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## Experimental results: Suboptimal robust linear visual servoing with delay for an underactuated system

Benitez-Morales, A.; Santos, O.; Ramos-Velasco, L.E.;

Centro de Investig. en Tecnol. de Informacion y Sist., Univ. Autonoma del Estado de Hidalgo, Pachuca de Soto, Mexico

**This paper appears in:** Methods and Models in Automation and Robotics (MMAR), 2010 15th International Conference on

**Issue Date:** 23-26 Aug. 2010

**On page(s):** 120 - 125

**Location:** Miedzyzdroje

**Print ISBN:** 978-1-4244-7828-6

**References Cited:** 17

**INSPEC Accession Number:** 11558721

**Digital Object Identifier:** 10.1109/MMAR.2010.5587251

**Date of Current Version:** 27 septiembre 2010

### ABSTRACT

This article synthesized suboptimal control for an underactuated system with delays; it also presents delay-dependent robust stability. A linear quadratic regulator (LQR) controller is synthesized using dynamic programming, which is applied to a linear matrix inequality, giving delay-dependent sufficient conditions. This delay is analyzed for time-invariant and time-variant case. We presented experimental results of the Visual Servoing for the inverted pendulum.

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