Mitsuo	Chiba Univ.
Marigo, Alessia	IAC-CNR	Takiguchi, Masatoshi	Chiba Univ.
Piccoli, Benedetto	I.A.CC.N.R.	Nonami, Kenzo	Chiba Univ.
09:40		09:40	
Minimizing Attention in a Motion (	Control Context (I), 3349		Control of Hard Disk Drives for
Brockett, Roger	Harvard Univ.	Computation Saving, 3420	
10:00		Hirata, Mitsuo	Chiba Univ.
Observation of Guarded Commar	nd Programs (I), 3353	Tomizuka, Masayoshi	Univ. of California at Berkeley
Del Vecchio, Domitilla	California Inst. of Tech.	10:00	
Klavins, Eric	Univ. of Washington	A Nonlinear Dynamic Filter to Ir Optical Storage Drives, 3426	nnrove Disturbance Rejection in
			riprove Disturbance (Nejection in
10:20			
	ne Motion Description Language	Heertjes, Marcel	Philips Centre For Industrial
On the Structural Complexity of the	, ,	Heertjes, Marcel	Philips Centre For Industrial Tech.
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris	Univ. of Maryland		Philips Centre For Industrial Tech. Philips Centre For Industrial
Egerstedt, Magnus	Univ. of Maryland Georgia Inst. of Tech.	Heertjes, Marcel Sperling, Frank	Philips Centre For Industrial Tech. Philips Centre For Industrial
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris	Univ. of Maryland	Heertjes, Marcel Sperling, Frank 10:20	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech.
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S. 10:40	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech.
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S. 10:40 From Discrete Specifications to He	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S. 10:40 From Discrete Specifications to Hamada, Paulo	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland Hybrid Control (I), 3366 Univ. of Notre Dame	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara
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On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S.  10:40 From Discrete Specifications to Habuada, Paulo Pappas, George J.  11:00	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland Hybrid Control (I), 3366 Univ. of Notre Dame Univ. of Pennsylvania	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431 Ranaweera, Aruna	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara Univ. of California at Santa Barbara Univ. of California at Santa
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On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S. 10:40 From Discrete Specifications to Habuada, Paulo Pappas, George J. 11:00 Explicit Solutions for Optimal Mat 3372	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland Hybrid Control (I), 3366 Univ. of Notre Dame Univ. of Pennsylvania	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431 Ranaweera, Aruna Bamleh, Bassam	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara Univ. of California at Santa Barbara Univ. of California at Santa
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On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S.  10:40 From Discrete Specifications to Hamada, Paulo Pappas, George J.  11:00 Explicit Solutions for Optimal Mara 3372 Frazzoli, Emilio	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland  dybrid Control (I), 3366 Univ. of Notre Dame Univ. of Pennsylvania  neuver-Based Motion Planning (I),  Univ. of Illinois at Urbana- champaign  Guest Room 350	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431 Ranaweera, Aruna Bamieh, Bassam Teel, Andrew R.  10:40 Optimization, Estimation, and O Simulations of Thin Film Depos	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara Univ. of California at Santa Barbara Univ. of California at Santa Barbara
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On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S.  10:40 From Discrete Specifications to Hamber Tabuada, Paulo Pappas, George J.  11:00 Explicit Solutions for Optimal Mara 3372 Frazzoli, Emilio  ThA10 Constrained Control I Chair: Tanner, Herbert Co-Chair: Petersen, John 09:20 Constrained Quadratic Programm	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland  dybrid Control (I), 3366 Univ. of Notre Dame Univ. of Pennsylvania  neuver-Based Motion Planning (I),  Univ. of Illinois at Urbana- champaign  Guest Room 350 Regular Session Univ. of New Mexico Raytheon Missile Systems	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431 Ranaweera, Aruna Bamieh, Bassam Teel, Andrew R.  10:40 Optimization, Estimation, and Composition of Thin Film Deposition of Thin Film Deposition of The Simulation of Thin Film Deposition of Thin Film	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara Univ. of California at Santa Barbara Univ. of California at Santa Barbara Control for Kinetic Monte Carlo ition, 3437 Georgia Inst. of Tech. Pomic Force Microscopy, 3443 Iowa State Univ. Asylum Res.
On the Structural Complexity of the MDLe (I), 3360 Hristu-Varsakelis, Dimitris Egerstedt, Magnus Krishnaprasad, P. S.  10:40 From Discrete Specifications to Habuada, Paulo Pappas, George J.  11:00 Explicit Solutions for Optimal Mara 3372 Frazzoli, Emilio  Tha10 Constrained Control 1 Chair: Tanner, Herbert	Univ. of Maryland Georgia Inst. of Tech. Univ. of Maryland  dybrid Control (I), 3366 Univ. of Notre Dame Univ. of Pennsylvania  neuver-Based Motion Planning (I),  Univ. of Illinois at Urbana- champaign  Guest Room 350 Regular Session Univ. of New Mexico Raytheon Missile Systems	Heertjes, Marcel Sperling, Frank  10:20 Nonlinear Stabilization of a Sph Optical Tweezer, 3431 Ranaweera, Aruna Bamieh, Bassam Teel, Andrew R.  10:40 Optimization, Estimation, and Composition of Thin Film Deposition of Thin Film Deposition of The Simulation of Thin Film Deposition of Thin Film	Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Philips Centre For Industrial Tech. Perical Particle Trapped in an Univ. of California, Santa Barbara Univ. of California at Santa Barbara Univ. of California at Santa Barbara Control for Kinetic Monte Carlo ition, 3437 Georgia Inst. of Tech.

Chair: Rohwer, Judd	Sandia National Lab.	Elimination of Harmonics in a M Theory of Symmetric Polynomia	
Co-Chair: Hadjicostis,	Univ. of Illinois at Urbana-	Chiasson, John	The Univ. of Tenness
Christoforos	Champaign	Tolbert, Leon	The Univ. of Tenness
09:20		McKenzie, Keith	The Univ. of Tenness
On the Tangential Q-Markov COV	ER Problem, 3445	Du, Zhong	The Univ. of Tenness
Enqvist, Per	INRIA		
Gombani, Andrea	CNR	ThA14	Guest Room 4
09:40		Sliding Mode Control I	Regular Sess
Least Squares Support Vector Ma Estimation, 3451	chines and Primal Space	Chair: Fridman, Leonid M.	National Autonomous Univ Mex
Espinoza, Marcelo	Katholieke Univ. Leuven, Belgium	Co-Chair: Costa, Ramon R.	COPPE - Federal Univ. of Rio Jane
Suykens, J.A.K.	Katholieke Univ. Leuven	09:20	
De Moor, Bart L.R. 10:00	Katholieke Univ. Leuven	Variable Structure Control of Sy Perturbed Analysis, 3513	nchronous Generator: Singularly
An EM Algorithm for Singular State	e Space Models, 3457	Soto, Adolfo	Ph.d. Stud
Solo, Victor	Univ. of New South Wales	Fridman, Leonid M.	National Autonomous Univ Mex
10:20	- Identification Alexanther 0404	Loukianov, Alexander G.	CINVEST
A Random Trimmed Least Square Bai, Er-Wei	S Identification Algorithm, 3461 Univ. of Iowa	Canedo, Jose M. 09:40	CINVEST
10:40			ling-Mode Control Scheme Robi
Stochastic Subspace Identification		against the Measurement Noise	
Tanaka, Hideyuki	Kyoto Univ.	Pisano, Alessandro	Univ. di Cag
Katayama, Tohru	Kyoto Univ.	Usai, Elio	Univ. degli Studi di Cag
11:00		10:00	-
Improving the Numerical Efficiency			ence Adaptive Control for System
Produced by the Combined Deterr Identification Algorithms, 3473	·	with Unknown High Frequency yan, lin	
Lopes dos Santos, P.	Faculdade de Engenharia da Univ. do Porto	Hsu, Liu	Jan COPPE - Federal Univ. of Ric
de Carvalho, J.L. Martins	Faculdade de Engenharia da Univ. do Porto	Costa, Ramon R.	Jan COPPE - Federal Univ. of Ric
ThA13	Guest Room 450		Jan
Polynomial Methods in	Invited Session	Lizarralde, Fernando C.	Federal Univ. of Rio de Jane
Control		10:20	
Chair: Henrion, Didier	LAAS-CNRS	Design of First Order Approxima	ation Hitters Applied to Sliding
Co-Chair: Sebek, Michael	Czech Tech. Univ. in Prague	Mode Control, 3531 Cunha, Jose Paulo V. S.	State Univ. of Rio de Jan-
Organizer: Henrion, Didier Organizer: Sebek, Michael	LAAS-CNRS Czech Tech. Univ. in Prague	Costa, Ramon R.	COPPE - Federal Univ. of Ric Jan
09:20		Hsu, Liu	COPPE - Federal Univ. of Ric
Hyperbolic QR Factorization for J- Polynomial Matrices (I), 3479		10:40	Jan
Henrion, Didier	LAAS-CNRS	Adaptive Gain Sliding Observer	Based Sliding Controller for
Hippe, Peter	Univ. Erlangen-Nuernberg	Uncertain Parameters Nonlinea	
09:40		Joint Robots, 3537	Systems. Approach to Alexion
Characterizing Polynomials with R	oots in a Semialgebraic Set (I),	FILIPESCU, ADRIAN	U
3485	01/00	Dugard, Luc	CNRS-IN
Lasserre, Jean B.	CNRS	Dion, Jean-Michel	URA CN
10:00	to Balanco de la trata de la t	11:00	
mportance of Coefficient Diagram Manabe, Shunji	in Polynomial Method (I), 3489 Retired, formerly Tokai Univ.	Sliding Mode Control Design Us Lee, Seung Hi	ing Fast Output Sampling, 3543 Samsung Adv. Inst. of Te
10:20	•	Chung, Chung Choo	Hanyang U
Time-Varying Optimal Control of a			
	Univ. of Strathclyde	ThAPI	Grand Promen
Martin, Peter	Univ. of Strathclyde	Strategies for Human-	Invited Poster/Interactive Sess
Grimble, Michael John	onn. or othernory ac	Automaton Resource Entity	
Grimble, Michael John 10:40	-		
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete	-Time SISO H2 and H-Infinity	Deployment	The Otto October
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete Controller Synthesis: Summary of t	-Time SISO H2 and H-Infinity	Deployment Chair: Cruz, Jose	
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete Controller Synthesis: Summary of t Solution (I), 3501	-Time SISO H2 and H-Infinity the Results and Existence of	Deployment Chair: Cruz, Jose Organizer: Cruz, Jose B.	The Ohio State Ui The Ohio State Ui
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete Controller Synthesis: Summary of t	-Time SISO H2 and H-Infinity the Results and Existence of Univ. of Illinois at Urbana-	Deployment Chair: Cruz, Jose Organizer: Cruz, Jose B. 09:20	The Ohio State U
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete Controller Synthesis: Summary of Solution (I), 3501 Bentsman, Joseph	-Time SISO H2 and H-Infinity the Results and Existence of Univ. of Illinois at Urbana- Champaign	Deployment Chair: Cruz, Jose Organizer: Cruz, Jose B. 09:20 Automated Support for Human I	The Ohio State U
Grimble, Michael John 10:40 Minimal Order Polynomial Discrete Controller Synthesis: Summary of t Solution (I), 3501	-Time SISO H2 and H-Infinity the Results and Existence of Univ. of Illinois at Urbana-	Deployment Chair: Cruz, Jose Organizer: Cruz, Jose B. 09:20	The Ohio State U

Area Search and Engagement (I), 35.			edictive Control of Multiple Flying
Decker, Doug	Air Force Inst. of Tech.	Robots, 3621	, , ,
Jacques, David Pachter, Meir	Air Force Inst. of Tech. Air Force Inst. of Tech.	Shim, David Hyunchul	ACAP LLC
r acriter, wen	All I bloc list of rech.	Kim, H. Jin	Univ. of California at Berkeley
Toom Disposion and Tootion in Chroti	ning faultumen Automaton	Sastry, Shankar	Univ. of California at Berkeley
Team Dynamics and Tactics in Strate Resource Entity Deployment (I), 3561	gies for Human-Automaton	ThM02	<b>.</b>
Liu, Yong	Univ. of Pittsburgh	Nonlinear Systems IV	Regency A Regular Session
Galati, David	Univ. of Pittsburgh	Chair: Michalska, Hannah H.	McGill Univ.
Simaan, Marwan A.	Univ. of Pittsburgh	Co-Chair: Perruquetti, Wilfrid	Ec. Centrale de Lille
	Cimi or r mobargi.	• •	EC. Centrale de Line
Cooperative Control for UAV's Searc	hina Picky Environments for	14:00	5 B.W.
Targets (I), 3567	ing Naky Environments for	Results on Converse Lyapunov Th Inclusions, 3627	leorems for Difference
Flint, Matthew	Univ. of Cincinnati	Kellett, Christopher	Univ. of Melbourne
Fernandez-Gaucherand.	Univ. of Cincinnati	Teel, Andrew R.	Univ. of California at Santa
Emmanuel		700,7 110,1017 11.	Barbara
Polycarpou, Marios M.	Univ. of Cincinnati	14:20	
•		Nonlinear Programming and the C	BU Formula in Foodback
Stability Analysis of Swarms in a Nois	sy Environment (I) 3573	Stabilization of Nonlinear Systems	
Liu, Yanfei	The Ohio State Univ.	Michalska, Hannah H.	McGill Univ
Passino, Kevin	Ohio State Univ.	Torres-Torriti, Miguel	McGill Univ
	0 0000 01117.	, <b>u</b>	Wicein Only.
eam Dynamics and Tootion for Mice	ion Planning (I) 2570	14:40	and the Assessed to the
eam Dynamics and Tactics for Miss Cruz. Jose	The Ohio State Univ.	Gaussian Radial Basis Functions	and the Approximation of Input-
Chen, Genshe	The Ohio State Univ.	Output Maps, 3635	Univ. of Taylor of Assets
Garagic, Denis	The Ohio State Univ.	Sandberg, Irwin W.	Univ. of Texas at Austir
Tan, Xiaohuan	The Ohio State Univ.	15:00	
Li, Dongxu	The Ohio State Univ.	Finite Time Stability of Non Linear	
Shen, Dan	The Ohio State Univ.	moulay, Emmanuel	Ec. Centrale de Lille
Wei, Mo	The Ohio State Univ.	Perruquetti, Wilfrid	Ec. Centrale de Lille
Wang, Xu	The Ohio State Univ.	15:20	
<b>3</b> .		Low Order Representation of Non-	
Battle Management for Unmanned A	arial Vahiolas /IV 3585	Starkl, Reinhard	Johannes Kepler Univ
Xu, Lu	The Ohio State Univ.	Del Re, Luigi	Johannes Kepler Univ. Linz
Ozguner, Umit	The Ohio State Univ.	15:40	
Ozganer, Onni	THE OTHO State OTHY.	Observability Quadratic Character	istic Numbers., 3653
ThNPL	Monarchy Ballroom	Chabraoui, Samira	Ec.
Plenary Panel: CSS Presidents	Plenary Panel	Boutat, Driss	Ensi De Bourges
Chair: Masten, Michael K.	Texas Inst Retired	Boutat-baddas, Latifa	Ec.
		Barbot, Jean Pierre	ENSEA
ThM01	Monarchy Ballroom	71.220	
ormation Control	Regular Session	ThM03	Regency B
Chair: Fierro, Rafael	Oklahoma State Univ.	Stability of Communication	Regular Session
Co-Chair: Sastry, Shankar	Univ. of California at Berkeley	Networks (III)	INDIA ENG
4:00		Chair: Kim, Ki-Baek	INRIA-ENS
uel Optimal Initialization of a Space	craft Formation, 3591	Co-Chair: Bauer, Peter H.	Notre Dame Univ
Yang, Guang	Pol. Univ.	14:00	
Kapila, Vikram	Pol. Univ.	Stability of Adaptive Congestion C	ontrollers for High Bandwidth
	Pol. Univ.	Connections, 3659	
		Kunniyur, Srisankar	Univ. of Pennsylvania
Wong, Hong			Univ. of Donneylyania
Wong, Hong 4:20	riodic Traincton, Tracking for	Kavak, Egemen	Only. Of Pennisylvania
Wong, Hong 4:20 daptive Learning Control-Based Per	riodic Trajectory Tracking for	Kavak, Egemen 14:20	Only. Of Fernisylvania
Wong, Hong 4:20 daptive Learning Control-Based Per pacecraft Formations, 3597	, , ,	• •	
Wong, Hong 4:20 daptive Learning Control-Based Per pacecraft Formations, 3597 Wong, Hong	Pol. Univ.	14:20	al Queue Dynamics in
Wong, Hong 4:20 daptive Learning Control-Based Per spacecraft Formations, 3597 Wong, Hong Kapila, Vikram	, , ,	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek	al Queue Dynamics in ays, 3665 INRIA-ENS
Wong, Hong 4:20 daptive Learning Control-Based Per pacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40	Pol. Univ. Pol. Univ.	14:20 A Stabilizing AQM Based on Virtu Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate
Wong, Hong 4:20 daptive Learning Control-Based Peripacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 formation Flying Control of a Pair of	Pol. Univ. Pol. Univ.	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate
Wong, Hong 4:20 daptive Learning Control-Based Perpaceraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of twitching Predictive Control, 3603	Pol. Univ. Pol. Univ. Nano-Satellites Based on	14:20 A Stabilizing AQM Based on Virtu Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate
Wong, Hong 4:20 Idaptive Learning Control-Based Perspacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 Formation Flying Control of a Pair of Switching Predictive Control, 3603 Mosca, Edoardo	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence	14:20 A Stabilizing AQM Based on Virtue Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40 Global Stability with Time-Delay of	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze	14:20 A Stabilizing AQM Based on Virtue Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40 Global Stability with Time-Delay of	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion Univ. of California, Los Angeles
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 formation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 teering Laws and Continuum Model	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze	14:20 A Stabilizing AQM Based on Virtus Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion Univ. of California, Los Angeles
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 teering Laws and Continuum Model Justh, Eric	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze s for Planar Formations, 3609 Univ. of Maryland	14:20 A Stabilizing AQM Based on Virtus Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven  14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando  15:00	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion Univ. of California, Los Angeles Univ. of California, Los Angeles
Wong, Hong 4:20 daptive Learning Control-Based Perpacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of witching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 teering Laws and Continuum Model Justh, Eric Krishnaprasad, P. S.	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven  14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando  15:00 Asymptotic Stability of Congestion	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion Univ. of California, Los Angeles Univ. of California, Los Angeles
Wong, Hong 4:20 Idaptive Learning Control-Based Perspacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 Formation Flying Control of a Pair of Switching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 Steering Laws and Continuum Model Justh, Eric Krishnaprasad, P. S. 5:20	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze is for Planar Formations, 3609 Univ. of Maryland Univ. of Maryland	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven  14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando  15:00 Asymptotic Stability of Congestion Sources, 3677	al Queue Dynamics in ays, 3665 INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion Univ. of California, Los Angeles Univ. of California, Los Angeles
Wong, Hong 4:20 daptive Learning Control-Based Peripacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 ormation Flying Control of a Pair of switching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 5:00 Justh, Eric Krishnaprasad, P. S. 5:20 Dual-Mode Model Predictive Control	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze is for Planar Formations, 3609 Univ. of Maryland Univ. of Maryland	14:20 A Stabilizing AQM Based on Virtu. Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven  14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando  15:00 Asymptotic Stability of Congestion	al Queue Dynamics in ays, 3665  INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion  Univ. of California, Los Angeles Univ. of California, Los Angeles Control Systems with Multiple  NC State Univ
Wong, Hong 4:20 Adaptive Learning Control-Based Perspacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 Formation Flying Control of a Pair of Switching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 Atteering Laws and Continuum Model Justh, Eric Krishnaprasad, P. S. 5:20 A Dual-Mode Model Predictive Control 615	Pol. Univ. Pol. Univ. Pol. Univ. Nano-Satellites Based on  Univ. of Florence Univ. Della Calabria Univ. di Firenze di For Planar Formations, 3609 Univ. of Maryland Univ. of Maryland Univ. of Maryland Coller for Robot Formations,	14:20 A Stabilizing AQM Based on Virtue Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando 15:00 Asymptotic Stability of Congestion Sources, 3677 Sichitiu, Mihail L.	al Queue Dynamics in ays, 3665  INRIA-ENS PhD Candidate California Inst. of Tech f a Primal-Dual Congestion  Univ. of California, Los Angeles Univ. of California, Los Angeles Control Systems with Multiple  NC State Univ
Wong, Hong 4:20 Idaptive Learning Control-Based Perspacecraft Formations, 3597 Wong, Hong Kapila, Vikram 4:40 Formation Flying Control of a Pair of Switching Predictive Control, 3603 Mosca, Edoardo Casavola, Alessandro Bacconi, Fabio 5:00 Justh, Eric Krishnaprasad, P. S. 5:20 Loual-Mode Model Predictive Control	Pol. Univ. Pol. Univ. Nano-Satellites Based on Univ. of Florence Univ. Della Calabria Univ. di Firenze is for Planar Formations, 3609 Univ. of Maryland Univ. of Maryland	14:20 A Stabilizing AQM Based on Virtue Supporting TCP with Arbitrary Del Kim, Ki-Baek Tang, Ao Low, Steven 14:40 Global Stability with Time-Delay of Control, 3671 Wang, Zhikui Paganini, Fernando 15:00 Asymptotic Stability of Congestion Sources, 3677 Sichitiu, Mihail L.	ays, 3665  INRIA-ENS PhD Candidate California Inst. of Tech.  f a Primal-Dual Congestion  Univ. of California, Los Angeles Univ. of California, Los Angeles

