
Contents

1	Introduction	1
1.1	What is Iterative Learning Control	1
1.1.1	The Simplest ILC: An Example	4
1.1.2	ILC for Non-affine Process	6
1.1.3	ILC for Dynamic Process	7
1.1.4	D-Type ILC for Dynamic Process	11
1.1.5	Can We Relax the Identical Initialization Condition? ..	13
1.1.6	Why ILC	14
1.2	History of ILC	16
1.3	Book Overview	17
2	Robust Optimal Design for the First Order Linear-Type ILC Scheme	21
2.1	Introduction	21
2.2	Problem Formulation	22
2.3	Convergence Properties in Iteration Domain	24
2.4	Robust Optimal Design for Convergence Speed	27
2.5	Robust Optimal Design for Global Uniform Bound	30
2.6	Monotonic Convergence Interval	33
2.7	Illustrative Examples	34
2.8	Conclusions	37
3	Analysis of Higher Order Linear-Type ILC Schemes	39
3.1	Introduction	39
3.2	Preliminary	40
3.3	Convergence Speed Analysis of the Second Order ILC	42
3.4	m -th Order ILC	45
3.5	Illustrative Example	51
3.6	Conclusions	51

4	Linear ILC Design for MIMO Dynamic Systems	53
4.1	Introduction	53
4.2	Preliminary	53
4.3	Problem Formulation	54
4.4	The Linear-Type ILC Approach	56
4.5	Robust Optimal Design for MIMO Dynamic Systems	58
4.6	Illustrative Example	64
4.7	Conclusions	66
5	Nonlinear-Type ILC Schemes	69
5.1	Introduction	69
5.2	Problem Statement	70
5.3	Convergence Analysis for Linear-Type ILC Scheme	71
5.4	The Newton-Type ILC Scheme	73
5.5	The Secant-Type ILC Scheme	77
5.6	Illustrative Example	80
5.7	Conclusions	80
6	Nonlinear ILC Design for MIMO Dynamic Systems	83
6.1	Introduction	83
6.2	Preliminary	83
6.3	The Newton-Type ILC Approach	86
6.4	The Secant-Type ILC Approach	88
6.5	Illustrative Example	93
6.6	Conclusions	94
7	Composite Energy Function Based Learning Control	95
7.1	Introduction	95
7.2	From Contraction Map to Energy Function Approach	96
7.2.1	ILC Bottleneck – GLC	97
7.2.2	What Can We Learn From Adaptive Control	99
7.2.3	ILC with Composite Energy Function	101
7.3	General Problem Formulation	105
7.4	Learning Control Configuration and Convergence Analysis	107
7.5	Illustrative Example	112
7.6	Conclusions	113
8	Quasi-Optimal Iterative Learning Control	115
8.1	Introduction	115
8.2	Problem Formulation	116
8.3	Nonlinear Optimal Control	117
8.4	Synthesized Quasi-Optimal Learning Control Scheme	118
8.5	Illustrative Example	123
8.6	Conclusions	125

9	Learning Wavelet Control Using Constructive Wavelet Networks	129
9.1	Introduction	129
9.2	Fundamentals of Wavelet Networks	130
9.3	LWC Design for Affine Nonlinear Uncertain Systems	132
9.3.1	Problem Formulation	132
9.3.2	Design and Analysis of LWC	135
9.4	LWC for Non-affine Dynamic Systems	142
9.4.1	Problem Formulation	142
9.4.2	LWC Design and Analysis	144
9.5	Illustrative Examples	147
9.6	Conclusions	153
10	Conclusions and Recommendation	155
10.1	Conclusions	155
10.2	Recommendation for Future Research	156
A	Appendix	159
	References	163
	Index	173