15:20		14:40	
	tness of Network Flow Control, 3683	Distributed and Asynchronous Dis	screte Event Systems Diagnosis
Fan, Xingzhe	Rensselaer Pol. Inst.	3742	crete Evern Oysterns Diagnosis,
Arcak, Murat	Rensselaer Pol. Inst.	Benveniste, Albert	IRISA-INRIA
Wen, John T.	Rensselaer Pol. Inst.	Haar, Stefan	Inria
	Transcribe. For their	Fabre, Eric	IRISA / INRIA
15:40	stability in Bata Controlled Naturalis	Jard, Claude	CNRS
3689	stability in Rate-Controlled Networks,	15:00	<b>5</b>
Ranjan, Priya	Univ. of Maryland, Coll. Park	Partial Order Diagnosability of Dis	errata Evant Systems Using Patri
Abed, Eyad H.	Univ. of Maryland, Coll. Park	Net Unfoldings, 3748	crete Event Systems Osing Feth
La, Richard J.	Univ. of Maryland, Coll. Park	Haar, Stefan	INRIA-IRISA
La, Monard J.	Offiv. of Maryland, Coll. 1 ark	Benveniste, Albert	INRIA-IRISA
ThM04	Regency C	Fabre, Eric	INRIA-IRISA
Model Predictive Control		Jard, Claude	CNRS-IRISA
Chair: Wills, Adrian	Univ. of Newcastle	15:20	
Co-Chair: Helmick, Daniel		Some Results on the Computation	n of Minimal Sinhons in Petri
14:00	<b>3.</b>	Nets. 3754	TO Millina Siphons in Feat
	Control for Constrained Linear	Cordone, Roberto	Univ. degli Studi di Milano
Systems: Stability Results, 36	Control for Constrained Linear	Ferrarini, Luca	Pol. di Milano
Rojas, Osvaldo J.	The Univ. of Newcastle	Piroddi, Luigi	Pol. di Milano
Seron, Maria	The Univ. of Newcastle	· •	i di di milano
Goodwin, Graham C.	Univ. of Newcastle	15:40	in Intermediad Detri Mate: A
	Gilly, Of Mewodastic	Sensor Selection for Observability	ını ınterpretea Petri Nets: A
14:20		Genetic Approach, 3760	Cuspur Univ De Cuadalaises
An Exterior/Interior-Point App	roach to inteasibility in Model	Aguirre-Salas, Luis	Cucsur Univ. De Guadalajara
Predictive Control, 3701	ljebi akklasses o	ThM06	Maui Suite 2
Wills, A. G.	Univ. of Newcastle		
Heath, W. P.	Univ. of Newcastle	Modeling and Adaptation Chair: Khammash, Mustafa	Regular Session Univ. of California at Santa
14:40		H.	Oniv. of California at Santa Barbara
	n a Contractive Sequence of Sets,	п. Co-Chair: de Callafon,	Univ. of California, San Diego
3706		Raymond A.	Offiv. of Camornia, San Diego
Limon, Daniel	Univ. de Sevilla	•	
Alamo, Teodoro	Univ. de Sevilla	14:00	4
Camacho, Eduardo F.	Univ. de Sevilla	Model Validation and Robustness	•
15:00		Shock Response Using SOSTOC	
Higher Order Modeling of Hys	teresis in Disk Drive Actuators, 3712	El-samad, Hana	Univ. of California at Santa
Helmick, Daniel	Carnegie Mellon Univ.	Dusing Stanban	Barbara
Messner, William	Carnegie Mellon Univ.	Prajna, Stephen	California Inst. of Tech. California Inst. of Tech.
15:20		Papachristodoulou, Antonis Khammash, Mustafa H.	Univ. of California at Santa
Two-Dimensional Frequency	Response Analysis and Insights for	Midilinasii, Mustala i i.	Barbara
Weight Selection in Cross-Dir	ectional Model Predictive Control,	Doyle, John C.	California Inst. of Tech.
3717		-	Camorna hist. of Tech.
Fan, Junqiang	Univ. of British Columbia	14:20	Madellia Kaleton AKada
Stewart, Greg E.	Honeywell Industrial Control	Coprime Factor Based Closed-Lo	op wodel validation Applied to a
Dumont, Guy A.	Univ. of British Columbia	Flexible Structure, 3772	Unit of California San Diago
15:40		de Callafon, Raymond A.	Univ. of California, San Diego
	s in Constrained Model Predictive	Crowder, Marianne	Univ. of California, San Diego
Control, 3724		14:40	
Grimm, Gene	Univ. of California, Santa Barbara	Required Event Sequences for Id	entification of Discrete Event
Messina, Michael J.	Univ. of California at Santa Barbara	Systems, 3778	011054 (0 11110 1111
Teel, Andrew R.	Univ. of California at Santa Barbara	Meda-Campana, Maria-Elena	CUCEA of Guadalajara Univ.
Tuna, Sezai E.	Univ. of California, Santa Barbara	Lopez-Mellado, Luis-Ernesto	CINVESTAV-IPN
		15:00	
ThM05	Maui Suite 1	Adaptive Backstepping Control of	Some Uncertain Nonlinear
Petri Nets	Regular Session	Oscillators, 3784	
Chair: Benveniste, Albert	IRISA-INRIA	ikhouane, Fayçal	Univ. Pol. de Catalunya
Co-Chair: Sreenivas,	Univ. of Illinois	Manosa, Victor	Univ. Pol. de Catalunya
Ramavarapu S.		Rodellar, Jose	Univ. Pol. de Catalunya
14:00		15:20	
	lets That Can Be Made Live by	Robust Flatness Based Control of	f an Electromagnetic Linear
Supervision, 3730		Actuator Using Adaptive PID Con	
Sreenivas, Ramavarapu S	. Univ. of Illinois	Mercorelli, Paolo	IAI Inst. für Automatisierung und
14:20			Informatik GmbH
	on for Resource Allocation Systems	Liu, Steven	Harz Univ. of Applied Studies
with Process Synchronization			and Res. (Hochschule Harz)
Chew, Song Foh	Purdue Univ.	Lehmann, Kai	IAI Inst. für Automatisierung und
Lawley, Mark	Purdue Univ.		Informatik GmbH
Reveliotis, Spyros	Georgia Inst. of Tech.		
	Coorgia mat. or reon.		

A New Superresolution Method in Antenna Array Signal Position Tracking for a Nonlinear Underactuated Hovercraft: Processing, 3796 Controller Design and Experimental Results, 3858 Univ. of California, Santa Barbara BARABANOV, Nikita E. North Dakota State Univ. ND. Aguiar, Antonio Pedro LISA Cremean, Lars B. California Inst. of Tech. Liss. Anna St.-Petersburg Electrotechnical Hespanha, Joao P. Univ. of California, Santa Barbara 15:40 A Design of Servo Controller for Nonlinear Systems Using State ThM07 Regency Boardroom Dependent Riccati Equation, 3864 **Optimization Algorithms** Regular Session Tokyo Denki Univ. Terashima, Satoru Chair: Campbell, Stephen L North Carolina State Univ. lwase, Masami Tokyo Denki Univ. Co-Chair: Megretski. Massachusetts Inst. of Tech. Furuta, Katsuhisa Tokyo Denki Unversity Alexandre Tokyo Denki Univ. Hatakeyama, Shoshiro Suzuki Satoshi Tokyo Denki Univ. 14:00 Initialization of Direct Transcription Optimal Control Software, 3802 ThM09 Maui Suite 4 Boeing Corp. North Carolina State Univ. **Power Systems** Regular Session Campbell, Stephen L. Kalla, N. N. North Carolina State Univ. Chair: Tolbert, Leon The Univ. of Tennessee Co-Chair: Chen. Jian Clemson Univ. 14:20 Stochastic Optimization with Inequality Constraints Using 14:00 Simultaneous Perturbations and Penalty Functions, 3808 Robust Output Feedback Design with Application to Power Johns Hopkins Univ. Systems, 3870 Wang, I-Jeng Zanchin, Volnei T. Univ. Federal do Rio Grande do Spall, James C. Johns Hopkins Univ. Sul 14:40 Univ. Federal Do Rio Grande Do Bazanella, Alexandre S. Positivity of Trigonometric Polynomials, 3814 Sul Megretski, Alexandre Massachusetts Inst. of Tech. 14:20 Nonlinear Controller for a Single Phase One Quadrant Unity Power An Asymptotically Efficient Algorithm for Finite Horizon Stochastic Factor Rectifier, 3876 Dynamic Programming Problems, 3818 Jain, Amit Univ. of Minnesota Chang, Hyeong Soo Sogang Univ. Behal, A. Clemson Univ. Univ. of Maryland Fu. Michael C. Mohan, Ned Univ. of Minnesota Marcus, Steven I. Univ. of Maryland 14:40 Perspectives for the Coordinated Design of Damping Controllers in Polynomial Complexity for a Nesterov-Todd Potential-Reduction Restructured Power Systems, 3882 Method with Inexact Search Directions, 3824 Ramos, Rodrigo A. Univ. Estadual do Oeste do Linköping Univ. Gillberg, Jonas Paraná Hansson, Anders Linkoping Univ. Escola de Enegnharia de São Oliveira, Ricardo V. 15:40 Carlos/USP Master-To-Slave Nonlinear Genetic Algorithm, 3830 Bretas, Newton G. Escola de Engenharia de São Cui, Zhi-hua Taiyuan Heavy Machinery Inst. Carlos / USP ThM08 Maui Suite 3 Impact of Generator Stator Dynamics on a Nonlinear Observability Mechanical Systems II Regular Session Formulation for Power System Dynamics, 3888 Chair: Jiang, Zhong Ping Pol. Univ. Drexel Univ. Dafis, Chris Co-Chair: Kelly, Rafael CICESE Nwankpa, Chika O. Drexel Univ. 14:00 Manipulator Velocity Field Control with Dynamic Friction Synchronous Motor VSS Control Using Recurrent High Order Compensation, 3834 Neural Networks, 3894 CICESE Moreno, Javier Campos, Joaquin Kelly, Rafael CICESE Loukianov, Alexander G. **CINVESTAV** 14:20 Sanchez, Edgar N. **CINVESTAV** Modeling of MR Damper with Hysteresis for Adaptive Vibration 15:40 Control, 3840 Active Noise Control of One Dimensional Duct Via Sampled-Data Sakai, Chiharu Keio Univ. Hinf Control, 3900 Ohmori, Hiromitsu Keio Univ. Kobayashi, Yasuhide Nagaoka Univ. of Tech. Sano, Akira Keio Univ. Fujioka, Hisaya Kyoto Univ. 14:40 Nonlinear Control of a Parametrically-Excited System Subject to ThM10 Guest Room 350 Actuator Saturation, 3846 **Constrained Control II** Regular Session Chen, Ley Univ. of Adelaide Chair: Kerrigan, Eric C. Univ. of Cambridge Hansen, Colin Henry Univ. of Adelaide Co-Chair: Rakovic, Sasa V. Imperial Coll. London 14:00 Simultaneous Tracking and Stabilization of Mobile Robots without Reachability Computations for Constrained Discrete-Time Systems Velocity Measurements, 3852 with State and Input Dependent Disturbances, 3905 The Univ. of Western Australia Do, Duc Rakovic, Sasa V. imperial Coll. London Jiang, Zhong Ping Pol. Univ. Univ. of Cambridge Kerrigan, Eric C. Pan, Jie The Univ. of Western Australia Mayne, David Q. Imperial Coll. London

15:20

15:40

14:20 Offset-Free Control of Constra. Subject to Persistent Unmeasu	ined Linear Discrete-Time Systems	14:00 A Kernel Method for Subspace Id Bilinear Systems, 3972	lentification of Multivariable
Pannocchia, Gabriele	Univ. of Pisa	Verdult, Vincent	Delft Univ. of Tech.
Kerrigan, Eric C.	Univ. of Cambridge	Verhaegen, Michel	Delft Univ. of Tech.
14:40		14:20	
Discrete-Time LTI Systems with	Robustly Positively Invariant Set for h Persistent State Disturbances,	Nonlinear Model Validation Using Dunstan, Wayne	GE Global Res.
3917		Bitmead, Robert	Univ. of California San Diego
Rakovic, Sasa V.	Imperial Coll. London	14:40	
Kerrigan, Eric C. Kouramas, Konstantinos	Univ. of Cambridge	Long-Range Nonlinear Prediction	
Mayne, David Q.	Imperial Coll. London	Piroddi, Luigi	Pol. Di Milano
•	impenar Coil. London	Spinelli, William	Pol. di Milano
15:00 Coordinated Control and Inform	action Architecture, 2010	15:00	
Bitmead, Robert	Univ. of California San Diego	Identification of Nonlinear System	ns Described by Hammerstein
Yan, Jun	Univ. of California San Diego	Models, 3990	Univ. of Dalaman
15:20	onition outlines outlines of	Alonge, Francesco Dippolito, Filippo	Univ. of Palermo Univ. of Palermo
CLF-Based Tracking Control fo	or LIAV Kinematic Models with	Raimondi, Francesco Maria	Univ. of Palermo
Saturation Constraints, 3924	OAV Ninematic Models with	Tumminaro, Salvatore	Univ. of Palermo
Ren, Wei	Brigham Young Univ.	*	Cint. Ci i dicinio
Beard, Randal W.	Brigham Young Univ.	15:20 Discrete-Time Nonlinear System	Identification Using Recurrent
15:40	<u> </u>	Neural Networks, 3996	raenancation Using Recurrent
	of Constrained Nonlinear Systems	Yu, Wen	CINVESTAV-IPN
with Application to a CSTR, 39.		Li, Xiaoou	CINVESTAV-IPN
Chisci, Luigi	Univ. di Firenze	15:40	
Falugi, Paola	Univ. of Florence		ork (TFNN) Systems for Dynamic
Zappa, Giovanni	Univ. Di Firenze	Systems Identification, 4002	- Tring Systems for Dynamic
		Lee, Ching-Hung	Yuan Ze Univ
ThM11	Guest Room 351	Lai, Wei-Yu	Yuan Ze Univ.
Control Applications II	Regular Session	Lin, Yu-Ching	Yuan Ze Univ.
Chair: Mestha, Lalit K.	Xerox Corp.		
Co-Chair: Mazenc, Frederic	Inria Lorraine,	ThM13	Guest Room 450
14:00	- Him or to A office 1 to a store of O and and	Control of Time Delay	Regular Session
Application of Exploratory Mode 3936	elling to Active Headrest Control,	Systems I	Univ. of Minarcai Calcandia
Veres, Sandor M	School of Engineering Sciences	Chair: Chellaboina, VijaySekhar	Univ. of Missouri- Columbia
•	School of Engineering Sciences	Co-Chair: Lozano, Rogelio	Univ. de Tech. de Compiegne
14:20	Control of a Flowbool Zora Bios	14:00	omv. do resit. de complegne
AMB System with Parameter U	Control of a Flywheel Zero-Bias	On Monotonicity of Solutions of N	Ionnegative and Compartmental
Sivrioglu, Selim	Gebze Inst. of Tech.	Dynamical Systems with Time De	
Nonami, Kenzo	Chiba Univ.	Chellaboina, VijaySekhar	Univ. of Missouri- Columbia
14:40		Haddad, Wassim M.	Georgia Inst. of Tech.
Velocity Control of 2-Mass-Spri	ng Systems with Large Load	Ramakrishnan, Jayanthy	Univ. of Missouri, Columbia
	stepping Control Approach, 3948	Bailey, James M.	Northeast Georgia Medical
Liu, Kang-Zhi	Chiba Univ.		Center
Namiki, Šusumu	Chiba Univ.	14:20	
Ishii, Hidekazu	Chiba Univ	Robust Prediction-Based Control	for Unstable Delay Systems,
15:00		4014	11.5. 4
	of 2 Dof Helicopter Model, 3954	Lozano, Rogelio	Univ. de Tech. de Compiegne
Dutka, Arkadiusz S.	Univ. of Strathclyde	Garcia Gil, Pedro José	Univ. Pol. de Valencia
Ordys, Andrzej W.	Univ. of Strathclyde	Castillo, Pedro Dzul, Alejandro	Univ. De Tech. De Compiegne Inst. Tecnológico de la Laguna
Grimble, Michael John	Univ. of Strathclyde	·	inst. Techologico de la caguna
15:20		14:40	f Fandfangand Costs
Forwarding Control of Scale Mo		Global Asymptotic Stabilization of	r reeatorward Systems with
Lyapunov Control Design., 396		Delay in the Input, 4020 Mazenc, Frederic	Inria Lorraine.
Mazenc, Frederic	Inria Lorraine,	Mondie, Sabine	CINVESTAV-IPN
Mahony, Robert	Monash Univ.	Francisco, Rogelio	CINVESTAV-IPN
Lozano, Rogelio	Univ. de Tech. de Compiegne	15:00	5 25 1
15:40	tral for Adicion in	Output Feedback Control Synthe	sis for Linear Time-Delay
Inverse Optimal Boundary Cont Magnetohydrodynamic Channe		Systems Via Infinite-Dimensional	
Schuster, Eugenio	Univ. of California San Diego	Azuma, Takehito	Kanazawa Univ
Condition, Edgerno	(ucsd)	Sagara, Seiichi	Kanazawa Univ
Krstic, Miroslav	Univ. of California at San Diego	Fujita, Masayuki Uchida, Kenko	Kanazawa Univ. Waseda Univ.
ThM12	Maui Suite 5		
Identification Algorithms	Regular Session		
dentineation Algorithms			
Chair: Verhaegen, Michel Co-Chair: Zheng, Wei Xing	Univ. of Twente Univ. of Western Sydney		

On Delay-Dependent Robust H- Continuous and Discrete-Time L		A Unified Approach to Design the R and Unstable Processes with Time-	
Delays, 4032		Zhang, Weidong	Shanghai Jiaotong Un
Palhares, Reinaldo M.	Federal Univ. of Minas Gerais		g
Campos, Claudio Dias	Pontifical Catholic Univ. of Minas Gerais	Study on the Relationships between Methods in Process Control.doc. 40	
Leles, Michel C. R.	Federal Univ. of Minas Gerais	Gu, Danying	Shanghai Jiaotong Un
Ekel, Petr Ya.	Pontifical Catholic Univ. of Minas		
ckei, Peli Ta.		liu, tao	Shanghai Jiaotong Un
	Gerais	Zhang, Weidong	Shanghai Jiaotong Un
d'angelo, Marcos F. S. V.	UNIMONTES		
15:40		Control of Heart Assist Devices, 408	8 <i>4</i>
PID Stabilization of LTI Plants w	ith Time-Delay, 4038	Antaki, James F.	Carnegie Mellon Un
Xu, Hao	Texas A & M Univ.	Boston, J.Robert	Univ. of Pittsbur
Datta, Aniruddha	Texas A & M Univ.	Simaan, Marwan A.	Univ. of Pittsbur
Bhattacharyya, Shankar P.	Texas A & M Univ.	ominati, marranti.	Cinv. or r mosar
Dilattacitaryya, Citatikai 1 .	I EXAS A G. IN CITIV.		
FL 184 4	O:+ P 454	Robust Control of Master-Slave Ma	
ΓhM14	Guest Room 451	Consideration of Actuator Dynamics	s and Uncertainty for Objects
Sliding Mode Control II	Regular Session	and Operator, 4090	
Chair: Parlangeli, Gianfranco		Ishii, Chiharu	Kogakuin Un
Co-Chair: Usai, Elio	Univ. degli Studi di Cagliari	Hashimoto, Hiroshi	Tokyo Univ. of Tee
14:00	-	Hernandez, Ricardo	Inst. Tecnologico
A Fault Tolerant Control System	for the Output Stabilization of		Aguascalien
SISO Plants with Actuator Unce			
1044	44.5. 474	Control Elements in Production Prin	nting and Publishing Systems
Parlangeli, Gianfranco	Univ. di Lecce	DocuColor Igen3, 4096	
Corradini, Maria Letizia	Univ. di Lecce	Mestha, Lalit K.	Xerox Co
14:20		Enzien, Mark	Xerox Co
· ··	nformation Demand for Relative-	Duke, Charles	Xerox Co
Degree 3 Systems, 4050		Platteter, Dale	Xerox Co
Usai, Elio	Univ. degli Studi di Cagliari	Bolte, Steve	Xerox Co
		Lanphere, John	Xerox Co
Bartolini, Giorgio	Univ. of Cagliari		General Elec
Pisano, Alessandro	Univ. di Cagliari	Viassolo, Daniel	
14:40		Mihalyov, Kenneth	Xerox Co
Robust Integral Silidina Mode R	egulator for Linear Systems with	Scarlata, Rick	Xerox Co
Multiple Time Delays in Control		Purvis, Lisa	Xerox Co
Basin, Michael V.	Autonomous Univ. of Nuevo	Mara, Bob	Xerox Co
Debin, intoriusi v.	Leon	Thompson, David	Xerox Co
Rodriguez Gonzalez, Jesus	Autonomous Univ. of Nuevo		
Rodriguez Gorizalez, Jesus		Debugt Estimation Algorithm for Sa	ostral Novachover Medela
A	Leon	Robust Estimation Algorithm for Spo	ectrar Neugebader Moders,
Acosta Cano De Los Ríos,	Inst. Tecnologico De Chihuahua	4109	Bd 11
Pedro Rafael		Rotea, Mario	Purdue Ur
Fridman, Leonid M.	National Autonomous Univ. of	Lana, Carlos	Purdue Ur
	Mexico	Viassolo, Daniel	•
15:00			
	ous Control System with Delayed	A Lean Document Production Contr	roller for Printshop
	us Control System With Delayed	Management, 4115	and for i finatiop
nput, 4062	Date of Occurre		V 0-
Levaggi, Laura	Univ. of Genova	Rai, Sudhendu	Xerox Co
Punta, Elisabetta	ISSIA CNR National Res. Council	Viassolo, Daniel E.	General Elec
	of Italy		
5:20		ThP01	Monarchy Ballro
.0	Bounded Disturbance Rejection for	Cooperative and	Invited Sessi
Incertain Impulsive Systems, 4		Noncooperative Systems	
		under Constrained Information	
Hao, Fei	Peking Univ.	Chair: Shamma, Jeff S.	Univ. of California Los Ange
Chu, Tianguang	Peking Univ.	Co-Chair: D'Andrea, Raffaello	Cornell Ur
Wang, Long	Peking Univ.		
Huang, Lin	Peking Univ.	Organizer: Shamma, Jeff S.	Univ. of California Los Ange
15:40	- -	Organizer: Dahleh, Munther	Massachusetts Inst. of Te
	lay Controller with Uncertain Time	Α.	
Delay, 4074	ay Controller with Officertain Time	16:20	
• •	Notional Autoropean Links of	Agreement Problems in Networks v	vith Directed Granhs and
Fridman, Leonid M.	National Autonomous Univ. of	Switching Topology (I), 4126	Directed Graphs and
	Mexico		Colifornia Inst. of To
	•	Olfati-Saber, Reza	California Inst. of Te
Strygin, Vadim		Murray, Richard M.	California Inst. of Te
Strygin, Vadim Polyakov, Andrei	•	• • • • • • • • • • • • • • • • • • • •	
	•	16:40	
	- Grand Promenade		
Polyakov, Andrei	Grand Promenade Poster/Interactive Paper Session	16:40 A Computation and Control Langua (I), 4133	

17:00		16:20	
A Feedback Stabilization Appr Shamma, Jeff S.	oach to Fictitious Play (I), 4140 Univ. of California Los Angeles	A Perfect Reconstruction Paradig 4196	ım for Digital Communication,
Arslan, Gurdal	Univ. of California at Los Angeles	Voulgaris, Petros G.	Univ. of Illinois at Urbana- Champaign
	fferential Games with Different	Hadjicostis, Christoforos	Univ. of Illinois at Urbana- Champaign
Information Patterns (I), 4146 Speyer, Jason L. Swarup, Ashitosh	Univ. of California at Los Angeles Univ. of California at Los Angeles	Touri, Rouzbeh	Univ. of Illinois at Urbana- champaign
17:40		16:40	
	oach to the Mode Estimation of	Power Control and Rate Adaptati Random Access, 4202	on As Stochastic Games for
Martins, Nuno C.	Massachusetts Inst. of Tech.	Sagduyu, Yalin Evren	Univ. of Maryland at Coll. Park
Dahleh, Munther A.	Massachusetts Inst. of Tech.	Ephremides, Anthony	Univ. of Maryland at Coll. Park
18:00		17:00 Attaining High Operating Bandwid	ofth I laing Sangar Arraya and
Using Airborne Vehicle-Based Communications with UAV Clu		Frequency Domain Methods, 420	
Breheny, Sean	Cornell Univ.	Suranthiran, Sugathevan	Texas A&M Univ.
D'Andrea, Raffaello	Cornell Univ.	Jayasuriya, Suhada	Texas A&M Univ.
Miller, Jeremy	Cornell Univ.	17:20	
TI DOO		A New Class of Soft MIMO Demo	odulation Algorithms Based on
ThP02 Nonlinear Systems Stability	Regency A Regular Session	Sequential Monte Carlo, 4214 Wang, Xiaodong	Columbia Univ.
	Regulal Session	•	Columbia Oniv.
Chair: Sepulchre, Rodolphe		17:40 On the Design of AQM Supporting	a TCP Flows I Isina Robust
J.	•	Control Theory, 4220	g TCT TIOWS OSING NODUSE
Co-Chair: Calafiore,	Pol. di Torino	Quet, Pierre-Francois	Ohio State Univ.
Giuseppe		Ozbay, Hitay	Ohio State Univ.
16:20		18:00	
Design of Nonlinear Controls U 4163	Jsing Structured Representations,	Modified Distributed Constrained Model in CDMA Cellular Systems	
Medanic, Juraj	Univ. of Illinois at Urbana-	Lee, Mooyoung	Doowon Tech. Coll.
	Champaign	Oh, Do Chang	Konyang Univ.
16:40		Kwon, Woohyen	Kyungpook National Univ.
Dissipativity Characterization of	f a Class of Oscillators and	ThP04	Power ov C
Networks of Oscillators, 4169 STAN, Guy-Bart V.	Univ. de Liege	Optimization of Stochastic	Regency C Regular Session
SEPULCHRE, Rodolphe J.		Systems	(tegulai dession
17:00		Chair: Guay, Martin	Queen's Univ.
Control of Heisenberg Spin Sy	stems; Lie Algebraic	Co-Chair: Malhame, Roland	Ec. Pol. de Montreal
Decompositions and Action-Ar	igle Variables, 4174	P.	
Vaidya, Umesh		16:20	
	Univ. of California Santa Barbara		/ O
D'Alessandro, Domenico	lowa State Univ.	Stochastic Power Control in Wire	
D'Alessandro, Domenico Mezic, Igor		Stochastic Power Control in Wire Analysis, Approximate Control Al	
D'Alessandro, Domenico Mezic, Igor 17:20	lowa State Univ. Univ. of California, Santa Barbara	Stochastic Power Control in Wire	gorithms and State Aggregation,
D'Alessandro, Domenico Mezic, Igor 17:20	lowa State Univ.	Stochastic Power Control in Wire Analysis, Approximate Control Al 4231 Huang, Minyi Malhame, Roland P.	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi	lowa State Univ. Univ. of California, Santa Barbara	Stochastic Power Control in Wire Analysis, Approximate Control Al 4231 Huang, Minyi	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179	lowa State Univ. Univ. of California, Santa Barbara ulations for a Class of Non-Linear	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ.
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of	lowa State Univ. Univ. of California, Santa Barbara ulations for a Class of Non-Linear	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ.
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-	Stochastic Power Control in Wire. Analysis, Approximate Control Al. 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ. f Spectral Density Functions,
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid- Univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T.	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ. f Spectral Density Functions, Univ. of Minnesota
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Algazata Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G.	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ. f Spectral Density Functions,
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid- Univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G.	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions, Univ. of Minnesota Royal Inst. of Tech.
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Algazata Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G.	gorithms and State Aggregation, Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions, Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory	gorithms and State Aggregation,  Mcgill Univ.  Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simi Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simul Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside	Stochastic Power Control in Wire. Analysis, Approximate Control Alg. 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication Systems	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Regency B Regular Session	Stochastic Power Control in Wire. Analysis, Approximate Control Algazania Huang, Minyi Malhame, Roland P. Caines, Peter E.  16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G.  17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin  17:20 Optimization of Stochastic Uncertand Robustness, 4249	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simul Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Attum Mechanics and Quantum  Res.  Regency B	Stochastic Power Control in Wirel Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D.	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  tain Systems: Large Deviations  Univ. of Ottawa
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication Systems Chair: Voulgaris, Petros G.	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Regency B Regency B Regular Session  Univ. of Illinois at Urbana-	Stochastic Power Control in Wirel Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D. Rezaei, Farzad	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  tain Systems: Large Deviations  Univ. of Ottawa
D'Alessandro, Domenico Mezic, Igor  17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe  17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander  18:00 Lagrangian Optimization, Quan Control, 4191 Lyshevski, Marina  ThP03 Control of Communication Systems Chair: Voulgaris, Petros G.	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Attention of California, Riverside Univ. of California, Riverside  Univ. of California, Riverside  Univ. of Illinois at Urbana- Champaign	Stochastic Power Control in Wirel Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D. Rezaei, Farzad	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  If Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  Itain Systems: Large Deviations Univ. of Ottawa PhD Student
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication Systems Chair: Voulgaris, Petros G.	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Attention of California, Riverside Univ. of California, Riverside  Univ. of California, Riverside  Univ. of Illinois at Urbana- Champaign	Stochastic Power Control in Wire. Analysis, Approximate Control Alg. 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D. Rezaei, Farzad 17:40 Optimal Output Probability Densit	gorithms and State Aggregation,  Mcgill Univ. Ec. Pol. de Montreal McGill Univ.  If Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  Itain Systems: Large Deviations  Univ. of Ottawa PhD Student
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication Systems Chair: Voulgaris, Petros G.	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Attention of California, Riverside Univ. of California, Riverside  Univ. of California, Riverside  Univ. of Illinois at Urbana- Champaign	Stochastic Power Control in Wirel Analysis, Approximate Control Alg 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D. Rezaei, Farzad	gorithms and State Aggregation,  McGill Univ. Ec. Pol. de Montreal McGill Univ.  If Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  Itain Systems: Large Deviations  Univ. of Ottawa PhD Student
D'Alessandro, Domenico Mezic, Igor 17:20 Orthotopic and Ellipsoidal Simil Systems, 4179 Calafiore, Giuseppe 17:40 Quantum Feedback Control of State Qubit, 4185 Ruskov, Rusko Zhang, Qin Korotkov, Alexander 18:00 Lagrangian Optimization, Quar Control, 4191 Lyshevski, Marina ThP03 Control of Communication Systems Chair: Voulgaris, Petros G.	lowa State Univ. Univ. of California, Santa Barbara  ulations for a Class of Non-Linear  Pol. di Torino  Coherent Oscillations in a Solid-  Univ. of California, Riverside Graduate student, UC Riverside Univ. of California, Riverside univ. of California, Riverside  Attention of California, Riverside Univ. of California, Riverside  Univ. of California, Riverside  Univ. of Illinois at Urbana- Champaign	Stochastic Power Control in Wire. Analysis, Approximate Control Alg. 4231 Huang, Minyi Malhame, Roland P. Caines, Peter E. 16:40 Kullback-Leibler Approximation of 4237 Georgiou, Tryphon T. Lindquist, Anders G. 17:00 Control Design for Discrete-Time with a Nonquadratic Performance Forbes, Michael Gregory Forbes, J. Fraser Guay, Martin 17:20 Optimization of Stochastic Uncert and Robustness, 4249 Charalambous, Charalambos D. Rezaei, Farzad 17:40 Optimal Output Probability Densit ARMAX Stochastic Systems, 425	gorithms and State Aggregation,  McGill Univ. Ec. Pol. de Montreal McGill Univ.  f Spectral Density Functions,  Univ. of Minnesota Royal Inst. of Tech.  Stochastic Nonlinear Processes Objective, 4243  Univ. of Alberta Univ. of Alberta Queen's Univ.  tain Systems: Large Deviations  Univ. of Ottawa  PhD Student

	al Disturbance Attenuation for	17:20 Theoretic Modeling and Adaptive Co	ntrol for Two Degree-Of
Nonlinear Stochastic Uncerta		Freedom Piezo-Electric Actuated Ch	
Charalambous, Charalami	oos Univ. of Ottawa	4315	
D. Pozosi Formed	Links of Ottown	Wang, Jian	Concordia Univ. Concordia Univ.
Rezaei, Farzad Djouadi, Seddik	Univ. of Ottawa Univ. of Arkansas at Little Rock	Su, Chun-Yi Oya, Masahiro	Kyushu Inst. of Tech.
TERROR		17:40	
ThP05 Stability of Nonlinear Switc	Maui Suite 1 hed Regular Session	Adaptive Control for Tracking and Di	
Systems	Negulai Session	SISO Linear Systems with Repeated Chen, Yu	Noisy Measurements, 4321 Univ. of Cincinnati
Chair: Johansson, Karl He		Pan, Zigang	Univ. of Cincinnati
Co-Chair: Orlov, Yuri V.	CICESE	18:00	
6:20	· _ · · · · · · · · · · · · · · · · · ·	Intelligent Compensation of Actuator	Nonlinearities, 4327
Piecewise Polynomial Lyapur Nonlinear Systems, 4265	nov Functions for a Class of Switched	Selmic, Rastko R.	Louisiana Tech. Univ.
Coutinho, Daniel Ferreira	Pontificia Univ. Catolica do Rio	Phoha, Vir V.	Louisiana Tech. Univ.
Coulinio, Daniel I enera	Grande do Sul	Lewis, Frank L.	Univ. of Texas at Arlington
Trofino, Alexandre	Federal Univ. of Santa Catarina	ThP07	Regency Boardroom
6:40		Optimization Methods and	Regular Session
	geneous Switched Systems, 4271	Algorithms	
Orlov, Yuri V.	CICESE	Chair: Feinberg, Eugene A.	SUNY at Stony Brook
7:00		Co-Chair: Menemenlis, Nickie	I.R.E.Q.
	put Cascade Nonlinear Systems,	16:20	
277	Material Company (1997)	Online Scheduling: Generalized Piny	
Cronin, Brian Spong, Mark W.	Univ. of Illinois at Urbana-Champaign	Feinberg, Eugene A.	SUNY at Stony Brook SUNY Stony brook
· -	Univ. of Illinois at Urbana-Champaign	Curry, Michael	SUINT STORY DIOOK
17:20 Stability of Planar Nonlinear S	Switched Systems 4282	16:40 Maximum Boint To Boint Bower Trai	refer Using Second Order
Boscain, Ugo V.	SISSA-ISAS	Maximum Point-To-Point Power Trail Approximation, 4339	isler Using Second Order
charlot, gregoire	SISSA-ISAS	Huneault, Maurice	I.R.E.Q.
7:40		Menemenlis, Nickie	I.R.E.Q.
	onsmooth Feedback Systems:	17:00	
Experimental Results and Th		Peer-To-Peer Refuelling within a Sai	ellite Constellation, Part I:
lannelli, Luigi	Univ. of Napoli Federico II	Zero-Cost Rendezvous Case, 4345	
Johansson, Karl Henrik	Royal Inst. of Tech.	Shen, Haijun	Georgia Inst. of Tech.
Jonsson, Ulf T.	Royal Inst. of Tech. Univ. of Sannio	Tsiotras, Panagiotis	Georgia Inst. of Tech.
Vasca, Francesco	Univ. or Sannio	17:20	
18:00 1 Sliding Mada Controllar for	Actuator Failure Compensation.,	Balancing of High-Speed Rotating M Optimization, 4351	achinery Using Convex
1291	Actuator railure Compensation.,	Li, Guoxin	Univ. of Virginia
Corradini, Maria Letizia	Univ. di Lecce	Lin, Zongli	Univ. of Virginia
Orlando, Giuseppe	Univ. di Ancona	Untaroiu, Costin	Univ. of Virginia
		Allaire, Paul	Univ. of Virginia
ThP06	Maui Suite 2	17:40	
Robust Adaptive Control Chair: Anderson, Brian D.	Regular Session	Probability Model for an Adaptive Ra	
	<ol> <li>Australian National Univ.</li> </ol>	Kumar, Rajeeva	
Co-Chair: Selmic, Rastko	<ol> <li>Australian National Univ.</li> </ol>	Hyland, David C.	The Univ. of Michigan
Co-Chair: Selmic, Rastko	O. Australian National Univ. R. Louisiana Tech. Univ.	Hyland, David C. Kabamba, Pierre T.	The Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha	<ol> <li>Australian National Univ.</li> </ol>	Hyland, David C. Kabamba, Pierre T. 18:00	The Univ. of Michigan Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model	Hyland, David C. Kabamba, Pierre T. 18:00 Peer-To-Peer Refuelling within a Sa.	The Univ. of Michigan Univ. of Michigan rellite Constellation, Part II:
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model Univ. of Cambridge The Australian National Univ.	Hyland, David C. Kabamba, Pierre T. 18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43	The Univ. of Michigan Univ. of Michigan rellite Constellation, Part II: 163
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge	Hyland, David C. Kabamba, Pierre T. 18:00 Peer-To-Peer Refuelling within a Sa.	The Univ. of Michigan Univ. of Michigan dellite Constellation, Part II: 163 Georgia Inst. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model Univ. of Cambridge The Australian National Univ. The Australian National Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 45 Shen, Haijun Tsiotras, Panagiotis	The Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ.  Introl for Time-Varying Nonlinear	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 45 Shen, Haijun Tsiotras, Panagiotis  ThP08	The Univ. of Michigan Univ. of Michigan tellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ.  Introl for Time-Varying Nonlinear Belative Degree, 4303	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III	The Univ. of Michigan Univ. of Michigan tellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session
Co-Chair: Selmic, Rastko 6:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 6:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ.  Introl for Time-Varying Nonlinear Telative Degree, 4303  Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M.	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ.  Introl for Time-Varying Nonlinear  Telative Degree, 4303  Kumamoto Univ. Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan
Co-Chair: Selmic, Rastko 6:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ.  Introl for Time-Varying Nonlinear Telative Degree, 4303  Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik 16:20	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Interview Degree, 4303  Kumamoto Univ. Kumamoto Univ. Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik  16:20 Controllability and Motion Planning of	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Interval for Time-Varying Nonlinear Itelative Degree, 4303  Kumamoto Univ. Kumamoto Univ. Kumamoto Univ. Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik  16:20 Controllability and Motion Planning of Nonholonomic Constraints, 4369	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maui Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech.
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00 Adaptive Robust Dynamic Su Levitation System, 4309	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Interval for Time-Varying Nonlinear Itelative Degree, 4303  Kumamoto Univ. Kumamoto Univ. Kumamoto Univ. Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik  16:20 Controllability and Motion Planning of	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech. of Multibody Systems with Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00 Adaptive Robust Dynamic Su Levitation System, 4309 Yang, Zi-jiang	O. Australian National Univ. R. Louisiana Tech. Univ.  Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Introl for Time-Varying Nonlinear Relative Degree, 4303  Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 45 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik 16:20 Controllability and Motion Planning of Nonholonomic Constraints, 4369 Shen, Jinglai	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maui Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech. If Multibody Systems with Univ. of Michigan Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00 Adaptive Robust Dynamic Su Levitation System, 4309 Yang, Zi-jiang Miyazaki, Kouichi	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Introl for Time-Varying Nonlinear Relative Degree, 4303  Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa. Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik 16:20 Controllability and Motion Planning of Nonholonomic Constraints, 4369 Shen, Jinglai Schneider, David A.	The Univ. of Michigan Univ. of Michigan Univ. of Michigan  dellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech.  of Multibody Systems with Univ. of Michigan Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00 Adaptive Robust Dynamic Su Levitation System, 4309 Yang, Zi-Jiang Miyazaki, Kouichi Kanae, Shunshoku	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Interventional Univ. Intervention	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik  16:20 Controllability and Motion Planning of Nonholonomic Constraints, 4369 Shen, Jinglai Schneider, David A. Bloch, Anthony M.  16:40 Asymptotic Stability in Flexible-Joint	The Univ. of Michigan Univ. of Michigan Univ. of Michigan Rellite Constellation, Part II: 163 Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech. of Multibody Systems with Univ. of Michigan Univ. of Michigan Univ. of Michigan
Co-Chair: Selmic, Rastko 16:20 Safe Adaptive Controller Cha Adjustments, 4297 Lecchini, Andrea Lanzon, Alexander Anderson, Brian D.O. 16:40 Robust Adaptive Tracking Co Systems with Higher Order R Mizumoto, Ikuro Michino, Ryuji Tao, Yuichi Iwai, Zenta 17:00 Adaptive Robust Dynamic Su Levitation System, 4309 Yang, Zi-jiang Miyazaki, Kouichi	O. Australian National Univ. R. Louisiana Tech. Univ. Inges Based on Reference Model  Univ. of Cambridge The Australian National Univ. The Australian National Univ. Introl for Time-Varying Nonlinear Relative Degree, 4303  Kumamoto Univ.	Hyland, David C. Kabamba, Pierre T.  18:00 Peer-To-Peer Refuelling within a Sa Nonzero-Cost Rendezvous Case, 43 Shen, Haijun Tsiotras, Panagiotis  ThP08 Mechanical Systems III Chair: Bloch, Anthony M. Co-Chair: Nijmeijer, Hendrik  16:20 Controllability and Motion Planning of Nonholonomic Constraints, 4369 Shen, Jinglal Schneider, David A. Bloch, Anthony M.  16:40 Asymptotic Stability in Flexible-Joint Delays, 4375	Georgia Inst. of Tech. Georgia Inst. of Tech. Maul Suite 3 Regular Session Univ. of Michigan Eindhoven Univ. of Tech.  If Multibody Systems with Univ. of Michigan Univ. of Michigan Univ. of Michigan

17:00		16:40	
Controlled Synchronization of Pe		New Results on Robust Stabiliz	ation Via Saturated Feedback,
Pogromsky, Alexander	Eindhoven Univ. of Tech.	4445	
Belykh, Vladimir	Volga State transport Acad.	Angeli, David	Univ. of Firenze
Nijmeijer, Hendrik	Eindhoven Univ. of Tech.	Chitour, Yacine	Lab. D'analyse Numerique
17:20		Marconi, Lorenzo	Univ. di Bologna
	Systems with Input Constraints Via	17:00	
Iterative Learning, 4387	y como min input o o noti anno via		teed Regions of Stability: An LMI-
Fujimoto, Kenji	Kyoto Univ.	Based Approach, 4451	toou regions or etablity rin =iiii
Horiuchi, Tetsu	Kyoto Univ.	Gomes Da Silva Jr., Joao	Univ. Federal do Rio Grande do
Sugie, Toshiharu	Kyoto Univ.	Manoel	Sul (UFRGS)
17:40	.,,	Tarbouriech, Sophie	LAAS-CNRS
	Pendulum System Using Saturation	17:20	
Functions, 4393	endulum System Osing Saturation		Generalized Predictive Control of
Fantoni, Isabelle	Univ. de Tech. de Compiegne	Non-Minimum Phase Processes	
Lozano, Rogelio	Univ. de Tech. de Complegne	Deng, Mingcong	Okayama Univ.
	Offiv. de l'ech. de Complègne	Inoue, Akira	Okayama Univ.
18:00	0	Yanou, Akira	Kinki Univ.
Classical Dual-Inverted-Pendulu		Hirashima, Yoichi	Okayama Univ.
Lundberg, Kent	MIT		Chayama Chir.
Roberge, James	MIT	17:40	Variation Contains for the Contain
TEDAG	Maui Suite 4	Stabilization of a Class of Time	
ThP09	muur Cunc 4	Saturations and Measurement I	voise with Application to
Learning in Control	Regular Session	Nonholonomic Systems, 4463	11-1-1-0-1
Chair: Gevers, Michel	Univ. Catholique de Louvain	Battilotti, Stefano	Univ. La Sapienza
Co-Chair: Chen, YangQuan	Utah State Univ.	18:00	
16:20		Composite Nonlinear Control w	
Constructing Performance Sensi			able Systems with Input Saturation,
Potentials As Building Blocks (I),		4469	
Cao, Xi-Ren	Hong Kong Univ. of Sci. & Tech.	He, Yingjie	National Univ. of Singapore
16:40		Chen, Ben M.	National Univ. of Singapore
Learning for Repeated Constrain	ed Games in Counter-Coalition	Wu, Chao	National Univ. of Singapore
Space, 4410			
Poznyak, Alexander S.	CINVESTAV-IPN	ThP11	Guest Room 351
Godoy-alcantar, Martin	CINVESTAV-IPN	Control Applications III	
Gomez-ramirez, Eduardo	La Salle Univ.	Chair: Mestha, Lalit K.	Xerox Corp.
17:00	•	Co-Chair: Viassolo, Daniel	General Electric
Iterative Learning Control with Ite	eration-Domain Adaptive	16:20	
Feedforward Compensation, 441			of Buck Power Converters, 4475
Chen, YangQuan	Utah State Univ.	Giri, Fouad	GREYC
Moore, Kevin L.	Utah State Univ.	El Fadil, Hassan	EMI
17:20	,	Chaoui, Fatima-Zahra	EMI
Optimization of the Prefilter in Ite	rative Feedback Tuning for	Haloua, Mohamed	EMI
Improved Accuracy of the Control		Ouadii, Hamid	GREYC
Hildebrand, Roland	Univ. Catholique de Louvain	16:40	• •
Lecchini, Andrea	Univ. of Cambridge		rol of Large Power Systems, 4481
SOLARI, Gabriel Elías	Phd. Student	okou, Francis A.	Ec. de Tech. superieure
Gevers, Michel	Univ. Catholique de Louvain	Akhrif, Ouassima	Ec. de Tech. superieure
17:40		Dessaint, Louis A.	Ec. de Tech. superieure
Iterative Learning Control of Rob	otic Manipulators by Hybrid	17:00	
Adaptation Schemes, 4428	zong manara ay i iyania	Control Strategy Using Vision for	
Miyasato, Yoshihiko	Inst. of Statistical Mathematics	Experimental PVTOL Aircraft Se	etup, 4487
18:00		Palomino, Amparo	Univ. de Tech. de Compičgne
Analysis and Design of Anticipate	on Learning Central 4424	Castillo, Pedro	Univ. De Tech. De Compiegne
Wang, Danwei	Nanyang Tech. Univ.	Fantoni, Isabelle	Univ. de Tech. de Compiegne
Ye, Yongqiang	Nanyang Tech. Univ. Nanyang Tech. Univ.	Lozano, Rogelio	Univ. de Tech. de Compiegne
Cheah, Chien Chern	Nanyang Tech. Univ.	Pegard, Claude	UPJV
Officially, Official Official	ivanyang rech. Oniv.	17:20	
			ctive Vibration Isolation System
ThP10	Guest Peem 350		
ThP10	Guest Room 350		spension, 4493
Constrained Nonlinear	Guest Room 350 Regular Session	Using Zero-Power Magnetic Su- Mizuno, Takeshi	spension, 4493 Saitama Univ.
Constrained Nonlinear Systems	Regular Session	Using Żero-Power Magnetic Su- Mizuno, Takeshi	
Constrained Nonlinear Systems Chair: Chitour, Yacine	Regular Session  Lab. D'analyse Numerique	Using Zero-Power Magnetic Su	Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David	Regular Session	Using Zero-Power Magnetic Su Mizuno, Takeshi Takasaki, Masaya	Saitama Univ. Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20	Regular Session  Lab. D'analyse Numerique Univ. of Firenze	Using Zero-Power Magnetic Su Mizuno, Takeshi Takasaki, Masaya Suzuki, Hirohisa Ishino, Yuji	Saitama Univ. Saitama Univ. Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20 Further Results on Global Stabilit	Regular Session  Lab. D'analyse Numerique	Using Zero-Power Magnetic Su Mizuno, Takeshi Takasaki, Masaya Suzuki, Hirohisa Ishino, Yuji 17:40	Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20 Further Results on Global Stabili: Bounded Controls, 4440	Regular Session  Lab. D'analyse Numerique Univ. of Firenze  zation for Multiple Integrators with	Using Zero-Power Magnetic Su- Mizuno, Takeshi Takasaki, Masayya Suzuki, Hirohisa Ishino, Yuji 17:40 Robust Regulation for a Magnet	Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20 Further Results on Global Stabilit	Regular Session  Lab. D'analyse Numerique Univ. of Firenze	Using Zero-Power Magnetic Su- Mizuno, Takeshi Takasaki, Masaya Suzuki, Hirohisa Ishino, Yuji 17:40 Robust Regulation for a Magnet Bonivento, Claudio	Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ. Univ. of Bologna
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20 Further Results on Global Stabili: Bounded Controls, 4440	Regular Session  Lab. D'analyse Numerique Univ. of Firenze  zation for Multiple Integrators with	Using Zero-Power Magnetic Su- Mizuno, Takeshi Takasaki, Masayya Suzuki, Hirohisa Ishino, Yuji 17:40 Robust Regulation for a Magnet	Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ.
Constrained Nonlinear Systems Chair: Chitour, Yacine Co-Chair: Angeli, David 16:20 Further Results on Global Stabili: Bounded Controls, 4440	Regular Session  Lab. D'analyse Numerique Univ. of Firenze  zation for Multiple Integrators with	Using Zero-Power Magnetic Su- Mizuno, Takeshi Takasaki, Masaya Suzuki, Hirohisa Ishino, Yuji 17:40 Robust Regulation for a Magnet Bonivento, Claudio Gentili, Luca	Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ. Saitama Univ. Univ. of Bologna Univ. of Bologna

iezolelectric Transducers, 45 Moallem, Mehrdad	Univ. of Western Ontario	Robustness Analysis, 4569 Mondie, Sabine	CINVESTAV-IPN
Kermani, Mehrdad R	Univ. of Western Ontario (PhD Candidate)	Michiels, Wim	K.U. Leuven
Patel, Rajni Ostojic, Mile	Univ. of Western Ontario National Res. Council of Canada	ThP14 Advances in High Order Sliding Modes	Guest Room 451 Invited Session
hP12	Maui Suite 5	Chair: Shtessel, Yuri B.	Univ. of Alabama at Huntsville
dentification and Estimatio	n Regular Session Royal Inst. of Tech.	Co-Chair: Levant, Arie Organizer: Shtessel, Yuri B.	Tel - Aviv Univ. Univ. of Alabama at Huntsville
Chair: Blomqvist, Anders Co-Chair: Denis, Nikolaos		Organizer: Levant, Arie	Tel - Aviv Univ.
6:20	Lookiiga Waitii	Organizer: Fridman, Leonid	
	ree Nevanlinna-Pick Interpolants by	M.	Mexico
olving Nonlinear Equations,		16:20	
Blomqvist, Anders	Royal Inst. of Tech.	Analysis of Second Order Slidi	ng Mode Algorithms in the
Fanizza, Giovanna	Royal Inst. of Tech.	Frequency Domain (I), 4575	01101
Nagamune, Ryozo	Royal Inst. of Tech.	Boiko, Igor CASTELLANOS GARCIA,	SNC-Lavalin National Autonomous Univ. of
8:40	alad David ata Ottoria una deda	MANUEL IVAN	Mexico
eature Extraction Using Wav JIANG, HAI	velet Packets Strategy, 4517 PH.D Candidate	Fridman, Leonid M.	National Autonomous Univ. of
Er, Meng Joo	PH.D Candidate NTU	, . =	Mexico
Gao, Yang	NTU	16:40	
7:00		_	ontrol of Switched Delayed Systems
	pplication to Automotive Powertrains,	(I), 4581	
521	•	Sira-Ramirez, Hebertt J.	CINVESTAV-IPN
Lagerberg, Adam	Jonkoping Univ.	17:00	
Egardt, Bo S.	Chalmers Univ. of Tech.		rol of Advanced Interceptors Using
7:20		Second Order Sliding Modes (i Shtessel, Yuri B.	0, 4067 Univ. of Alabama at Huntsville
	ace Tracking Theorems, 4527 Univ. of Central Florida	Shkolnikov, Ilya	Z/I Imaging Corp.
Luo, Dapeng Leonessa, Alexander	Univ. of Central Florida	17:20	
:40	Only. of Contrart longs		Control in Constrained Motion with
• -	ection Using Dynamic Bayesian	Friction (I), 4593	
tworks, 4533	socion coming by marmo baycolan	Bartolini, Giorgio	Univ. of Caglian
	Lockheed Martin	Punta, Elisabetta	ISSIA CNR - National Res.
Denis, Nikolaos	Lockheed Martin	Punta, Elisabetta	ISSIA CNR - National Res.
Denis, Nikolaos :00 plication of BELS Based M	lethods in Direct Identification of	Punta, Elisabetta	ISSIA CNR - National Res Council of Italy
Denis, Nikolaos :00 plication of BELS Based M tear Systems from Closed I	lethods in Direct Identification of Loop Data, 4539	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte	ISSIA CNR - National Res Council of Italy
Denis, Nikolaos :00 oplication of BELS Based M	lethods in Direct Identification of	Punta, Elisabetta	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear
Denis, Nikolaos :00 :plication of BELS Based M near Systems from Closed I Zheng, Wei Xing	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney	Punta, Elisabetta 17:40 Finite Time Stabilization of Inte Systems (I), 4599	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS
Denis, Nikolaos 3:00 optication of BELS Based M near Systems from Closed I	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450	Punta, Elisabetta 17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS
Denis, Nikolaos :00 polication of BELS Based M near Systems from Closed in Zheng, Wei Xing  P13 pntrol of Time Delay stems II	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V. 18:00	ISSIA CNR - National Res Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE
Denis, Nikolaos :00 plication of BELS Based M near Systems from Closed I Zheng, Wei Xing  P13 portrol of Time Delay stems II Chair: Jankovic, Mrdjan	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session Ford Res. Lab.	Punta, Elisabetta  17:40  Finite Time Stabilization of Inte Systems (I), 4599  Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00  Quasi-Continuous High-Order	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605
Denis, Nikolaos 200 plication of BELS Based Mear Systems from Closed In Zheng, Wei Xing  P13 photol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre-	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V. 18:00	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605
Denis, Nikolaos 2:00 oplication of BELS Based Manear Systems from Closed In Zheng, Wei Xing nP13 ontrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session Ford Res. Lab.	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.
Denis, Nikolaos 200 plication of BELS Based Mear Systems from Closed I Zheng, Wei Xing P13 ntrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session Ford Res. Lab. INRIA-Rocquencourt	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ
Denis, Nikolaos 00 plication of BELS Based M ear Systems from Closed I Zheng, Wei Xing P13 ntrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J 20 ntrol of Nonlinear Systems	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney  Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ
Denis, Nikolaos 00 plication of BELS Based M ear Systems from Closed I Zheng, Wei Xing P13 ntrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J 20 ntrol of Nonlinear Systems Jankovic, Mrdjan	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney Guest Room 450 Regular Session Ford Res. Lab. INRIA-Rocquencourt	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ. Grand Promenade In Invited Poster/Interactive Session
Denis, Nikolaos 100 plication of BELS Based M lear Systems from Closed I Zheng, Wei Xing P13 Introl of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J 120 Introl of Nonlinear Systems Jankovic, Mrdjan 140	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney  Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab.	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ. Grand Promenade in Invited Poster/Interactive Session Univ. degli Studi di Napol Federico I
Denis, Nikolaos 200 plication of BELS Based M lear Systems from Closed I Zheng, Wei Xing P13 Introl of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J 20 Introl of Nonlinear Systems Jankovic, Mrdjan	lethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney  Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control Tokamaks	ISSIA CNR - National Res. Council of Italy erconnected Second Order Nonlinear LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ. Grand Promenade in Invited Poster/Interactive Session Univ. degli Studi di Napol Federico I Univ. degli Studi di Napol
Denis, Nikolaos :00 pplication of BELS Based M near Systems from Closed I Zheng, Wei Xing  P13 pntrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J :20 pntrol of Nonlinear Systems Jankovic, Mrdjan :40 pckstepping Design for Time control of Nonlinear Systems	Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. E-Delay Nonlinear Systems, 4551 Inria Lorraine,	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo Co-Chair: Ariola, Marco	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II
Denis, Nikolaos :00 plication of BELS Based Mear Systems from Closed I Zheng, Wei Xing  P13 phtrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J :20 phtrol of Nonlinear Systems Jankovic, Mrdjan :40 ckstepping Design for Time Mazenc, Frederic Bliman, Pierre-Alexandre	Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. Pe-Delay Nonlinear Systems, 4551 Inria Lorraine,	Punta, Elisabetta  17:40 Finite Time Stabilization of Inte Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napol Federico II Univ. degli Studi di Napol Federico II Univ. degli Studi di Napol
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Denis, Nikolaos :00 plication of BELS Based Mear Systems from Closed I Zheng, Wei Xing  P13 phtrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J :20 phtrol of Nonlinear Systems Jankovic, Mrdjan :40 pkstepping Design for Time Mazenc, Frederic Bliman, Pierre-Alexandre . :00 pedback Linearization of No Marquez, Luis Moog, Claude :20 posedness of Optimal Contre	Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. Inria Lorraine, INRIA-Rocquencourt  Inria Lorraine, INRIA-Rocquencourt  Ford Res. Lab. Ce-Delay Nonlinear Systems, 4551 Inria Lorraine, INRIA-Rocquencourt  Intinear Time-Delay Systems, 4557 CICESE Res. Center	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo  Co-Chair: Ariola, Marco Organizer: Pironti, Alfredo  16:20 Controlling Extremely Shaped 4611 Ariola, Marco De Tommasi, Gianmaria	ISSIA CNR - National Res Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napol Federico I Univ. degli Studi di Napol Federico II Univ. degli Studi di Napoli Federico I
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Denis, Nikolaos :00 pplication of BELS Based Mear Systems from Closed I Zheng, Wei Xing  P13 phtrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J :20 phtrol of Nonlinear Systems Jankovic, Mrdjan :40 phtrol of Nonlinear Systems Jankovic, Mrdjan  140 phtrol of Nonlinear Systems  140 phtrol of Nonlinear Systems  140	Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. INRIA-Rocquencourt  Invia Lorraine, I Inria Lorraine	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo Co-Chair: Ariola, Marco Organizer: Pironti, Alfredo  16:20 Controlling Extremely Shaped 4611 Ariola, Marco De Tommasi, Gianmaria Pironti, Alfredo	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II Plasmas in the JET Tokamak (I), Univ. degli Studi di Napoli Federico II
Denis, Nikolaos 200 plication of BELS Based Mear Systems from Closed I Zheng, Wei Xing P13 Introl of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J 20 Introl of Nonlinear Systems Jankovic, Mrdjan 240 ckstepping Design for Time Mazenc, Frederic Bliman, Pierre-Alexandre Cool and Marquez, Luis Moog, Claude 20 osedness of Optimal Controlay* Matveev, Alexey S. 440 Haptic Interface Design for aining and Collaboration in	Jethods in Direct Identification of Loop Data, 4539 Univ. of Western Sydney  Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. Inria Lorraine, Inria Lorraine, INRIA-Rocquencourt  Inflinear Time-Delay Systems, 4557 CICESE Res. Center CNRS  rol Problems by Perturbation of Time St.Petersburg Univ.  Minimally Invasive Telesurgical the Presence of Time Delay, 4563	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo Co-Chair: Ariola, Marco Organizer: Pironti, Alfredo  16:20 Controlling Extremely Shaped 4611 Ariola, Marco De Tommasi, Gianmaria Pironti, Alfredo	ISSIA CNR - National Res Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napol Federico I Univ. degli Studi di Napol Federico II Univ. degli Studi di Napoli Federico I
Denis, Nikolaos :00 plication of BELS Based M hear Systems from Closed I Zheng, Wei Xing  P13 phtrol of Time Delay stems II Chair: Jankovic, Mrdjan Co-Chair: Bliman, Pierre- Alexandre J :20 phtrol of Nonlinear Systems Jankovic, Mrdjan :40 phtrol of Nonlinear Systems Jankovic, Mrdjan  **Mazenc, Frederic Bliman, Pierre-Alexandre :40 phtrol of Nonlinear Systems Jankovic, Mrdjan  **Matveev, Alexey S :40 phtrol of Time Delay  **Matveev, Alexey S :40 phtrol of Ti	Guest Room 450 Regular Session  Ford Res. Lab. INRIA-Rocquencourt  with Time Delay, 4545 Ford Res. Lab. INRIA-Rocquencourt  Invia Lorraine, I Inria Lorraine	Punta, Elisabetta  17:40 Finite Time Stabilization of Intel Systems (I), 4599 Perruquetti, Wilfrid Floquet, Thierry Orlov, Yuri V.  18:00 Quasi-Continuous High-Order Levant, Arie  ThPI Advances in Plasma Control Tokamaks Chair: Pironti, Alfredo Co-Chair: Ariola, Marco Organizer: Pironti, Alfredo  16:20 Controlling Extremely Shaped 4611 Ariola, Marco De Tommasi, Gianmaria Pironti, Alfredo	ISSIA CNR - National Res. Council of Italy reconnected Second Order Nonlinear  LAIL UMR 8021CNRS LAIL UMR 8021CNRS CICESE  Sliding-Mode Controllers (I), 4605 Tel - Aviv Univ.  Grand Promenade In Invited Poster/Interactive Session  Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II Univ. degli Studi di Napoli Federico II

Favez, Jean-yves			um of Squares Programming (I),
	EPFL	4676	
Mullhaupt, Philippe	Ec. Pol. Fed. de Lausanne	Jarvis-Włoszek, Zachary	Univ. of California at Berkeley
Srinivasan, B.	Res. Associate CRPP-EPFL	Feeley, Ryan	Univ. of California at Berkeley
Lister, Jonathan B.	EPFL	Tan, Weehong	Univ. of California at Berkeley
Bonvin, Dominique	EPFL	Sun, Kunpeng	Univ. of California at Berkeley
Boundary Reconstruction and G	eometric Parameterisation for	Packard, Andrew K.	Univ. of California at Berkeley
Plasma Shape Control (I), 4622	edification arameterisation for	FrA02	Regency A
Beghi, Alessandro	Univ. of Padova	Nonlinear Systems V	Regular Session
Cenedese, Angelo	DIE-Univ. of Padova; ENEA- Consorzio RFX	Chair: Di Bernardo, Mario Co-Chair: Shiriaev, Anton	Univ. of Sannic Odense Univ
Plasma Position and Current Co 4628	ntrol Management at JET (I),	08:40 Sufficient Conditions for Dynami Via the Circle Criterion, 4682	cal Output Feedback Stabilization
Sartori, Filippo	Euratom/UKAEA Fusion Association	Shiriaev, Anton	Odense Univ Lund Univ
Cenedese, Angelo	DIE-Univ. of Padova; ENEA-	Johansson, Rolf Robertsson, Anders	Lund Univ
Celledese, Aligelo	Consorzio RFX	•	Euria Omi
		09:00 Analysis of the Energy Based Co	ontrol for Swinging up Two
Antiwindup Scheme for Plasma	Shane Control with Rate and	Pendulums, 4688	ondo for owniging up I wo
	s in the DIII-D Tokamak (I), 4634	Xin, Xin	Okayama Prefectural Univ
Schuster, Eugenio	Univ. of California San Diego	Kaneda, Masahiro	Okayama Prefectural Univ
	(ucsd)	09:20	-
Walker, Michael L.	General Atomics	Coprime Factorisation and Gap	Metric for Nonlinear Systems.
Krstic, Miroslav	Univ. of California at San Diego	4694	
Humphreys, D.A.	General Atomics	Bian, Wenming	Univ. of Southamptor
Di		French, Mark	Univ. of Southamptor
Plasma Boundary Control in Tok	tamaks (I), 4640 EURATOM	09:40	
Portone, Alfredo Albert, Des	Hewlett-Packard	by the Transverse Function App	
FrA01	Monarchy Ballroom	Morin, Pascal	INRIA INRIA Sophia-Antipoli
Positive Polynomials in	Invited Session	Samson, Claude 10:00	INRIA Sopnia-Antipolis
Control		A Factorization Approach to C^2	1 Stabilization of Nonlinear
Chair: Garulli, Andrea	Univ. di Siena	Triangular Systems, 4705	Glabinzalion of Norminal
Co-Chair: Henrion, Didier	LAAS-CNRS	Dacic, Dragan	Univ. of California Santa Barbara
Organizer: Garulli, Andrea Organizer: Henrion, Didier	Univ. di Siena LAAS-CNRS	Goebel, Rafal	Univ. of California
Organizer. Henrion, Didier		Kokotovic, Petar V.	
00:40		Nokotovio, i otal v.	
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LMI Optimization for Fixed-Orde		10:20	Barbara
LMI Optimization for Fixed-Orde		10:20 Analysis of Linear Systems in th	Barbara
08:40 <i>LMI Optimization for Fixed-Orde</i> 4646 Henrion, Didier 09:00	r H-Infinity Controller Design (I),	10:20 Analysis of Linear Systems in th and L2 Disturbances, 4711	Univ. of California at Santa Barbara re Presence of Actuator Saturation
LMI Optimization for Fixed-Orde 4646 Henrion, Didier	r H-Infinity Controller Design (I), LAAS-CNRS	10:20 Analysis of Linear Systems in th and L2 Disturbances, 4711 Fang, Haijun	Barbara re Presence of Actuator Saturation Univ. of Virginia
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4	r H-Infinity Controller Design (I), LAAS-CNRS abust LMI Problems with 652	10:20 Analysis of Linear Systems in th and L2 Disturbances, 4711	Barbara ne Presence of Actuator Saturation Univ. of Virginia Univ. of Virginia
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro	r H-Infinity Controller Design (I), LAAS-CNRS	10:20 Analysis of Linear Systems in th and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu	Barbara re Presence of Actuator Saturation Univ. of Virgini Univ. of Virgini Univ. of Virgini
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03	Barbara ne Presence of Actuator Saturation Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I	Barbari De Presence of Actuator Saturation Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency I Regular Sessio
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo	Barbara The Presence of Actuator Saturation Univ. of Virginia Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E Regular Sessio Univ. of Electro-Communication
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for lems Derived from the KYP	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang	Barbara The Presence of Actuator Saturation Univ. of Virginia Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E Regular Sessio Univ. of Electro-Communication
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40	Barbara The Presence of Actuator Saturation Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency I Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kon
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for lems Derived from the KYP  Univ. of California Los Angeles	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the	Barbara ne Presence of Actuator Saturation Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency I Regular Session Univ. of Electro-Communication City Univ. of Hong Kong
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan,	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for lems Derived from the KYP  Univ. of California Los Angeles	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A	Barbara  T-S Fuzzy Model of a Flexible-  Barbara  Barbara  Univ. of Virginia  Univ. of Virginia  Regency E  Regular Session  City Univ. of Hong Kong
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for lems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems:I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie Arm Gurkan, Evren	Barbara  Te Presence of Actuator Saturation  Univ. of Virginia  Univ. of Virginia  Univ. of Virginia  Regency I  Regular Session  Univ. of Electro-Communication  City Univ. of Hong Kong  T-S Fuzzy Model of a Flexible-  ligebra, 4717  Middle East Tech. Univ.
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A	Barbara  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ. of Saturation  Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E Regular Session Univ. of Electro-Communication City Univ. of Hong Kong Univ. of Sheffiel
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ. Linkoping Univ.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie Alegurkan, Evren Banks, Stephen Paul Erkmen, Ismet	Barbara  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ. of Saturation  Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E Regular Session Univ. of Electro-Communication City Univ. of Hong Kong Univ. of Sheffiel
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ. Linkoping Univ.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet	Barbara  The Presence of Actuator Saturation  Univ. of Virginia Univ. of Virginia Univ. of Virginia Regency E Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kong  T-S Fuzzy Model of a Flexible- Algebra, 4717  Middle East Tech. Univ. Univ. of Sheffiel Middle East Tech. Univ.
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S. Parrilo, Pablo A.	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ. Linkoping Univ.	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie Alegurkan, Evren Banks, Stephen Paul Erkmen, Ismet	Barbari  Te Presence of Actuator Saturation  Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency I Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kon  T-S Fuzzy Model of a Flexible- Ilgebra, 4717  Middle East Tech. Univ. Univ. of Sheffiel Middle East Tech. Univ.
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys	TH-Infinity Controller Design (I),  LAAS-CNRS  Abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for lems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  ETH Zurich  Stems Via Polynomially Parameter-	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub	Barbar  Te Presence of Actuator Saturation  Univ. of Virgini Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kon  T-S Fuzzy Model of a Flexible- ligebra, 4717 Middle East Tech. Univ Univ. of Sheffiel Middle East Tech. Univ
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Iems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ. Linkoping Univ. Linkoping Univ. Added ETH Zurich  stems Via Polynomially Parameter- (I), 4670	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Methologic Controller, 4723	Barbar.  Te Presence of Actuator Saturation  Univ. of Virgini Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency I Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kon  T-S Fuzzy Model of a Flexible- Ilgebra, 4717 Middle East Tech. Univ Univ. of Sheffiel Middle East Tech. Univ
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions Chesi, Graziano	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with 652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ. Linkoping Univ. Linkoping Univ. Linkoping Univ.  Quares Programs (I), 4664  ETH Zurich  stems Via Polynomially Parameter- (I), 4670  Univ. Di Siena	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub	Barbar.  Te Presence of Actuator Saturation  Univ. of Virgini Univ. of Virgini Univ. of Virgini Univ. of Virgini Regency I Regular Sessio Univ. of Electro-Communication City Univ. of Hong Kon  T-S Fuzzy Model of a Flexible- Ilgebra, 4717 Middle East Tech. Univ Univ. of Sheffiel Middle East Tech. Univ
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions Chesi, Graziano Garulli, Andrea	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Curres Programs (I), 4664  ETH Zurich  Stems Via Polynomially Parameter-  (I), 4670  Univ. Di Siena Univ. di Siena	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems: Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub Prijaca, Naser 09:20 A T-S Type of Rough Fuzzy Con	Barban  Te Presence of Actuator Saturation  Univ. of Virgini Univ. of Virgini Univ. of Virgini Univ. of Virgini Regular Sessio  Univ. of Electro-Communication City Univ. of Hong Kon  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ Univ. of Sheffiel Middle East Tech. Univ odology of Near Optimal Fuzzy  Univ. Clinical Cente Faculty of Electrical Engineerin
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions Chesi, Graziano Garulli, Andrea Tesi, Alberto	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Cuares Programs (I), 4664  ETH Zurich  Stems Via Polynomially Parameter-  (I), 4670  Univ. Di Siena Univ. di Siena Univ. di Firenze	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems: Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub Prijaca, Naser 09:20 A T-S Type of Rough Fuzzy Coloutput Data, 4729	Barbara  The Presence of Actuator Saturation  Univ. of Virginia Regency E Regular Session  Univ. of Electro-Communication City Univ. of Hong Kong  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ. Univ. of Sheffiel Middle East Tech. Univ. odology of Near Optimal Fuzzy  Univ. Clinical Cente Faculty of Electrical Engineering
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions Chesi, Graziano Garulli, Andrea	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Curres Programs (I), 4664  ETH Zurich  Stems Via Polynomially Parameter-  (I), 4670  Univ. Di Siena Univ. di Siena	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems I Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub Prijaca, Naser 09:20 A T-S Type of Rough Fuzzy Coloutput Data, 4729 Huang, Jinjie	Barbara  The Presence of Actuator Saturation  Univ. of Virginia Regency E Regular Session  Univ. of Electro-Communications City Univ. of Hong Kong  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ Univ. of Sheffield Middle East Tech. Univ odology of Near Optimal Fuzzy  Univ. Clinical Cente Faculty of Electrical Engineering
LMI Optimization for Fixed-Orde 4646 Henrion, Didier 09:00 Higher-Order Relaxations for Ro Verifications for Exactness (I), 4 Scherer, Carsten W. 09:20 On the Implementation of Prima Semidefinite Programming Prob Lemma. (I), 4658 Vandenberghe, Lieven Balakrishnan, Venkataramanan Wallin, Ragnar Hansson, Anders 09:40 Exploiting Structure in Sum of S Parrilo, Pablo A. 10:00 Robust Stability of Polytopic Sys Dependent Lyapunov Functions Chesi, Graziano Garulli, Andrea Tesi, Alberto	r H-Infinity Controller Design (I),  LAAS-CNRS  abust LMI Problems with  652  Delft Univ. of Tech.  I-Dual Interior-Point Methods for Ilems Derived from the KYP  Univ. of California Los Angeles Purdue Univ.  Linkoping Univ.  Linkoping Univ.  Linkoping Univ.  Cuares Programs (I), 4664  ETH Zurich  Stems Via Polynomially Parameter-  (I), 4670  Univ. Di Siena Univ. di Siena Univ. di Firenze	10:20 Analysis of Linear Systems in the and L2 Disturbances, 4711 Fang, Haijun Lin, Zongli Hu, Tingshu  FrA03 Fuzzy Systems: Chair: Tanaka, Kazuo Co-Chair: Feng, Gang 08:40 Stable Controller Design for the Joint Robot Arm Based on Lie A Gurkan, Evren Banks, Stephen Paul Erkmen, Ismet 09:00 Study of Two Step Design Meth Logic Controller, 4723 Osmic, Jakub Prijaca, Naser 09:20 A T-S Type of Rough Fuzzy Coloutput Data, 4729	Barbara  The Presence of Actuator Saturation  Univ. of Virginia Regency E Regular Session  Univ. of Electro-Communications City Univ. of Hong Kong  T-S Fuzzy Model of a Flexible- ligebra, 4717  Middle East Tech. Univ Univ. of Sheffield Middle East Tech. Univ odology of Near Optimal Fuzzy  Univ. Clinical Cente Faculty of Electrical Engineering

09:40		08:40	
Piecewise Nonlinear Control, 4		Gradient Algorithms for Finding	Common Lyapunov Functions,
Ohtake, Hiroshi Tanaka, Kazuo	Univ. of Electro-Communications Univ. of Electro-communications	4782 Liberzon, Daniel	Univ. of Illinois at Urbana-
Wang, Hua O. 10:00	Boston Univ.	Tempo, Roberto	Champaign Pol. di Torino
	ontroller Synthesis of Discrete Time	09:00	
Fuzzy Systems, 4741	ontroller dynaresia or Disorcio Time		Switched Linear Systems through
Wang, Louis	Univ. of New South Wales	Randomized Algorithms, 4788	
Feng, Gang	City Univ. of Hong Kong	Ishii, Hideaki	Univ. of Illinois at Urbana-
Hesketh, Timothy	Univ. of New South Wales		Champaign
10:20		Basar, Tamer	Univ. of Illinois at Urbana-
	del Functional Relationships in	Tamas Dahada	Champaign
Product Planning, 4747		Tempo, Roberto	Pol. di Torino
Chen, Yizeng	Northeastern Univ.	09:20	
Tang, Jiafu	Northeastern Univ.		WM Systems Using Sampled-Data
FrA04	Pagangy C	Modeling, 4794 Almer, Stefan	Royal Inst. of Tech.
Process Control	Regency C Regular Session	Jonsson, Ulf T.	Royal Inst. of Tech.
Chair: Guay, Martin	Queen's Univ.	Kao, Chung-Yao	Massachusetts Inst. of Tech.
Co-Chair: Peng, Hui	The Inst. of Statistical	Mari, Jorge	Royal Inst. of Tech.
Co-Chair. Peng, Hui	Mathematics	· •	Noyal first. of Teori.
	Mathematics	09:40	t1.1 i 01 1000
08:40		On Convergence Rates of Switch	
Adpative Extremum Seeking C		Sun, Zhendong	National Univ. of Ireland,
	ctors with Temperature Constraints,	Charter Dahart	Maynooth
4753	According to the t	Shorten, Robert	National Univ. of Ireland, Maynooth
Guay, Martin	Queen's Univ. Univ. Catholique de Louvain	40.00	waynooti
Dochain, Denis Perrier, Michel	Ec. Pol.	10:00	
	EC. Pol.	Synthesis of Uniformly Ultimate	
09:00		Fordiscrete-Time Uncertain Swit	
End-Point Optimization of Bate		Lin, Hai	Univ. of Notre Dame
Palanki, Srinivas	Florida State Univ.	Antsaklis, Panos J.	Univ. of Notre Dame
Vemuri, Jyothy	Florida State Univ.	10:20	
09:20			ontrol Synthesis for Discrete-Time
Composition Control of Binary	Mixtures in STEC Plant by a Model	Uncertain Switched Systems, 48	
Free Control Method*		Xie, Dongmei	Peking Univ.
Zhao, Zhong	Saga Univ.	Wang, Long	Peking Univ.
Nakamura, Masatoshi	Saga Univ.	Hao, Fei	Peking Univ.
lkegami, Y.	Saga Univ.	Xie, Guangming	Peking Univ.
09:40			
Hybrid Modelling and Monitori.	ng of Streptomycin Fermentation	FrA06	Maui Suite 2
Process, 4765		Learning and Optimizing Based on Experience: Sample	Invited Session
Jin, Xiaoming	Zhejiang Univ.	Path Approaches: From PA to	
Wang, Shuqing	Zhejiang Univ.	MDPs	
10:00		Chair: Panayiotou, Christos	Univ. of Cyprus
Modeling and Control of Nonlin	near Nitrogen Oxide Decomposition	Co-Chair: Cao, Xi-Ren	Hong Kong Univ. of Sci. & Tech.
Process, 4770	-	Organizer: Panayiotou,	Univ. of Cyprus
Peng, Hui	The Inst. of Statistical	Christos	Offiv. of Cypius
	Mathematics	Organizer: Cao, Xi-Ren	Hong Kong Univ. of Sci. & Tech.
Ozaki, Tohru	The Inst. of Statistical	Organizer: Wardi, Yorai	Georgia Inst. of Tech.
	Mathematics	•	. Coolgia mon or reon.
Haggan-Ozaki, Valerie	Sophia Univ.	08:40	huted Decision Meline Pennd
10:20			buted Decision Making Based on
	e Control for Linear Uncertain	Experience, 4818	Harvard Univ.
		Ho, Yu-Chi	narvard Univ.
Systems with Saturations, 477 Hu, Li-sheng		09:00	
Systems with Saturations, 477	6 Shanghai Jiao Tong Univ. Univ. of Alberta	A System Theoretic Perspective	of Learning and Optimization (I),
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan	6 Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia	A System Theoretic Perspective 4820	- , , , , , , , , , , , , , , , , , , ,
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao	6 Shanghai Jiao Tong Univ. Univ. of Alberta	A System Theoretic Perspective 4820 Cao, Xi-Ren	- , , , , , , , , , , , , , , , , , , ,
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan Shao, Hui-He	Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia Shanghai Jiao Tong Univ.	A System Theoretic Perspective 4820 Cao, Xi-Ren 09:20	Hong Kong Univ. of Sci. & Tech.
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan Shao, Hui-He FrA05	Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia Shanghai Jiao Tong Univ. Maui Suite 1	A System Theoretic Perspective 4820 Cao, Xi-Ren 09:20 Congestion Control Using Policy	Hong Kong Univ. of Sci. & Tech.
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan Shao, Hui-He  FrA05 Stability of Switched System	Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia Shanghai Jiao Tong Univ.  Maui Suite 1 Regular Session	A System Theoretic Perspective 4820 Cao, Xi-Ren 09:20 Congestion Control Using Policy Wu, Gang	Hong Kong Univ. of Sci. & Tech.  Rollout (I), 4825  Purdue Univ.
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan Shao, Hui-He FrA05	Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia Shanghai Jiao Tong Univ. Maui Suite 1	A System Theoretic Perspective 4820 Cao, Xi-Ren 09:20 Congestion Control Using Policy	Hong Kong Univ. of Sci. & Tech.  **Rollout (I), 4825  Purdue Univ.  Colorado State Univ.
Systems with Saturations, 477 Hu, Li-sheng Huang, Biao Cao, Yong-Yan Shao, Hui-He  FrA05 Stability of Switched System	Shanghai Jiao Tong Univ. Univ. of Alberta Univ. of Virginia Shanghai Jiao Tong Univ.  Maui Suite 1 Regular Session Univ. of Illinois at Urbana-	A System Theoretic Perspective 4820 Cao, Xi-Ren 09:20 Congestion Control Using Policy Wu, Gang Chong, Edwin K. P. Givan, Robert	Hong Kong Univ. of Sci. & Tech.  **Rollout (I), 4825  Purdue Univ.  Colorado State Univ.
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Maui Suite 4
Regular Session
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Jniv. of Western Australia
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NASA Langley Res. Ctr.
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namics, 4932
Univ. of Bristol
Univ. of Bristol
Univ. of Bristol
Univ. of Sannio
Univ. of Bristol
/ing Model, 4939
California State Univ.
niv. of Southern California
California State Univ.
Guest Room 350
Regular Session
Cong Univ. of Sci. & Tech.
City Univ.
rol, 4945
Kong Univ. of Sci. & Tech.
Lousiana State Univ.
Hilbert Spaces, 4951
Univ. of Padova
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Univ. of Siena
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Longoria, Raul Limroth, John L	Scaled Vericle, 4962 Patil Chinmaya	The Univ of Texas at Austin		
Limroth, John 10:00 Selection of Initial Gain for Optimal Compensators. 4968 Akpan, Eddie Akpan,				Tel-Avia Olliv
Selection of Initial Gain for Optimal Compensators, 4968 Akpan, Eddie  A				istics of Markovian Jump Linear
Selection of Initial Gain for Optimal Compensators. 4968 Akpan, Eddie  NASA FrA11 Computational Methods and Chair de Oliveira, Maurclo Chair de Oliveira, Maurclo Chair de Oliveira, Maurclo Chair de Oliveira, Maurclo Chair Li, Faming Co-Chair Li, Faming Co-Chair Li, Faming Computer Engineering Univ. of California, San Diego Computer Algebra Tailcred to Matrix Inequalities in Control, 4973 de Oliveira, Maurclo C. Computer Engineering Univ. of California at San Diego Computer Algebra Tailcred to Matrix Inequalities in Control, 4973 de Oliveira, Maurclo C. Computer Engineering Univ. of Campinas Helton, J. William Univ. of California at San Diego One A Frind Site Projective Algorithm for Solving Linear Matrix Inequalities of Control of Computer Engineering Univ. of California at San Diego One A Frind Site Projective Algorithm for Solving Linear Matrix Inequalities of Control of Computer Engineering Univ. of California at San Diego One A Frind Site Projective Algorithm for Solving Linear Matrix Inequalities of Control of Uncertainty Problems, 4985 A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 U. Hand Control of Uncertainty One Algorithm of California at San Diego One Control of California at San Diego One Calif				stics of Markovian Jump Linear
Fr.A13 Guest Room 351 Computed Englational Methods and Inear Inequalities Chair de Oliveira, Mauricio C. School of Electrical and Computer Engineering Univ. of Catifornia, San Diego 18-40 D8-40 D8-40 D8-40 D8-60 D8-6	Selection of Initial Gain for Optin			Univ. of Illinois at Urbana- Champaigr
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Chair: de Oliveira, Mauricio C. Chair: Li, Faming Co-Chair: Li, Faming Computer Fallored to Matrix Inequalities in Control, 4973 de Oliveira, Mauricio C. Computer Engineering Univ. of California at San Diego On Analysis of Multiple Interval Delay Systems Univ. of Missouri-Columbia Massachusetts Inst. 1 Georgia Inst. of Tech Onalysis of Multiple Interval Delay Systems Univ. of Missouri-Columbia On Testing Univ. of California at San Diego On Interval Delay Systems Univ. of California at San Diego Conditions, 5048 Chen. Jie Ward Mardavij Massachusetts Inst. of Tech Onalysis of Multiple Interval Delay Systems Via Misacri Univ. of Tech On Testing the Stability of Quasipolynomials: Frequency-Sweeping Conditions, 5048 Chen. Jie Warticle Character Character Character Character Character Characte	Computational Methods and			champaigr
Co-Chair: Li, Faming Univ. of California, San Diego Osa-40 Computer Algobra Tailored to Matrix Inequalities in Control. 4973 de Oliveira, Mauricio C. School of Electrical and Computer Engineering Univ. of California at San Diego Osa-90 Osa-90 Osa-90 Osa-10 A Finite Step Projective Algorithm for Solving Linear Matrix Inequalities. 973 Ors. Robert E. Chines Winiv of House of California at San Diego Moore, John B. Australian National Univ. Of Salfornia at San Diego Osa-90 A Semidefinite Representation for Some Minimum Cardinality Problems. 4985 of Aspremont, Alexandre Osa-90 Skelton, Robert E. Univ. of California at San Diego Onatic Politoria Scandina Systems Via Surfaced Univ. California at San Diego Onatic Politoria Scandina Systems Scandi		School of Electrical and		от Uncertain iviarkovian Jump
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de Oliveira, Mauricio C.  School of Electrical and Computer Engineering Univ. of Campinas Helton, J. William  Univ. of California at San Diego (9:0)  4. Finite Step Projective Algorithm for Solving Linear Matrix Indequalities. 4979  Ordinary Moore, John B.  Rami, Mustapha Ait  Chinese Univ. of Hong Kong Australian National Univ. 09:20  A Semidefinite Representation for Some Minimum Cardinality  The Conomical Simulation Problem. 4991  U. Faming  U. H. Faming  Univ. of California at San Diego  Univ. of Missouri-Columbia  Rami, Ajeet  Univ. of Wissouri-Columbia  Rami, Ajeet  Univ. of Wissouri-Columbia  Ramida, Ajeet  Univ. of California at San Diego  Univ. of Wissouri-Columbia  Ramida, Ajeet  Univ. of Wissouri-Columbia  Ramida, Ajeet  Univ. of Wissouri-Cunival  Ramida, Ajeet  Univ. of Wissouri-Cunival  Ramida, Aje	08:40	•		
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A Finite Step Projective Algorithm for Solving Linear Matrix Inequalities, 4979 Orsi, Robert National ICT Australia Rami, Mustapha Alt Chinese Univ. of Hong Kong Moore, John B. Australian National Univ. 94. Semidefinite Representation for Some Minimum Cardinality Problems, 4985 A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 A Semidefinite Representation for Some Minimum Cardinality Problems, 4986 A Semidefinite Representation for Some Minimum Cardinality Problems, 4987 Discovery of Asserting Control of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4987 Discovery of Asserting Control of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4981 Discovery of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4981 Discovery of Asserting Control of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4981 Discovery of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4982 Discovery of Missouri-Columbia Os. 40 A Semidefinite Representation for Some Minimum Cardinality Problems, 4981 Discovery of Missouri-Columbia Os. 90 On Analysis of Multiple Interval Delay Systems Vis Sufficient and Symptotically Necessary Companison Systems Vis Sufficient and Symptoticall		- -	·	-
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Moore, John B. Australian National Univ. 09:20 A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 Of Asprenont, Alexandre Stanford Univ. 09:40 Display Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. of California at San Diego Sketton, Robert E. Univ. Of California at San Diego Conditions, 5048 Chen, Jie Univ. of Quasipolynomials: Frequency-Sweeping Conditions, 5048 Chen, Jie Univ. of California at Riversid Univ. Of Techsting the Stability of Linear Neutral Systems A DLF Approach, 5054 Han, Cling-long Central Queensland Univ. Of Techsting the Stability of Linear Neutral Systems, 5060 Routh-Hurwitz Criterion and Stability of Neutral Systems with Mixed Time-Varying Delay Arguments, 5066 Li, Tao Dalian Univ. of Techst Membership Identification for Adaptive Control: Input Design, 5011 Cadic, Maria Twente Univ. of Melbourne Darion Co-Chair: Angeli, David Univ. of Techst Membership Identification for Melbourne Darion Co-Chair: Angeli, David Univ. of Fieraz Systems with Polyhedral Uncertainty, 5017 Blanchini, Glanni Univ. of Illinois at Urbanat Champaign Dalian Univ. of Techsular Systems with Polyhedral Uncertainty, 5017 Blanchini, Glanni Univ. of Linear Systems Affected by Time-Invariant Hypercubic Parametric Uncertainty, 5019 Univ. of Melbourne Univ. Of Selonation Univ. Of Linear Systems Affected by Time-Invariant Hypercubic Parametric Uncerta				Univ. of Missouri- Columbia
A Semidefinite Representation for Some Minimum Cardinality Problems, 4985 d'Aspremont, Alexandre Stanford Univ. 09:40 The Economical Simulation Problem, 4991 Li, Faming Univ. of California at San Diego Skelton, Robert E. Univ. of California at San Diego 10:00 Fast Linear Iterations for Distributed Averaging, 4997 Xiao, Lin Boyd, Stephen P Stanford Univ. 10:20 MILP Formulation and Polynomial Time Algorithm for an Aircraft Scheduling Problem, 5003 Bayen, Alexandre M. Stanford Univ. Tomlin, Claire J. Stanford Univ. Thoman, Jiawei Stanford Univ. Thoman, Jawei Stanford Univ. Thang, Jiawei Stanford Univ. Thang, Jiawei Stanford Univ. Thang, Jiawei Stanford Univ. The Univ. of Melbourne Co-Chair: Mareels, Iven Univ. of Melbourne Co-Chair: Mareels, Iven The Univ. of Melbourne Mareels, Iv	•			
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## Analysis of Multiple Interval Delay Systems Via Sufficient and Asymptotically Necessary Comparison Systems, 5041  **Nanospe.**Carl R.**  **Nanospe.**Carl R.**  **Nospe.**Carl R.**  **Nobust Stability of Quasipolynomials: Frequency-Sweeping Conditions. 5048  Chen. Jie Univ. of California at Riverside Niculescu, Siviu-Julian Univ. of California at Riverside Niculescu, Siviu-Julian Univ. of California at Riverside Niculescu, Siviu-Julian Univ. of California at San Diego Modulis. Frequency-Sweeping Conditions. 5048  Chen. Jie B.**  **Nobust Stability of Quasipolynomials: Frequency-Sweeping Conditions. 5048  Chen. Jie B.**  **Nobust Stability of Linear Neutral Systems With Mixed Time-World Univ.			•	Univ. of Missouri-Columbia
d'Aspremont, Alexandre 09:40  17he Economical Simulation Problem, 4991  Li, Faming Li, Faming Li, Faming Li, Faming Univ. of California at San Diego Skelton, Robert E. Univ. of California at San Diego 10:00  Fast Linear Iterations for Distributed Averaging, 4997 Xiao, Lin Boyd, Stephen P Stanford Univ. 10:20  MILP Formulation and Polynomial Time Algorithm for an Aircraft Scheduling Problem, 5003 Bayen, Alexandre M. Tomlin, Claire J. Stanford Univ. Tomlang, Jiawei Stanford Univ. Stanford Univ. Tomlin, Claire J. Stanford Uni		or Some Minimum Cardinality		Systems Via Sufficient and
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A Note on Computing Polynomial Filters for Robust SPR of Systems with Polyhedral Uncertainty, 5017 Bianchini, Gianni Univ. di Siena 09:20 Robust Analysis of Linear Systems Affected by Time-Invariant Hypercubic Parametric Uncertainty, 5019 Chesi, Graziano Univ. Di Siena  Co-Chair: Angeli, David Univ. of Firenz 08:40 Analysis of Input to State Stability for Discrete Time Nonlinear Systems Via Dynamic Programming, 5068 Huang, Shoudong James, Matthew R. Nesic, Dragan Univ. of Melbourn	09:00			Univ. of Melbourne
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Bianchini, Gianni Univ. di Siena  09:20  Robust Analysis of Linear Systems Affected by Time-Invariant Hypercubic Parametric Uncertainty, 5019  Chesi, Graziano  Univ. di Siena  Analysis of Input to State Stability for Discrete Time Nonlinear Systems Via Dynamic Programming, 5068 Huang, Shoudong James, Matthew R. Australian National Univ. Nesic, Dragan Univ. of Melbourn			08:40	
Robust Analysis of Linear Systems Affected by Time-Invariant Huang, Shoudong Australian National Univ. Parametric Uncertainty, 5019 James, Matthew R. Australian National Univ. Chesi, Graziano Univ. Di Siena Nesic, Dragan Univ. of Melbourn				for Discrete Time Nonlinear
Robust Analysis of Linear Systems Affected by Time-Invariant Huang, Shoudong Australian National Univ. Phypercubic Parametric Uncertainty, 5019 James, Matthew R. Australian National Univ. Chesi, Graziano Univ. Di Siena Nesic, Dragan Univ. of Melbourn	09:20			
Chesi, Graziano Univ. Di Siena Nesic, Dragan Univ. of Melbourn		ms Affected by Time-Invariant		Australian National Univ
Cilesi, Giaziano Ciliv. Di Siena	Hypercubic Parametric Uncertai	nty, 5019		
	Chesi, Graziano	Univ. Di Siena	Nesic, Dragan Dower, Peter M.	Univ. of Melbourn The Univ. of Melbourn

09:00	•	Degenerative Systems, 5135	
Scaling Supply Rates of ISS Syste	ems for Stability of Feedback	Johnson, Timothy L.	GE Global Res.
Interconnected Nonlinear System		Cabbi	·
Ito, Hiroshi	Kyushu Inst. of Tech.	FrDPL Bode Lecture	Monarchy Ballroom
09:20		Chair: Shaw, Leonard	Plenary Session Pol. Univ.
Some Remarks on Density Functi	ons for Dual Lyapunov Methods,	·	FOI. Offiv.
5080 Angeli, David	Univ. of Firenze	11:00 Challenges of Nonlinear Identifica	ation *
<del>.</del> .	Univ. of Firenze	Ljung, Lennart	Linköping Univ.
09:40 A New Approach for Asymptotic S	Stability Analysis in the Case of		
Discontinuous Lyapunov Function	Derivative 5083	FrM01	Monarchy Ballroom
Lu, Xiao-yun	Univ. of California at Berkeley	Linear Matrix Inequalities	Regular Session
Hedrick, J. Karl	Univ. of California at Berkeley	Chair: Skelton, Robert E.	Univ. of California at San Diego
10:00		Co-Chair: Peres, Pedro L. D.	Univ. of Campinas
Converse Theorems of the Princip	al Lyapunov Results for Partial	12:40	
Stability of General Dynamical Sys		A Unified LMI Approach to Reduc Pencil Perspective, 5137	ed-Order Controllers: A Matrix
Molchanov, Alexander P. Michel, Anthony N.	Russian Acad. of Sciences	Xin, Xin	Okayama Prefectural Univ.
Sun, Ye	Univ. of Notre Dame Univ. of Notre Dame	13:00	onayama i rorostarar omir.
10:20	Offiv. of Notic Dame	An LMI Optimization Approach for	r Structured Linear Cntrollers.
A Generalization of Piecewise Line	ear I vanunov Functions 5091	5143	
Ohta, Yuzo	Kobe Univ.	Han, JeongHeon	Univ. of California at San Diego
Tsuji, Masaaki	Kobe Univ.	Skelton, Robert E.	Univ. of California at San Diego
		13:20	
FrAPI	Grand Promenade	Less Conservative LMI Condition	
Discrete Events and Learning Chair: Abdallah, Chaouki T.		Oliveira, Ricardo C. L. F. Peres, Pedro L. D.	Univ. of Campinas Univ. of Campinas
•	Univ. of New Mexico	•	Oniv. or Campinas
08:40 Least Squares Support Vector Ma	phinon for Fixed Stop and Fixed	13:40 On Strong Stabilization and Hinfir	nity Strong Stabilization E1EE
Set CDMA Power Control, 5097	times for rixed-step and rixed-	Chou, Yung-Shan	Tamkang Univ.
Rohwer, Judd	Sandia National Lab.	Wu, David Tai-Zu	National Central Univ.
Abdallah, Chaouki T.	The Univ. of New Mexico	Leu, Jiunn-Liang	Tamkang Univ.
Christodoulou, Christos	The Univ. of New Mexico	14:00	
		Low Order Multicriteria H-Inf Desi	gn Via Bilinear Matrix
Neural Network Application to Line	ear Systems with Binary Inputs,	Inequalities, 5161	<b>-</b>
5103	~	Fransson, Carl-magnus	Chalmers Univ. of Tech.
Holderbaum, William	The Univ. of Reading	Lennartson, Bengt	Chalmers Univ. of Tech.
Poblist Mobile Pabetia Formation	Combant Hair - Into and Life	14:20 Parameter-Dependent Lyapunov	Eunstians for Stability Analysis of
Robust Mobile Robotic Formation Protocols, 5109	Control Using Internet-Like	LTI Parameter Dependent System	runctions for Stability Arialysis of
Sandoval-Rodriguez, Rafael	Univ. of New Mexico	Zhang, Xiping	Georgia Inst. of Tech.
Abdallah, Chaouki T.	Univ. of New Mexico	Tsiotras, Panagiotis	Georgia Inst. of Tech.
Hokayem, Peter	Univ. of New Mexico	lwasaki, Tetsuya	Univ. of Virginia
Schamiloglu, Edl Byrne, Ray H.	Univ. of New Mexico	FrM02	D
byine, Ray n.	Sandia National Lab.	Nonlinear Systems VI	Regency A Regular Session
Study on Real Time Disercts Even	at Systems by I lains Cantrallad	Chair: Medanic, Juraj V.	Univ. of Illinois at Urbana-
Study on Real-Time Discrete Even Temporal Timed-Petri-Nets. 5113	t Systems by Using Controlled	onam inclaims, cara, vi	Champaign
Liu, Changyou	Civil Aviation Univ. of China	Co-Chair: French, Mark	Univ. of Southampton
Li, Yongjian	Tshinghua Univ.	12:40	·
<del></del>		Invariance for Impulsive Control S	ystems, 5174
Fault Isolation in Discrete Event Sy	stems by Observational	Oliveira, Valeriano	IMECC- UNICAMP
Abstraction, 5118	•	Pereira, Fernando Lobo	Porto Univ. Inst. For Systems &
Lawesson, Dan	Linköping Univ.	Silva G N	Robotics
Nilsson, Ulf	Linköping Univ.	Silva, G.N.	Univ. Estadual Paulista
Klein, Inger	Linköping Univ.	13:00 Gap Metric Robustness of a Back	stenning Control Dooise 5480
Stochastic Single Machine Setred	ding with Brane-dieset to	Xie, Chengkang	Stepping Control Design, 5180 Univ. of Southampton
Stochastic Single Machine Schedu Weights to Minimize Deviations of		French, Mark	Univ. of Southampton
Common Due Date, 5124	оопревол типез пон а	13:20	
Jia, Chunfu	Nankai Univ.	Nonlinear Output Feedback Contr	oller Design by Proiective
		Controls, 5185	
Dynamic Discrete-Time Load Balar	ncing in Distributed Systems in	Medanic, Juraj V.	Univ. of Illinois at Urbana-
the Presence of Time Delays, 5128			Champaign
Dhakal, Sagar	Univ. of New Mexico	13:40	
Paskaleva, Biliana	Univ. of New Mexico	Stabilization of a Chain of Integrat	
Hayat, Majeed M. Schamiloglu, Edl	Univ. of New Mexico	Application to the Inverted Pendul Lozano, Rogelio	
Abdallah, Chaouki T.	Univ. of New Mexico Univ. of New Mexico	Dimogianopoulos, Dimitrios	Univ. de Tech. de Compiegne Univ. de Tech. de Compiegne
- Committee of the Comm	OTHE. OF INCA MICKIGO	Damogianopoulos, Dillinillos	C.MV. do 1 Com. de Complègne

14:00		13:20	
14:00 Properties of the Composite Qua	dratic Lyapunov Functions, 5197	POD Model Reduction with S	tability Guarantee 5254
Hu, Tingshu	Univ. of Virginia	Prajna, Stephen	California Inst. of Tech.
Lin, Zongli	Univ. of Virginia	• ' •	Camornia mat. or reon.
14:20		13:40	Systems Approximation by
Discrete Time Versus Hybrid Sys	stome F202	Model Reduction of Uncertain Uncertain System, 5259	1 Systems: Approximation by
Monaco, Salvatore	Univ. degli Studi di Roma La	Dolgin, Yuri	Tech Israel Inst. of Tech.
Wichaco, Salvatore	Sapienza	Zeheb, Ezra	Tech. Inst. of Tech.
Normand-Cyrot, Marie-	CNRS-ESE	•	reon. mat. or reon.
dorothee	0.11.0-202	14:00	and Markey to Table and Their
Califano, Claudia	Univ. di Roma		ons Via the Jury Table and Their
		Applications, 5265 Zhao, Xiaodong	Hong Kong Univ. of Sci. & Tech.
FrM03	Regency B	Qiu, Li	Hong Kong Univ. of Sci. & Tech.
Fuzzy Systems II	Regular Session		riong Rong Only, or Sci. & Tech.
Chair: Fadali, Mohammed	Univ. of Nevada	14:20	District 1 0 -1 - 5074
Sami		Samar, Sikandar	eneous Distributed Systems, 5271
Co-Chair: Sonbol, Assem	Univ. of Nevada - Reno	Samar, Sikanuai	Univ. of Illinois at Urbana-
12:40		Beck, Carolyn L.	Champaign Univ. of Illinois at Urbana-
Fuzzy Lyapunov Stability Analysi	is of Discrere Type II TSK	Deck, Carolyn L.	Champaign
Systems, 5209			Champaigh
Sonbol, Assem	Univ. of Nevada - Reno	FrM05	Maul Suite 1
Fadali, Mohammed Sami	Univ. of Nevada	Switched Systems I	Regular Session
13:00		Chair: Asai, Toru	Osaka Univ.
Hybrid Kalman Filter-Fuzzy Logic	Multisensor Data Fusion	Co-Chair: Pettersson, Ste	
Architectures, 5215	Wallischsor Data Fasion	12:40	onamicio oniv. or recii.
Mort. Neil	Univ. of Sheffield	,_,,	wat Attanuation of Disturbance
Escamilla-Ambrosio,	Univ. of Bristol	Responses Due to Switching	oust Attenuation of Disturbance
Ponciano Jorge		Asai, Toru	Osaka Univ.
13:20		•	Osaka Olliv.
	to Fuzzy Decision Making, 5221	13:00	0
Lee, E. Stanley	Kansas State Univ.	Synthesis of Switched Linear	
syau, Yu-Ru	Da Yeh Univ.	Pettersson, Stefan	Chalmers Univ. of Tech.
13:40	24 (011 0)	13:20	
Adaptive Fuzzy Control for a Cla	na of Lincortoin Manlinear		perties for Discrete-Time Uncertain
Systems, 5227	SS OF Officertain Nothinear	Switched Linear Systems, 52	
Vélez-Díaz, Daniel	National Univ. of Mexico	Lin, Hai	Univ. of Notre Dame
Tang, Yu	National Univ. of Mexico	Antsaklis, Panos J.	Univ. of Notre Dame
*·	Tatonal Gilly, or Moxido	13:40	
14:00 State Foodback Stabilization for	Nanlinger Time Dalou Sustame: A		trol of Switching Systems, 5295
	Nonlinear Time-Delay Systems: A nt Lyapunov-Krasovskii Functional	Bengea, Sorin C.	Purdue Univ.
Approach, 5233	it Lyapunov-raasovskii i unctionai	DeCarlo, Raymond A.	Purdue Univ.
Park, PooGyeon	Pohang Univ. of Sci. & Tech.	14:00	
Lee, Seung Shin	Pohang Univ. of Science and	The Multivariable Circle Crite	rion for Switched Continuous
	Tech.	Systems, 5301	
Choi, Doo Jin	Pohang Univ. of Sci. & Tech.	Bedillion, Mark	Carnegie Mellon Univ.
14:20		Messner, William	Carnegie Mellon Univ.
H2 State Feedback Control for F	uzzy Singularly Parturbad	14:20	
Systems, 5239	uzzy Sirigulariy Ferturbed	Kinematic Reducibility of Mul	tiple Model Systems, 5307
Liu, Huaping	Univ. of Tsinghua	Murphey, Todd	The Aerospace Corp.
Sun, Fuchun	Univ. of Tsinghua	Burdick, Joel W.	California Inst. of Tech.
He, Kezhong	Univ. of Tsinghua		
Sun, Zengqi	Univ. of Tsinghua	FrM06	Maui Suite 2
oun, zengqi	Only. Or Tsinghaa	Stochastic Systems I	Regular Session
FrM04	Regency C	Chair: Buche, Robert	NC State Univ.
Model Reduction	Regular Session	Co-Chair: Hu, Jianghai	Univ. of California at Berkeley
Chair: Samar, Sikandar	Stanford Univ.	12:40	-
Co-Chair: Antoulas,	Rice Univ.		iscrete Time Systems: An Application
Athanasios C.		to Aircraft Collision Avoidance	
12:40		Watkins, Oliver	Univ. of Cambridge
Model Reduction of Spatially-Inve	ariant Array Systems 5244	Lygeros, John	Univ. of Patras
Samar, Sikandar	Univ. of Illinois at Urbana-	13:00	
Carrier, Cineriosi	Champaign		cking Algorithms: Applications to
Beck, Carolyn L.	Univ. of Illinois at Urbana-	Adaptive Antenna Arrays for	
	Champaign	Communications, 5320	and the state of t
13:00	5pa.gii	Buche, Robert	NC State Univ.
A Time-Limited Balanced Reduc	tion Method 5250	Kushner, Harold J.	Brown Univ.
Gugercin, Serkan	Virginia Tech.		
Antoulas, Athanasios C.	Rice Univ.		
	THOO STITE		

13:20		12:40	
Feedforward Feedback Control 5328	ller Design for Uncertain Systems,	An Exponential Class of Model-Fa the Presence of Uncertain Camel	ree Visual Servoing Controllers in ra ra Calibration, 5390
Wik, Torsten	Chalmers Univ. of Tech.	Fang, Yongchun	Cornell Univ.
Fransson, Carl-magnus	Chalmers Univ. of Tech.	Dixon, Warren E.	Oak Ridge NationI Lab.
Lennartson, Bengt	Chalmers Univ. of Tech.	Dawson, Darren M.	Clemson Univ.
		Chen, Jian	Clemson Univ.
13:40	T. D		Cicinson Cini.
	Three Dimensional Aircraft Flight,	13:00	
5335		Adaptive Visual Servoing in the P	resence of Intrinsic Calibration
Hu, Jianghai	Univ. of California at Berkeley	Uncertainty, 5396	
Prandini, Maria	Pol. di Milano	Chen, Jian	Clemson Univ.
Sastry, Shankar	Univ. of California at Berkeley	Behal, A.	Clemson Univ.
14:00		Dawson, Darren M.	Clemson Univ.
	ring a Class of Multi-Agent Markov	Dixon, Warren E.	Oak Ridge Nationl Lab.
Decision Problems, 5341	mg a crace or man, rigorn marries	13:20	
Chang, Hyeong Soo	Sogang Univ.	Identification of a Moving Object's	s Velocity with a Fixed Camera
Fu, Michael C.	Univ. of Maryland	5402	o tology will at mod odinolog,
•	One. or waryland	chitrakaran, vilas	Clemson Univ.
14:20		Dawson, Darren M.	Clemson Univ.
Probabilistic Distances between	n Finite-State Finite-Alphabet	Dixon, Warren E.	Oak Ridge NationI Lab.
Hidden Markov Models, 5347			Clemson Univ.
Xie, Li	Univ. Coll. The Univ. of New	Chen, Jian	Clemson only.
	South Wales	13:40	
Ugrinovskii, Valery	Australian Defence Force Acad.	Visual Servoing of 6 DOF Manipu	ulator by Multirate Control with
Petersen, Ian R.	Australian Defence Force Acad.	Depth Identification, 5408	-
		Fujimoto, Hiroshi	Nagaoka Univ. of Tech.
FrM07	Regency Boardroom	14:00	•
Estimation II	Regular Session	Image-Based Tracking Control of	f a Plima 5414
Chair: Bodson, Marc	Univ. of Utah	Fukao, Takanori	Kyoto Univ. Carnegie Mellon
Co-Chair: Skelton, Robert E		rukao, takanon	
•	. Onv. or ourronna at our blogs	Fulitari Varushi	Univ.
12:40	4	Fujitani, Kazushi	Kyoto Univ. Carnegie Mellon
Performance Analysis of Hybrid		Manager Talan	Univ.
Hwang, Inseok	Stanford Univ.	Kanade, Takeo	Carnegie Mellon Univ.
Balakrishnan, Hamsa	Stanford Univ.	14:20	
Tomlin, Claire J.	Stanford Univ.	An LMI Solution to Visual-Based	Localization As the Dual of Visual
13:00		Servoing, 5420	
Frequency Estimation and Trac	king of Multiple Sinusoidal	Bellot, Delphine	LAAS-CNRS
Components, 5360		Danes, Patrick	LAAS-CNRS
Guo, Xiuyan	Univ. of Utah	•	
Bodson, Marc	Univ. of Utah	FrM09	Maui Suite 4
	Oinv. Or Otali	Missile and Aircraft GNC	Regular Session
13:20	- for Montineau Diseasts	Chair: Lyshevski, Sergey	Rochester Inst. of Tech.
Progressive Bayesian Estimation		Co-Chair: Kaminer, Isaac	Naval Post-Graduate School
TimeSystems: The Filter Step for		·	Travair out Chadadio Conto
Andmultidimensional States, 53		12:40	
Hanebeck, Uwe	Univ. Karlsruhe	MEMS Smart Variable-Geometry	Flexible Flight Control Surfaces:
Feiermann, Olga	Univ. Karlsruhe	Distributed Control and High-Fide	
13:40		Lyshevski, Sergey	Rochester Inst. of Tech.
Multi-Scan Parametric Target T	racking in Clutter, 5372	13:00	
Musicki, Darko	Univ. of Melbourne	Space Transformation Method in	Control of Agile Interceptors and
Evans, Robin J.	Univ. of Melbourne	Missiles with Advanced Microelec	ctromechanical Actuators, 5432
La Scala, Barbara F.	Univ. of Melbourne	Lyshevski, Sergey	Rochester Inst. of Tech.
			reconduction material recons
14:00		13:20	
State Estimation with Finite Sign		On the Development of GNC Alg	orithm for a High-Glide Payload
Li, Weiwei	Univ. of California San Diego	Delivery System, 5438	
Skelton, Robert E.	Univ. of California at San Diego	Kaminer, Isaac	Naval Postgraduate School
14:20		Yakimenko, Oleg	Naval Postgraduate School
Observer Design for Linear Sind	gular Time-Delay Systems, 5384	13:40	
Feng, Jun'e	Shandong Univ.	Optical-Flow Based Precision Mis	ssile Guidance Inspired by
Zhu, Shuqian	Shandong Univ.	Honeybee Navigation, 5444	,,,,,
Cheng, Zhaolin	Shandong Univ.	Manchester, lan	Univ. of New South Wales
3g,	onding only.	Savkin, Andrey V.	Univ. of New South Wales
FrM08	Maui Suite 3	Faruqi, Farhan	Defence Science Tech.
Visual Servo Control	Regular Session	i wadii i willeli	Organisation
Chair: Danes, Patrick	LAAS-CNRS	44.00	Organisation
	I MAG-CINISO	14:00	
Co-Chair: Fang, Yongchun	Clemson Univ.	Capture Zones in a Pursuit-Evasi Shima, Tal	ion Game, 5450 Rafael

Epsilon-Feasible Approximation of the State Reachable Set for Control Surface Inverse Algorithm and Application to Nonlinear H\_; Discrete-Time Systems, 5520 Missile Control, 5456 Osaka Univ. Kung, Chien-Chung Chung Cheng Inst. of Tech. Hirata, Kenji Osaka Univ. National Defense Univ. Ohta, Yoshito Yang, Ciann-Dong National Cheng Kung Univ. 14:20 Via Tech. Inc. Lei, Keng-lon Fuzzy-Based Controller/observer Via Grid Point Design and SVD-Consolidation, 5526 FrM10 **Guest Room 350** The Chinese Univ. of Hong Kong Yam, Yeung Lee, Wai Man Control in Manufacturing Regular Session The Chinese Univ. of Hong Kong Chair: Abdallah, Chaouki T. Univ. of New Mexico Boston Univ. Co-Chair: Paschalidis. FrM12 Maui Suite 5 loannis System Identification Regular Session Boston Univ. Chair: Venkatesh, S. R. Pol. di Torino Co-Chair: Milanese, Mario Optimal Discrete-Flow Control of a Single-Stage Failure-Prone Manufacturing System., 5462 12:40 INRIA MOURANI, Iyad Identification of Uncertain Systems Described by Linear Fractional **ENIM** Hennequin, Sophie Transformations, 5532 **INRIA** Xie, Xiaolan Venkatesh, S.R. Boston Univ. 13:00 13:00 Optimal Distributed Real-Time Scheduling of Flexible Structured Experimental Modeling of Complex Nonlinear Systems, Manufacturing Networks Modeled As Hybrid Dynamical Systems, 5538 5468 Pol di Torino Milanese, Mario Savkin, Andrey V. Univ. of New South Wales Pol. di Torino Novara, Carlo Pivano, Luca Pol. di Torino 13:20 A Modelling Approach for the Dynamic Scheduling Problem of 13:20 Manufacturing Systems with Non Negligible Setup Times and Musical Pitch Tracking Using Internal Model Control Based Finite Buffers, 5472 Frequency Cancellation, 5544 Boccadoro, Mauro Univ. di Perugia Zhao, Zhenyu the Univ. of Western Ontario Valigi, Paolo Univ. di Perugia Univ. of Western Ontario Brown, Lyndon J. 13:40 Supply Chain (SC) Production Scheduling with Dynamic Lead Identifiability of Linear Time-Invariant Differential-Algebraic Time and Quality of Service Constraints, 5478 Systems - Application of Differential Algebra, 5549 Caramanis, Michael C. Boston Univ. Queen's Univ. Ben-Zvi, Amos Anli, Osman Murat Boston Univ. McLellan, P. James Queen's Univ. Boston Univ. Paschalidis, Ioannis Queen's Univ. McAuley, Kim 14:00 Optimal Scheduling Strategies of Jobs Belonging to Different Parameter Identification and Intersample Output Estimation of a Classes on a Single Machine with Variable Processing Times, Class of Dual-Rate Systems, 5555 Univ. of Alberta Ding, Feng Univ. of Genova Giglio, Davide Univ. of Alberta Chen, Tongwen Univ. of Genova Minciardi, Riccardo Univ. of Genova Tassara, Stefano An Optimal Algorithm for the Parameter Identification of MIMO 14:20 Linear Systems Using Bounding Ellipsoids, 5561 Enforcing Service-Level Constraints in Supply Chains with Becis-Aubry, Yasmina Centre de Recherche en Assembly Operations, 5490 Automatique de Nancy (CRAN) Univ. Del Sannio Del Vecchio, Carmen CRAN-CNRS URA 821 Boutayeb, M. Paschalidis, Ioannis Ch. Boston Univ. Univ. Henri Poincare-Nancy Darouach, Mohamed FrM11 Guest Room 351 **Guest Room 450** FrM13 Computational Methods for Regular Session Regular Session Stability of Time-Delay Systems Systems II Chair: Ohta, Yoshito Osaka Univ. Southern Illinois Univ. at Chair: Gu, Kegin Co-Chair: Mitchell, Ian Univ. of British Columbia Edwardsville Univ. de Tech. de Compiegne Co-Chair: Niculescu, Silviu-Trajectory Following Optimization by Gradient Transformation lulian Differential Equations, 5496 12:40 Grantham, Walter J. Washington State Univ. On the Stability of Coupled Delay Differential and Continuous Time Difference Equations, 5567 13:00 Continuous Path Planning with Multiple Constraints, 5502 Pepe, Pierdomenico Univ. of L' Aquila Univ. of British Columbia Verriest, Erik I. Georgia Inst. of Tech. Mitchell, lan Sastry, Shankar Univ. of California at Berkeley 13:00 Quadratic Lyapunov Functions for Linear Control Systems with 13:20 Optimal Switching Policies Using Coarse Timesteppers, 5508 Delays, 5573 BARABANOV, Nikita E. North Dakota State Univ. ND, Armaou, Antonios The Pennsylvania State Univ. Princeton Univ. Kevrekidis, Ioannis

14:00

14:20

13:40

Donde, Vaibhav Hiskens, Ian A.

Shooting for Border Collision Bifurcations in Hybrid Systems, 5514

Univ. of Illinois at UC

Univ. of Wisconsin - Madison

13:20		15:00	
Robust Stability of Teleoperation	Schemes Subject to Constant	Inversion of Perturbed Liner Opera	ators That Are Singular at the
and Time Varying Communication		Origin, 5628	atore machine emigrical at the
Taoutaou, Damia	Univ. de Tech. de Compiegne	Howlett, Philip George	Univ. of South Australia
Niculescu, Silviu-Iulian	Univ. de Tech. de Compiegne	Ejov, Vladimir	Univ. of South Australia
Gu, Kegin	Southern Illinois Univ. at	Avrachenkov, Konstantin E.	INRIA Sophia Antipolis
•	Edwardsville	15:20	·
13:40	•	Structured Controller Synthesis Us	sing I MI and Alternating
Robust H_; Control for a Class of	of Uncertain Lur'e Singular	Projection Method, 5632	sing Livit and Alternating
Systems with Time-Delays, 558		Ebihara, Yoshio	Kyoto Univ.
Lu, RenQuan	Zhejiang Univ.	Hagiwara, Tomomichi	Kyoto Univ.
Su, HongYe	Zhejiang Univ.	- · · · · · · · · · · · · · · · · · · ·	Nyoto Cinv.
Chu, Jian	Zhejiang Univ.	15:40	
14:00	Endjiang Chiv	Model Reduction of Stabilizable N	
	and of TCD Like Convention	Farhood, Mazen	Univ. of Illinois at Urbana-
Remarks on the Stability of a Cla Control Models, 5591	ass of TCP-Like Congestion	Beck, Carolyn L.	champaign Univ. of Illinois at Urbana-
Mazenc, Frederic	Inria Lorraine.	Beck, Carolyn L.	Champaign
Niculescu, Silviu-Iulian	Univ. de Tech. de Compiegne	Dullerud, Geir E.	Univ. of Illinois at Urbana-
	Oniv. de l'ech. de Compleghe	Dullerda, Gell L.	champaign
14:20		40.00	onampaign
	stems Via Lifting Technique, 5595	16:00	( . O) (( D) ( O . (
Hirata, Kentaro	Osaka Prefecture Univ.	On Switching H-Infinity Controllers	s for a Class of LPV Systems,
Kokame, Hideki	Osaka Prefecture Univ.	5644	The Object Oreas Hele
F-114/4-15	Guest Room 451	Yan, Peng	The Ohio State Univ.
	Oucot Housin 401	Ozbay, Hitay	Bilkent Univ.
Stability of Nonlinear Systems		16:20	•
Chair: Haddad, Wassim M.	Georgia Inst. of Tech.	Linear Parameter Varying Control	ler for an Induction Machine,
Co-Chair: Chellaboina,	Univ. of Missouri- Columbia	5651	
VijaySekhar		Mosskull, Henrik	-Bombardier Transportation,
12:40			Sweden
Stabilization of Nonlinear RLC C	ircuits: Power Shaping and	± ± ± ± ± ± ± ± ± ± ± ± ± ± ± ± ± ± ±	
Passivation, 5597		FrP02	Regency A
Ortega, Romeo	LSS-SUPELEC	Nonlinear Systems VII	Regular Session
Jeltsema, Dimitri	Delft Univ. of Tech.	Chair: Di Bernardo, Mario	Univ. of Sannio
Scherpen, Jacquelien M.A.	Delft Univ. of Tech.	Co-Chair: Lin, Zongli	Univ. of Virginia
13:00		15:00	
Large-Scale Nonlinear Dynamic	al Systems: A Vector Dissipative	Passivity-Based Control of a Doub	
Systems Approach, 5603		Interconnected with an Induction N	Motor, 5657
Haddad, Wassim M.	Georgia Inst. of Tech.	Becherif, mohamed	LSS-SUPELEC LGEP
Chellaboina, VijaySekhar	Univ. of Missouri- Columbia	Ortega, Romeo	LSS-SUPELEC
Nersesov, Sergey G.	Georgia Inst. of Tech.	Mendes, Eduardo	ESISAR-INPG
13:20		Lee, SangCheol	Postech
Estimating the Domain of Attract	tion: A Light LMI Technique for a	15:20	
Class of Polynomial Systems, 56		Finite Gain Lp Stabilization of Disc	
Chesi, Graziano	Univ. Di Siena	Subject to Actuator Saturation: Th	e Case of P=1, 5663
13:40		Chitour, Yacine	Lab. D'analyse Numerique
Calculation of Stability Region, 5	i615	Lin, Zongli	Univ. of Virginia
Cheng, Daizhan	Chinese Acad. of Sciences	15:40	
Ma, Jin	Tsinghua Univ.	Establishing Lipschitz Properties of	of Multivariable Algebraic Loops
14:00	-	with Incremental Sector Nonlinear	
	ria for Single-Input Single-Output	Grimm, Gene l	Jniv. of California, Santa Barbara
Systems, 5621		Teel, Andrew R.	Univ. of California at Santa
Shorten, Robert	National Univ. of Ireland,		Barbara
·	Maynooth	Zaccarian, Luca	Univ. di Roma, Tor Vergata
Curran, Paul	NUI Dublin	16:00	
Wulff, Kai	NUI Maynooth	Finite Time Convergent Observers	s for Nonlinear Systems 5673
14:20		Menold, Patrick H.	Univ. of Stuttgart
A Nontangency-Based Sufficient	Condition for Roundadness of	Findeisen, Rolf	Univ. of Stuttgart
Orbits, 5626	Condition for Boundedness of	Allgower, Frank	Univ. of Stuttgart
Bhat, Sanjay P.	Indian Inst. of Tech Bombay	16:20	
onat, Ganjay F.	indian hist. Of Feon Bolliday		nuous Stabilizina Controllars for
FrP01	Monarchy Ballroom	A New Method to Design Discontil Chained Systems, 5679	
Lmi/lpv	Regular Session	Ogata, Akihiro	Chiba Univ.
Chair: Dullerud, Geir E.	Univ. of Illinois at Urbana-	Tashiro, Yasuhiro	Chiba Univ.
onaii. Duiletuu, Geli E.	champaign	Liu, Kang-Zhi	Chiba Univ.
Co-Chair: Ariola, Marco	Univ. degli Studi di Napoli	Saito, Osami	Chiba Univ.
20 0 1	Federico II	,···	J.,,,,,
	i caenco n		

Ciassicai State Space Realizability 5685	of Input-Output Bilinear Models,	An Integrated Nonlinear Observer wi a Class of Nonlinear Uncertain Syste	
Kotta, Ülle	Inst. of Cybernetics at TTU	Cao, W.	Nanyang Tech. Univ
Nomm, Sven	Inst. of Cybernetics at TTU	Soh, Y. C.	NanyangTech. Univ
Zinober, Alan	The Univ. of Sheffield	Veluvolu, K. C.	Nanyang Tech. Univ
rP03	Regency B	16:20	· · · · · · · · · · · · · · · · · · ·
eural Network Control		Order Reduction Method for System: Dynamics*	s with Scalar, Linear Fast
Chair: Jagannathan,	The Univ. of Missouri-Rolla	Leizarowitz, Arie	Tech
Sarangapani		16:40	, 55
Co-Chair: Hill, David J.	City Univ. of Hong Kong	Gaussian Inference in Loopy Graphic	cal Models, 5747
5:00		Plarre, Kurt	Univ. of Illinois at Urbana
eural Network Adaptive Control fo			Champaig
onnegative Dynamical Systems, t		Kumar, P. R.	Univ. of Illinois at Urbana
Haddad, Wassim M. Chellaboina, VijaySekhar	Georgia Inst. of Tech. Univ. of Missouri- Columbia		Champaig
Hui, Qing	Georgia Inst. of Tech.	FrP05	Maui Suite
Hayakawa, Tomohisa	Georgia Inst. of Tech.	Switched Systems II	Regular Session
5:20		Chair: Egerstedt, Magnus	Georgia Inst. of Tech
Passivity-Based Neural Network Ad	daptive Output Feedback	Co-Chair: Mukherjee, Ranjan	Michigan State Univ
ontrol for Nonlinear Nonnegative		15:00	mongan etate em
Hayakawa, Tomohisa	Georgia Inst. of Tech.	Controllability and Observability Enh	ancement through Switching:
Haddad, Wassim M.	Georgia Inst. of Tech.	Application to Vibration Control, 575	
Bailey, James M.	Emory Univ. Hospital	Nudehi, Shahin	Michigan State Univ
Hovakimyan, Naira	Georgia Inst. of Tech.	Mukherjee, Ranjan	Michigan State Univ
5:40		15:20	
Discrete-Time Neural Network Con	trol of Nonlinear Systems in	Accessibility of Switched Linear Syst	ems, 5759
Non-Strict Feedback Form, 5703 He, Pingan	Univ. of Missouri-Rolla	Cheng, Daizhan	Chinese Acad. of Science:
Jagannathan, Sarangapani	Univ. of Missouri-Rolla	Chen, Han-Fu	Chinese Acad. of Sciences
	Offiv. of Missour-Rolla	15:40	
l6:00 Adaptive Critic Neural Network-Bas	and Controller for Nonlinear	Reachability of Switched Discrete-Til	me Systems under
Systems with Input Constraints, 57		Constrained Switching, 5765	<b>5</b>
He, Pingan	Univ. of Missouri-Rolla	Wang, Yijing	Peking Univ
Jagannathan, Sarangapani	Univ. of Missouri-Rolla	Xie, Guangming Wang, Long	Peking Univ Peking Univ
6:20		16:00	r exilig office
An Adaptive Approach to Control of	f Distributed Parameter	Pathwise Observability and Controlla	phility Are Decideble 5771
Systems, 5715		Babaali, Mohamed	Georgia Inst. of Tech
King, Belinda B.	AFOSR/NM	Egerstedt, Magnus	Georgia Inst. of Tech
Hovakimyan, Naira	Georgia Inst. of Tech.	16:20	-
16:40		On Observability and Detectability of	f Continuous-Time Linear
earning from Neural Control, 5721		Switching Systems, 5777	
Wang, Cong Hill, David J.	City Univ. of Hong Kong City Univ. of Hong Kong	De Santis, Elena	Univ. of L'Aquil
mili, David J.	City Univ. of Hong Kong	Di Benedetto, M. Domenica	Univ. of L'Aquil
rP04	Regency C	Pola, Giordano	Univ. of L'aquil
lodel Reduction and	Regular Session	16:40	
Estimation	•	Parameter Estimation of Switching P	
Chair: Xie, Lihua	Nanyang Tech. Univ.	Ragot, José	CRAN-INP
Co-Chair: Leizarowitz, Arie	Tech.	Mourot, Gilles Maquin, Didier	CRAN-INP CRAN-INP
5:00		Maquili, Didiel	CICAINTINE
Model Reduction of Irreducible Mar		FrP06	Maui Suite
Kotsalis, Georgios N. Dahleh, Munther A.	Massachusetts Inst. of Tech.	Stochastic Systems II	Regular Sessio
	Massachusetts Inst. of Tech.	Chair: La, Richard J.	Univ. of Maryland, Coll. Par
5:20	Olean of Benjamalla Otable	Co-Chair: Ohara, Atsumi	Osaka Univ
Bilinear Model Approximation for a Jncertain Nonlinear Systems, 5729		15:00	
incertain Nonlinear Systems, 5725 Coutinho, Daniel Ferreira	Pontificia Univ. Catolica do Rio	Weak Detectability and the LQ Probl	em of Discrete-Time Infinite
- Camino, Ballion Follona	Grande do Sui	Markov Jump Linear Systems, 5789	
Trofino, Alexandre	Federal Univ. of Santa Catarina	Costa, Eduardo F.	Unicam
15:40		Do Val, Joao B.R.	UNICAM
3.40 Necessary and Sufficient Condition	for H Infinity Estimation of	Fragoso, Marcelo	LNCC / CNQ
inear Time Delay Systems, 5735		15:20	
Zhang, Huanshui	Hong Kong Pol. Univ.	An Algebraic Characterization of Cov	variance Extension Problem
· ·	The Henry Kenry Del Links	and Its Applications, 5795	
Zhang, David Xie, Lihua	The Hong Kong Pol. Univ. Nanyang Tech. Univ.	Ohara, Atsumi	Osaka Univ

15:40		15:00	
Outsourcing and Price-QoS Equil. Internet Firms: IT On-Demand, 58		Approximate Jacobian Robot Cont Matrix, 5859	rol with Adaptive Jacobian
Dube, Parijat	IBM Watson Res. Center	Cheah, C.C.	Nanyang Tech. Univ.
Liu, Zhen	IBM Watson Res. Center	15:20	
Wynter, Laura	IBM Watson Res. Center	Transfer Matrices of Orthogonal G	ough-Stewart Platforms 5865
Xia, Cathy	IBM Watson Res. Center	Jafari, Farhad	Univ. of Wyoming
16:00		McInroy, John E.	Univ. of Wyoming
Optimal Linear Communication C	ompression in Multisensor	15:40	
Estimation Fusion, 5807	5,1, <b>,</b> 5, 5,5,5,1, 11, 11, 11, 11, 11, 11, 11,	An Hybrid Mapping Approach with	Place Forgetting 5871
Zhu, Yunmin	Sichuan Univ.	Abreu, Antonio	ESTS/IPS
Song, Enbin	Sichuan Univ.	Correia, Luis	Departamento Informática.
Zhou, Jie	Sichuan Univ.	0011010, 2010	Faculdade de Ciencias e
You, Zhisheng	Sichuan Univ.		Tecnologia. Un
16:20	•	16:00	
Limiting Model of ECN/RED unde		Modified Newton's Method Applied	to Potential Field Navigation,
Heterogeneous TCP Flows, 5813		5873	
Tinnakornsrisuphap,	Univ. of Maryland, Coll. Park	McIsaac, Kenneth Alexander	Univ. of Western Ontario
Peerapol	Link of Mandand Call Bark	Ren, Jing	The Univ. of Western Ontario
La, Richard J.	Univ. of Maryland, Coll. Park	Huang, Xishi	The Univ. of Western Ontario
16:40	35 Ot1 5040	16:20	
A Maximum Principle for Risk-Sei		A Biomimetic Apparatus for Sound	Source Localization, 5879
Zhou, Xun Yu	Chinese Univ. of Hong Kong Univ. of California	Handzel, Amir A.	Univ. of Maryland
Lim, Andrew	Olliv. of California	Andersson, Sean	Univ. of Maryland
FrP07	Regency Boardroom	Gebremichael, Martha	Univ. of Maryland Univ. of Maryland
Nonlinear Estimation	Regular Session	Krishnaprasad, P. S.	Citiv. Of Maryland
Chair: Camacho, Eduardo F.	Univ. of Sevilla	16:40	- to laint Valacities Including
Co-Chair: Zheng, Wei Xing	Univ. of Western Sydney	Optimal Filters from Task Velocitie Both Position and Velocity Limits,	
15:00		McInroy, John E.	Univ. of Wyoming
Receding-Horizon Estimation for	Noisy Nonlinear Discrete-Time	Aphale, Sumeet	Univ. of Wyoming
Systems, 5825	•	,	· · · · · · · · · · · · · · · · · · ·
Alessandri, Angelo	National Res. Council of Italy	FrP09	Maui Suite 4
Baglietto, Marco	Univ. of Genova		Regular Session
Battistelli, Giorgio	Univ. of Genova	Chair: Viassolo, Daniel	General Electric
Parisini, Thomas	Univ. of Trieste	Co-Chair: Mihalyov, Kenneth	Xerox Corp.
15:20		15:00	
Guaranteed State Estimation by 2		Current Waveform Optimization for	
Alamo, Teodoro Bravo, Jose Manuel	Univ. de Sevilla Huelva Univ. Spain	Linear Synchronous Motors, 5891	
Camacho, Eduardo F.	Univ. of Sevilla	Roehrig, Christof	Univ. of Hagen
15:40		15:20	
Remarks on Equivalence between	Eull Order and Reduced Order	Discrete-Time Nonlinear Control S Generator, 5897	scneme for Synchronous
Nonlinear Observers, 5837		De Leon-Morales, Jesus	FIME-UANL
Shim, Hyungbo	Seoul National Univ.	Huerta-guevara, Oscar	Univ. Autonoma De Nuevo Leon
Praly, Laurent	Ec. des Mines	Dugard, Luc	CNRS-INPG
16:00		Dion, Jean-Michel	URA CNRS
Observer Linearization of Nonline	ar Systems by Generalized	15:40	*
Transformations, 5841		Discrete-Time LPV Current Contro	ol of an Induction Motor, 5903
Guay, Martin	Queen's Univ.	Bendtsen, Jan Dimon	Aalborg Univ.
16:20		Trangbaek, Klaus	Inst. of Electronic Systems
Robust Output Feedback Stabiliz	ation and Nonlinear Observer		Aalborg Univ. Denmark
Design, 5847		16:00	
Karafyllis, Iasson	National Tech. Univ. of Athens	A COMBINED Hoo/QFT CONTRO	
Kravaris, Costas	Univ. of Patras	Castaño, Fernando	School of Engineering, Univ. of
16:40			Seville
Recent Results on Classification	of Low Dimensional Estimation	Jiménez, Daniel	School of Engineering, Univ. of
Algebras, 5853	F. Jan Hein	Pubio E P	Seville Univ. de Sevilla
Chico, Wen-Lin	Fu-Jen Univ. Fu-Jen Univ.	Rubio, F.R.	Oniv. de Sevilla
Chiueh, Woei-Ren Yau, Stephen ST.	Univ. of Illinois at Chicago	16:20	E Estimation of Speed and Poter
au, otephen o1.	Other of finitions at Officago	Sensorless IPMSM Drive with EK Position, 5915	г Езинацон от эреей али котог
FrP08	Maui Suite 3	Kosaka, Manabu	Kin-ki Univ.
Robotics	Regular Session	Uda, Hiroshi	Kin-ki Univ.
Chair: Cheah, C.C.	Nanyang Tech. Univ.	16:40	
Co-Chair: McIsaac, Kenneth	Univ. of Western Ontario	Field-Oriented Control of Induction	n Motors by Application of the
Alexander		Transverse Function Control Appl	
		Morin, Pascal	INRIA
		Samson, Claude	INRIA Sophia-Antipolis
		•	•

FrP10	Guest Room 350	16:20	W. C. W. C. L. C.
Manufacturing and Finance Chair: Maheswaran, Rajiv T.	Regular Session Univ. of Illinois at Urbana-	Stability and Performance Recovery	within Discretized Nonlinear
Chair. Maneswaran, Rajiv 1.	Champaign	Control Systems, 5985 Herrmann, Guido	Univ. of Leicester
Co-Chair: Ramírez-	Univ. of Cincinnati	Spurgeon, Sarah K.	Univ. of Leicester
Hernández, José A.		Edwards, Christopher	Univ. of Leicester
15:00		16:40	
An Algorithm to Convert Wafer to 0		A Multirate Approach to Input or Out	tput Augmentation for
Maintenance Schedules for Semice	onductor Manufacturing	Sampled-Data Static Output Feedba	
Systems, 5927	I I-iv. of Cincinnati	Galeani, Sergio	Univ. di Roma Tor Vergata
Ramírez-Hernández, José A.	Univ. of Cincinnati Univ. of Cincinnati	Menini, Laura	Univ. di Roma Tor Vergata
Fernandez, Emmanuel	Only. Of Calcumat	Tornambe, Antonio	Univ. di Roma Tor Vergata
15:20	ntral Sustama E022	FrP12	Maui Suite 5
UML Extensions for Real-Time Co. Gao, Qimin	The Univ. of Western Ontario	Uncertainty in System ID	Regular Session
Brown, Lyndon J.	Univ. of Western Ontario	Chair: Ninness, Brett	Univ. of Newcastle
Capretz, Luiz	Univ. of Western Ontario	Co-Chair: Campi, M. C.	Univ. di Brescia
15:40		15:00	
Equilibrium and Negotiation in Mul	tiple Resource Auctions, 5939	Accuracy of Closed Loop Estimates	Revisited, 5997 -
Maheswaran, Rajiv T.	Univ. of Illinois at Urbana-	Ninness, Brett	Univ. of Newcastle
	Champaign	Hjalmarsson, Hakan	Royal Inst. of Tech.
Basar, Tamer	Univ. of Illinois at Urbana-	15:20	
	Champaign	The Analysis of Variance Error: Qua	antifications Exact for Finite
16:00	Desire Obstaclastic At	Model Order, 6003	Univ. of Newcastle
Continuous-Time Mean-Variance I	Portfolio Choice with No-	Ninness, Brett	Only, of Newcastle
Bankruptcy Constraint, 5945 Jin, Hanging	Chinese Univ. of HongKong	15:40	
Bielecki, Tomasz R.	Northeastern Illinois Univ.	Estimation of Confidence Regions for Models - Guaranted Non-Asymptotic	
Pliska, Stanley R.	Univ. of a Illinois - Chicago	Campi, M. C.	Univ. di Brescia
Zhou, Xun Yu	Chinese Univ. of Hong Kong	Weyer, Erik	Univ. of Melbourne
16:20		16:00	
Research on Approach of Supply	Chain Planning with Quality	Model Quality Assessment for Instru	umental Variable Methods: Use
Control in an OKP Environment, 5		of the Asymptotic Theory in Practice	
Wang, Wei	Dalian Naval Acad.	Garatti, Simone	Pol. Di Milano
16:40		Campi, M.C.	Univ. di Brescia
Neural Network Based Uniformity		Bittanti, Sergio	Pol. Di Milano
Chemical-Mechanical Planarization		16:20	
Yi, Jingang	Lam Res. Corp.	Model Quality in Nonlinear SM Iden	tification 6021
Chang Va	· · · · · · · · · · · · · · · · · · ·		
Sheng, Ye Xu, C. Shan	Univ. of California at Berkeley	Milanese, Mario	Pol. di Torino
Sheng, Ye Xu, C. Shan	· · · · · · · · · · · · · · · · · · ·	Novara, Carlo	Pol. di Torino
Xu, C. Shan	Univ. of California at Berkeley	Novara, Ćarlo 16:40	Pol. di Torino Pol. di Torino
Xu, C. Shan  FrP11 Stability and Control of	Univ. of California at Berkeley Lam Res. Corp.	Novara, Carlo 16:40 The Variance of Non-Parametric Er	Pol. di Torino Pol. di Torino
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems	Univ. of California at Berkeley Lam Res. Corp. Guest Room 351 Regular Session	Novara, Carlo 16:40 The Variance of Non-Parametric Er 6027	Pol. di Torino Pol. di Torino
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata'	Novara, Carlo 16:40 The Variance of Non-Parametric Er	Pol. di Torino Pol. di Torino rors-In-Variables Estimates,
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond	Univ. of California at Berkeley Lam Res. Corp. Guest Room 351 Regular Session	Novara, Carlo 16:40 The Variance of Non-Parametric Er 6027	Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata'	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems	Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria	Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session Univ. Pol. delle Marche
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control-	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  -Lyapunov Functions, 5961	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier	Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session Univ. Pol. delle Marche
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control- Kellett, Christopher	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00	Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session Univ. Pol. delle Marche INPO
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control-	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session Univ. Pol. delle Marche INPG
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 600	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Session Univ. Pol. delle Marche INPG
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPG Per Robust Absolute Stability of 33 Zhejiang Univ. of Tech
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPO Per Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  -Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPO Per Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A.  15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited Chiba Univ.	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60:3 Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPO Per Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  -Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function Fujitsu Lab. Limited	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPO Per Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech
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Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keltaro Hirata, Mitsuo Horowitz, Roberto 15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  coliity of Time-Varying scades, 5973	Novara, Carlo 16:40 The Variance of Non-Parametric En 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fill Systems, 60:38	Pol. di Torino Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates,  Univ. of Newcastle  Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPG Per Robust Absolute Stability of 33  Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech tering for Linear Delay  School of Electrical and Computer Engineering Univ. o
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto  15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas Nesic, Dragan	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  coliity of Time-Varying scades, 5973 Univ. of Melbourne	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60:3 Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fil Systems, 60:38 de Oliveira, Mauricio C.	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates, Univ. of Newcastle Guest Room 450 Regular Sessior Univ. Pol. delle Marche INPO Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech Zhejiang Univ. of Tech Central Gueesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech Central Computer Engineering Univ. o Campinas
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Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto 15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas Nesic, Dragan Loria, Antonio 16:00	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  collity of Time-Varying scades, 5973 Univ. of Melbourne CNRS	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fill Systems, 60:8 de Oliveira, Mauricio C.  Geromel, Jose C. 15:40	Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates,  Univ. of Newcastle  Guest Room 450  Regular Sessior Univ. Pol. delle Marche INPO Pol. delle Marche INPO Robust Absolute Stability of 33  Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech tering for Linear Delay  School of Electrical and Computer Engineering Univ. o Campinat UNICAME
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Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto  15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas Nesic, Dragan Loria, Antonio  16:00 Ripple-Suppressed Multirate Conts System with an Ultra Sonic Senso	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  collity of Time-Varying scades, 5973 Univ. of Melbourne CNRS	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fill Systems, 60:38 de Oliveira, Mauricio C.  Geromel, Jose C. 15:40 A H Infinity Design Method of PID Of Processes with Integrator and Time	Pol. di Torino Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates,  Univ. of Newcastle  Guest Room 450 Regular Session Univ. Pol. delle Marche INPG Robust Absolute Stability of 33 Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech Zhejiang Univ. of Tech Computer Engineering Univ. o Campinas UNICAMF Controller for Second-Order Poles 2014
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto 15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas Nesic, Dragan Loria, Antonio 16:00 Ripple-Suppressed Multirate Cont System with an Ultra Sonic Senso Ishitobi, Mitsuaki	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  colity of Time-Varying scades, 5973 Univ. of Melbourne CNRS  trol and Its Application to a or, 5979  Kumamoto Univ.	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60:3 Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fill Systems, 60:38 de Oliveira, Mauricio C.  Geromel, Jose C. 15:40 A H Infinity Design Method of PID Of Processes with Integrator and Time-liu, tao	Pol. di Torino Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates,  Univ. of Newcastle  Guest Room 450 Regular Session Univ. Pol. delle Marche INPG Proposition Regular Session Univ. Pol. delle Marche INPG Proposition Regular Session Univ. of Tech Central Queesland Univ. of Tech Zhejiang Univ. of Tech Zhejiang Univ. of Tech Itering for Linear Delay School of Electrical and Computer Engineering Univ. o Campinas UNICAME Controller for Second-Order Proposition Regular Technology Shanghai Jiaotong Univ
Xu, C. Shan  FrP11 Stability and Control of Discrete-Time Systems Chair: Menini, Laura Co-Chair: DeCarlo, Raymond A. 15:00 Results on Discrete-Time Control- Kellett, Christopher Teel, Andrew R.  15:20 A Comparative Study of the Use of for HDDs, 5967 Ohno, Keitaro Hirata, Mitsuo Horowitz, Roberto 15:40 Uniform Practical Asymptotic Stab Parameterized Discrete-Time Cas Nesic, Dragan Loria, Antonio 16:00 Ripple-Suppressed Multirate Cont System with an Ultra Sonic Senso	Univ. of California at Berkeley Lam Res. Corp.  Guest Room 351 Regular Session  Univ. di Roma 'Tor Vergata' Purdue Univ.  Lyapunov Functions, 5961 Univ. of Melbourne Univ. of California at Santa Barbara  of the Generalized Hold Function  Fujitsu Lab. Limited Chiba Univ. Univ. of California at Berkeley  collity of Time-Varying scades, 5973 Univ. of Melbourne CNRS	Novara, Carlo 16:40 The Variance of Non-Parametric En. 6027 Heath, William P.  FrP13 Time-Delay Systems Chair: Perdon, Anna Maria Co-Chair: Sename, Olivier 15:00 Delay-Dependent Conditions for the Uncertain Time-Delay Systems, 60: Yu, Li Han, Qing-Long Yu, Shiming Gao, Jinfeng 15:20 H2 and Hoo Robust Nonrational Fill Systems, 60:38 de Oliveira, Mauricio C.  Geromel, Jose C. 15:40 A H Infinity Design Method of PID Of Processes with Integrator and Time	Pol. di Torino Pol. di Torino Pol. di Torino Pol. di Torino rors-In-Variables Estimates,  Univ. of Newcastle  Guest Room 450 Regular Session Univ. Pol. delle Marche INPG PROBUST Absolute Stability of 33  Zhejiang Univ. of Tech Central Queesland Univ Zhejiang Univ. of Tech Zhejiang Univ. of Tech Tering for Linear Delay  School of Electrical and Computer Engineering Univ. of Campinas UNICAMF

16:00		18:00	
On Stability for Neutral Differential Systems with Multiple Time-		Synthesis of Output Feedback Gain-Scheduling Controllers Based	
Varying Delay Arguments, 6050	,	on Descriptor LPV System Repres	
Yang, Bin	Dalian Univ. of Tech.	Masubuchi, Izumi	Hiroshima Univ.
Li, Tao	Dalian Univ. of Tech.	Akiyama, Tomoaki	Hiroshima Univ.
Jian, Yanhong	Dalian Univ. of Tech.	Saeki, Masami	Hiroshima Univ.
Wang, Jincheng	Dalian Univ. of Tech.	18:20	
16:20		Convex Necessary and Sufficient	Conditions for Model
Unknown Input Observers for Linear De	elav Systems: A Geometric	(In)Validation under SLTV Structured Uncertainty, 6121	
Approach, 6054	say systems. The second and	Mazzaro, Maria Cecilia	Pennsylvania State Univ.
Perdon, Anna Maria	Univ. Pol. delle Marche	Sznaier, Mario	Pennsylvania State Univ.
Conte, Giuseppe	Univ. Pol. delle Marche	18:40	
Guidone Peroli, Giovanna	Univ. Pol. delle Marche	Gain-Scheduling of Minimax Optim	nol State Foodbank Controllers
16:40		for Uncertain Linear Parameter-Va	uning Systems 6127
Finite Spectrum Assignment Controller	for Telegoperation Systems	Yoon, Myung-gon	The Univ. of New South Wales
with Time Delay, 6060	tor reicoperation cystems	Ugrinovskii, Valery	Australian Defence Force Acad.
Fattouh, Anas	URA CNRS	Pszczel, Marek	Defence Science and Tech.
Sename, Olivier	INPG		Organisation
		19:00	- · <b>3</b>
FrP14	Guest Room 451		st Stability of Linear Time-
Geometric Methods for	Regular Session	A New LMI Condition for the Robust Stability of Linear Time- Varying Systems, 6133	
Nonlinear Systems		Montagner, Vinicius F.	Univ. of Campinas
Chair: Fujimoto, Kenji	Kyoto Univ:	Peres, Pedro L. D.	Univ. of Campinas
Co-Chair: Tabuada, Paulo	Univ. of Notre Dame		o o. oupao
15:00		FrE02	Regency A
A Reachable Set Approach to Feedbac	k Stabilization of Nonlinear	Nonlinear Uncertain Systems	Regular Session
Systems with Drift, 6066		Chair: Khorrami, Farshad	Pol. Univ.
Michalska, Hannah H.	McGill Univ.	Co-Chair: Lin, Wei	Case Western Res. Univ.
Torres-Torriti, Miguel	McGill Univ.	17:40	
15:20			Monlinear Systems Via Dynamic
Nonlinear Balanced Realization Based	on Singular Value Analysis	Global Robust State-Feedback for Nonlinear Systems Via Dynamic High-Gain Scaling, 6139	
of Hankel Operators, 6072	on onigular value Analysis	Krishnamurthy, Prashanth	Pol. Univ.
Fujimoto, Kenji	Kyoto Univ.	Khorrami, Farshad	Pol. Univ.
Scherpen, Jacquelien M.A.	Delft Univ. of Tech.	18:00	
15:40			and Sustama: State Foodback
System Immersion into a Locally Obser	nyahla Bolynomial In The	Global Robust Control of Feedform and Output-Feedback, 6145	ard Systems. State-reedback
State Representation, 6078	vable Folynomial-III-The-	Krishnamurthy, Prashanth	Pol. Univ.
Ohtsuka, Toshiyuki	Osaka Univ.	Khorrami, Farshad	Pol. Univ.
•	Osaka Omv.		i di dine.
16:00	Cotting 6094	18:20	Non Minimum Dhace Mentineer
Jacobian Linearisation in a Geometric S Lewis, Andrew D.	Queen's Univ.	Model-Based Control of Unstable, Processes, 6151	Non-winimum-Phase, Nonlinear
Tyner, David	Queen's Univ.	Panjapornpon, Chanin	Drexel Univ.
_	. Queen's Oniv.	Soroush, Masoud	Drexel Univ.
16:20	Class of Naminasa	Seider, Warren D.	Univ. of Pennsylvania
Hierarchical Trajectory Generation for a Systems, 6090	i Class of Norllinear	18:40	• · · · · · · · · · · · · · · · · · · ·
Tabuada, Paulo	Univ. of Notre Dame		ly Deremotorized Cyptomoby
Pappas, George J.	Univ. of Pennsylvania	Adaptive Stabilization of Nonlinear C^0 Partial-State Feedback, 6157	ly Parameterized Systemsby
- · · · ·	Oniv. of Fellisylvania	Lin, Wei	Case Western Res. Univ.
16:40		Pongvuthithum, Radom	Case Western Res. Univ.
Geometric Homogeneity and Controllat	υπιτη οτ Nonlinear Systems,	-	Cuso Trostelli INGS. Offiv.
6096	California lant of Took	19:00	
Vela, Patricio A.	California Inst. of Tech.	On Measuring Closed-Loop Nonlin	learity - a Vinnicombe ivietric
Burdick, Joel W.	California Inst. of Tech.	Approach, 6163	Univ. of British Columbia
FrE01	Monarchy Ballroom	Tan, Guan Tien Huzmezan, Mihai	Univ. of British Columbia
Linear Parameter Varying	Regular Session	Kwok, K. Ezra	Univ. of British Columbia
Methods	Regulai Session	NWOK, N. EZIA	Only. Of British Columbia
Chair: Sznaier, Mario	Penn State Univ.	FrE03	Regency B
Co-Chair: Allgower, Frank	Univ. of Stuttgart	Neural Networks Optimization	Regular Session
•	Only. or Stategart	Chair: Wang, I-Jeng	Johns Hopkins Univ.
17:20		Co-Chair: Alessandri, Angelo	National Res. Council of Italy
Stabilization of LPV Systems, 6103		· •	National Res. Council of Italy
Bliman, Pierre-Alexandre J	INRIA-Rocquencourt	17:20	د مد سوسی مرازی می
17:40		A General Recurrent Neural Netwo	ork iviodel for Time-Varying
An Approach to Gain-Scheduled L_1-0	ptimal Control of Linear	Matrix Inversion, 6169	Notional Units of Classes
Parameter-Varying Systems, 6109		Zhang, Yunong	National Univ. of Singapore
Rieber, Jochen M.	Univ. of Stuttgart	Ge, Shuzhi Sam	National Univ. of Singapore
Allgower, Frank	Univ. of Stuttgart		

17:40		FrE05	Maui Suite 1
An Adaptive RBFN-Based Filter for	Adaptive Noise Cancellation,	Switched Systems III	Regular Session
6175		Chair: Peres, Pedro L. D.	Univ. of Campinas
LI, Zhengrong	Nanyang Tech. Univ.	Co-Chair: higuchi, kohji	The Univ. of Electro- Communications
Er, Meng Joo Gao, Yang	NTU Nanyang Tech. Univ.	47:20	Communications
	Nanyang Tech. Only.	17:20	Bala I coation and Structural
18:00 On the Convergence EKF-Based F	Parameters Ontimization for	Discrete-Time Switched Systems: Pole Location and Structural Constrained Control, 6242	
Neural Networks, 6181	arameters Optimization for	Montagner, Vinícius F.	Univ. of Campinas
Alessandri, Angelo	ISSIA-CNR, Genova, Italy	Leite, Valter J. S.	CEFET/MG - UnED Div.
Cuneo, Marta	ISSIA-CNR, Genova, Italy	Peres, Pedro L. D.	Univ. of Campinas
Pagnan, Sergio	ISSIA-CNR, Genova, Italy	17:40	
Sanguineti, Marcello	Univ. of Genova	Robust Digital Control of PWM Pov	ver Amplifier by Approximate 2-
18:20		Degree-Of-Freedom System with B	
Shortest Path Problems on Stocha	stic Graphs: A Neuro Dynamic	Higuchi, Kohji	The Univ. of Electro-
Programming Approach, 6187			Communications
Baglietto, Marco	Univ. of Genova	Nakano, Kazushi	The Univ. of Electro-
Battistelli, Giorgio	Univ. of Genova	Kajikawa Tatauwashi	Communications
Vitali, Federico	Univ. of Genova	Kajikawa, Tatsuyoshi	The Univ. of Electro- Communications
Zoppoli, Riccardo	Univ. of Genova	Araki, Kuniya	NF Corp.
18:40		Chino, Fumiho	NF Corp.
Robust Neural Network Tracking C		18:00	т. Со.р.
Perturbation Stochastic Approxima Song, Qing	Nanyang Tech. Univ.	Suboptimal Switched Control in Co.	ntext of Singular Arcs 6254
Spall, James C.	Johns Hopkins Univ.	Riedinger, Pierre	CRAN
Soh, Yeng Chai	Nanyang Tech. Univ.	Daafouz, Jamal	CRAN -INPL
19:00	ranjung ruma dini.	lung, Claude	CRAN
Inverse Optimal Design for Trajecto	ory Tracking with Input	18:20	
Saturations Via Adaptive Recurrent	t Neural Control. 6200	Adaptive Control of Switched Syste	ms, 6260
Ricalde, Luis J.	CINVESTAV	Cheng, Daizhan	Chinese Acad. of Sciences
Sanchez, Edgar N.	CINVESTAV	zhang, Lijun	Chinese Acedamy of Science
		18:40	
FrE04	Regency C	New Results on Stabilizability of Sv	vitched Linear Systems, 6265
Modeling	Regular Session	Xie, Guangming	Peking Univ.
Chair: Chiasson, John	Univ. of Tennessee	Wang, Long	Peking Univ.
Co-Chair: Guinee, Richard A.	Cork Inst. of Tech.	19:00	
17:20		Reachability of Switched Linear Imp	
Modeling, Simulation and Optimiza	tion of Commercial Naphtha	Xie, Guangming	Peking Univ.
Catalytic Reforming Process, 6206 Hu, Yongyou		Wang, Long	Peking Univ.
Su, Hongye	Zhejiang Univ. Zhejiang Univ.	E-E08	
Chu, Jian	Zhejiang Univ. Zhejiang Univ.	FrE06 Stochastic Discrete-Event	Maui Suite 2
17:40	Englang Onv.	Systems and Markov	Regular Session
Modeling and Simulation of the Ind	uction Motor with Position	Processes	
Dependent Load Torque, 6212	action with Fosition	Chair: Cassandras, Christos	Boston Univ.
Delaleau, Emmanuel	Univ. Paris-sud	G.	2333
Stankovic, Aleksandar M.	Northeastern Univ.	Co-Chair: Krishnamurthy,	Univ. of British Columbia
18:00		Vikram	
A Model for Impact Dynamics and I	Its Application to Frequency	17:20	
Analysis of Tapping-Mode Atomic I		Perturbation Analysis of Feedback-	Controlled Stochastic Flow
Materassi, Donatello	Univ. di Firenze	Systems, 6277	
Basso, Michele	Univ. di Firenze	Yu, Haining	Boston Univ.
Genesio, Roberto	Univ. di Firenze	Cassandras, Christos G.	Boston Univ.
18:20		17:40	
Piecewise Linear Systems in Econo	omic Models, 6224"	State-Feedback Control of Markov	Chains with Safety Bounds,
- Martinez, Alfredo	California Inst. of Tech.	6283	
18:40		Arapostathis, Ari	Univ. of Texas at Austin
A Novel Modulated Single Fourier S		Kumar, Ratnesh Hsu, Shun-Pin	lowa State Univ. Univ. of Texas at Austin
Mathematical Modelling and Simula	ation of Natural Sampled Pulse	,	Only. Of Texas at Austin
Width Modulation in High Performa	nce Brushless Motor Drives,	18:00	-4- 6000
6230 Guinee, Richard A.	Code land of Tool	Diagnosability of Stochastic Automa Thorsley, David	ata, 6289 Univ. of Michigan
Lyden, Colin	Cork Inst. of Tech. c/o National Microelectronics	Teneketzis, Demosthenis	Univ. of Michigan Univ. of Michigan
Lyden, Com	Res. Centre, Univ. Coll.	Tonocalo, Domostionio	Cinv. or whichigan
19:00	. too. Contro, Oliv. Con.		
Analysis of the Semilinear Duhem I	Model for Rate-Independent		
Hysteresis, 6236			
Oh, JinHyoung	Univ. of Michigan		
Bernstein, Dennis S.	Univ. of Michigan		

	Modelling: A Stochastic Discrete	17:20 Regulation of 1DOF Linear Med	
Event System Approach, 629	5	Configuration for Smooth or Non-Smooth Impacts, 6345	
Visnevski, Nikita	McMaster Univ.	Galeani, Sergio	Univ. Di Roma Tor Vergata
Krishnamurthy, Vikram	Univ. of British Columbia	Menini, Laura	Univ. di Roma Tor Vergata
Haykin, Simon	McMaster Univ.	Tornambe, Antonio	Univ. Di Roma Tor Vergata
Currie, Brian	McMaster Univ.	•	
Dilkes, Fred	Defence R&D Canada	17:40	Had Cingularities, Dhysiaelly, Based
Lavoie, Pierre	Defence R&D Canada		olled Singularities: Physically-Based
	Delence Nab Canada	Representation and Control-Ori	
18:40		Bentsman, Joseph	Univ. of Illinois at Urbana-
Strategic Reconfigurability in .	Air Operations, 6301		Champaign
Wu, Neng Eva	Binghamton Univ.	Miller, Boris	Russian Acad. of Science, Inst.
Busch, Timothy	AFRL		of Information Transmissio
19:00		18:00	
	ana Manaura Daramatara far Disarata		on Conditions of Ontimolity for
Online Identification of Language Measure Parameters for Discrete		First and Second Order Necessary Conditions of Optimality for	
Event Supervisory Control, 63		Impulsive Control Problems, 63	
Wang, Xi	Penn State Univ.	Arutyunov, Aram V.	Russian Peoples Friendship
Ray, Asok	Pennsylvania State Univ.		Univ
khatkhate, Amol	The Pennsylvania State Univ.	Dykhta, Vladimir	Irkutsk State Ec. Acad
		Pereira, Fernando Lobo	Porto Univ. Inst. For Systems 8
FrE07	Regency Boardroom		Robotics
Applications of Estimation	Regular Session	18:20	,
Chair: Stankovic, Alex M.	Northeastern Univ.		aking Adoptive Control Books
Co-Chair: Ghosh, Bijoy	Professor		cking Adaptive Control Based on
	Fiolessor	the Internal Inverse Models, 63	
17:20		Ushida, Shun	Univ. of Tokyo
Stochastic Approximation for	Optimal Observer Trajectory	Kimura, Hidenori	Univ. of Tokyo
Planning, 6313		18:40	
Singh, Sumeetpal	Univ. of Melbourne		ct Contact Detection for a Fluidic
Vo, Ba-Ngu	Univ. of Melbourne	Actuated Robotic Hand, 6369	or contact betechon for a rituale
Doucet, Arnaud	Cambridge Univ.	Beck, Sebastian	Earnahungarantrum Karlasuh
Evans, Robin J.	Univ. of Melbourne		Forschungszentrum Karlsruhe
	Offiv. of Meibourne	Mikut, Ralf	Forschungszentrum Karlsruhe
17:40	•	Lehmann, Arne	Forschungszentrum Karlsruhe
Nonlinear Observers for Pers	pective Time-Invariant Linear	Bretthauer, Georg	Forschungszentrum Karlsruhe
Systems, 6319		19:00	
Abdursul, Rixat	Tokyo Denki Univ.		dination for Mobile Robots, 6375
Inaba, Hiroshi	Tokyo Denki Univ.		
Ghosh, Bijoy	Washington Univ.	Hu, Xiaoming	Royal Inst. of Tech
* =	wasnington only.	Fuentes, David	
18:00		Gustavi, Tove	Royal Inst. of Tech
A Low-Power Filtering Schem	e for Distributed Sensor Networks,		
6325		FrE09	Maui Suite 4
Wolfe, Jonathan D.	Univ. of California at Los Angeles	Noise and Vibration Control	Regular Session
Speyer, Jason L.	Univ. of California at Los Angeles	Chair: Pao, Lucy Y.	Univ. of Colorado
18:20		Co-Chair: Laila, Dina Shona	
	and the state of t	•	perial con. London
	on of Short-Time Fourier Coefficients	17:20	الماسين والماسور
n Energy Applications, 6327			al Energy in Active Noise Control,
Stankovic, Alex M.	Northeastern Univ.	6381	
Lev-Ari, Hanoch	Northeastern Univ.	Pota, Hemanshu R.	Univ. Coll. Univ. of New Soutl
Perisic, Milun	Northeastern Univ.		Wales
8:40		He, Bingrong	Kansas State Univ
	ion Uning Improved Minters Value -		
ngriway rrailic State Estimat	ion Using Improved Mixture Kalman	17:40	orderes a Ofess today
Filters for Effective Ramp Met	ering Control, 6333	Robust Vibration Control of Stru	ictures. Simulations and
Sun, Xiaotian	Univ. of California at Berkeley	Experiments, 6386	
Munoz, Laura	Univ. of California at Berkeley	Ma, Kougen	Univ. of Hawaii at Manor
Horowitz, Roberto	Univ. of California at Berkeley	Melcher, Joerg	German Aerospace Cente
9:00		. •	· · · · · · · · · · · · · · · · · · ·
	Observat Fatimation to	18:00	a to an Atostock Had a control
Multiuser Detection with Joint			n in an Airduct Using Generalized
	yleigh Fading Channels, 6339	FIR Filter Estimation, 6392	
Pham, David	Univ. of Connecticut	de Callafon, Raymond A.	Univ. of California, San Diego
Pattipati, Krishna R.	Qualtech Systems, Inc.	Zeng, Jie	Univ. of California, San Diego
Willett, Peter K.	Univ. of Connecticut	18:20	
• • • •			and Control of Northwest 14/at
rE08	Maui Suite 3	Robust Lyapunov-Based Feedb	ack Control of Nonlinear Web-
Mechanical Systems and	Regular Session	Winding Systems, 6398	11-5
	ivedrial pession	Baumgart, Matthew	Univ. of Colorado
Robotics	11.115	Pao, Lucy Y.	Univ. of Colorado
Chair: Menini, Laura	Univ. di Roma 'Tor Vergata'	18:40	
Co-Chair: Tornambe, Anto	nio Univ. Di Roma Tor Vergata	Integrated Design of Discrete-T	ime Controller for an Active
		Suspension System, 6406	and Controller for all Active
			The Univ. of Melbourne
		Laila, Dina Shona	The Only, of Melbourne

Location and Coverage of Enhanced Self-Sensing Piezoelectric Preservation of Fundamental Properties in N-D Systems Using Actuators for Active-Passive Hybrid Vibration Control of Beam S\_{n} Functions, 6462 Fernandez-Anaya, Guillermo Univ. Iberoamericana Structures, 6412 CINVESTAV-IPN Torres-Munoz, Jorge A. Liao, Wei-Hsin The Chinese Univ. of Hong Kong CINVESTAV-IPN Gao, Jianxin The Chinese Univ. of Hong Kong Kharitonov, V.L. Guest Room 350 FrE10 Stabilization Via Output Static Feedback in Discrete-Time Linear **Biological and Biomedical** Regular Session Systems, 6466 **Systems** Univ. of California at Los Angeles Najson, Federico Professor Chair: Ghosh, Bijoy Univ. of California at Los Angeles Speyer, Jason L. Purdue Univ. at Indianapolis Co-Chair: Ramos, Jose A. 19:00 17:20 Characterization of Standrad Controllers Satisfying Given Modeling the Dynamics of Oculomotor System in Three H infinity Specifications, 6474 Univ. degli Studi di Udine Dimensions, 6418 Blanchini, Franco Univ. degli Studi di Udine Washington Univ. Polpitiya, Ashoka Miani, Stefano Washington Univ. Ghosh, Bijoy Viaro, Umberto Univ. of Udine Lepshcy, Antonio Univ. of Padova 17:40 Information-Theoretic Analysis of Turtle Cortical Waves, 6423 Maui Suite 5 FrE12 Du, Xiuxia Washington Univ. in St. Louis Practical System Identification Regular Session Ghosh, Bijov United Arab Emirates Univ. Chair: Nounou, Mohamed 18:00 Air Force Res. Lab. Co-Chair: Lacy, Seth L. Generation and Control of Propagating Waves in the Visual 17:20 Cortex, 6429 Empirical Bayesian Finite Impulse Response Modeling, 6480 Ulinski, Philip Univ. of Chicago Washington Univ. Nounou, Mohamed United Arab Emirates Univ. wang, wenxue Professor Ghosh, Bijoy Finite-Horizon Input Selection for System Identification, 6485 Lacy, Seth L. A Total Least Squares Approach for Data Reduction of Longterm Air Force Res. Lab. Univ. of Michigan ECG Recordings, 6435 Bernstein, Dennis S. Space Vehicles Directorate Ramos, Jose A. Purdue Univ. at Indianapolis Erwin, Richard Scott Paul, Joseph Suresh National Univ. of Singapore 18:00 LTI Systems, Additive Noise, and Order Estimation, 6491 Massachusetts Inst. of Tech. Beheshti, Soosan Controllability Issues in Flapping Flight for Biomimetic Micro Aerial Dahleh, Munther A. Massachusetts Inst. of Tech. Vehicles (MAVs), 6441 Univ. of California at Berkeley Schenato, Luca Campolo, Domenico Univ. of California, Berkeley On Optimal Input Design in Conditional Set Membership Sastry, Shankar Univ. of California at Berkeley Identification, 6497 Casini, Marco Univ. of Siena 19:00 Separation of Bioparticles Using the Travelling Wave Garulli, Andrea Univ. di Siena Vicino, Antonio Univ. di Siena Dielectrophoresis with Multiple Frequencies, 6448 Univ. of California, Santa Barbara Chang, Dong Eui 18:40 Loire, Sophie Univ. Bordeaux I Robust Estimation of Parallel Robot Dynamic Parameters with Mezic, Igor Univ. of California, Santa Barbara Interval Analysis, 6503 Poignet, Philippe Univ. Montpellier 2 FrE11 **Guest Room 351** Ramdani, Nacim Univ. Paris XII Stability of Linear Systems Regular Session Univ. Montpellier 2 Vivas, A. Univ. of California at Los Angeles Chair: Najson, Federico Co-Chair: Chadli, Mohammed CRAN-INPL-CNRS, UMR 7039 Model Validation in L-1 Using Frequency-Domain Data, 6509 Univ. of California at Riverside Chen, Jie Stability Analysis of a Class of Multidimensional Systems, 6454 Univ. of California Liu, Wenguo Peking Univ. Chu, Tianguang Nanyang Tech. Univ. Zhang, Cishen Guest Room 450 FrE13 Xie, Lihua Nanyang Tech. Univ. Preview and Filtering in Time-Regular Session Nanyang Tech. Univ. Soh, Yeng Chai **Delay Systems** Chair: Tadmor, Gilead Northeastern Univ. On the Stability Analysis of a Class of Multiple Models, 6458 Co-Chair: Kojima, Akira Tokyo Metro. Inst. of Tech. CRAN-INPL-CNRS, UMR 7039 Chadli, Mohammed 17:20 CRAN-INPL Maquin, Didier H-Inf Preview Control and Fixed-Lag Smoothing I: Matrix ARE Ragot, Jose CRAN-INPL Solutions in Continuous-Time Systems, 6515 18:00 Tadmor, Gilead Northeastern Univ. Convex Directions for Nested Hurwitz Polynomials, 6460 Mirkin, Leonid Tech. The Univ. of Melbourne An. Seniian Liu Wan Quan Curtin Univ. of Tech. H-Inf Preview Control and Fixed-Lag Smoothing II: Fixed Sized Univ. of Melbourne Manton, Jonathan H. ARE Solutions in Discrete-Time Systems, 6521 Northeastern Univ. Tadmor, Gilead Mirkin, Leonid Tech.

18:20

19:00

18:00 H-Inf Preview Control and Fixed-Lag Smoothing III: H-Inf Discretization, 6527 Mirkin, Leonid Tadmor, Gilead Northeastern Univ. 18:20 Formulas on Preview and Delayed H-Infinity Control, 6532 Tokyo Metro. Inst. of Tech. Ishijima, Shintaro Tokyo Metro. Inst. of Tech. 18:40 Optimal Design of Fractional Delay Filters, 6539 Nagahara, Masaaki Kyoto Univ. Yamamoto, Yutaka Kyoto Univ. 19:00 Delay-Dependent Robust Kalman Filtering for Interval Systems with Time Delay, 6545 Su, Te-Jen National Kaohsiung Univ. of Applied Sciences FrE14 Guest Room 451 Control of Large-Scale Regular Session Systems Xerox Corp. Chair: Mestha, Lalit K. Univ. of North Carolina at Co-Chair: Wang, Sheng-Guo Charlotte Using Dynamic Optimization for Control of Real Rate CPU Resource Management Applications, 6547 Oregon State Univ. Vahia, Varin Univ. of Toronto Goel, Ashvin Walpole, Jonathan Oregon Health & Sciences Univ. Shor, Molly H. Oregon State Univ. Multi-Dimensional Gain Scheduling with Application to Power Plant Control, 6553 Bendtsen, Jan Dimon Aalborg Univ. Stoustrup, Jakob Aalborg Univ. Trangbaek, Klaus Aalborg Univ. On the Application of Predictive Functional Control in Steam Temperature Systems of Thermal Power Plant, 6559 North China Electric Power Univ. Han, Pu Wang, Guoyu North China Electric Power Univ. Wang, Dongfeng North China Electric Power Univ. 18:20 Some Nonlinear Controls for Nonlinear Processes in the DIII-D Tokamak, 6565 Walker, M.L. General Atomics Humphreys, D.A. General Atomics Univ. of California, San Diego Schuster, E. LQG-Alpha Control and Its Simulations for Structural Benchmark Problems against Winds and Earthquakes, 6572 Univ. of North Carolina at Wang, Sheng-Guo Charlotte Nonlinear Control of a Planar Mangetic Levitation System, 6578 Levis, Michel Univ. of Toronto

Maggiore, Manfredi

Univ. of Toronto