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electrical power systems using
two nonlinear control synthesis
techniques. For this transient
stabilization problem the actuator
considered is a power electronic

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device, a controllable series capacitor (CSC). The power system is described using two different nonlinear models - the second order swing equation and the third order flux-decay model.

Nonlinear Control Synthesis for

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Nonlinear systems are defined by those, which do not follow the principle of superposition.

Nonlinearities in process variables can be caused by stiction in control valves, which, in turn, sets up oscillations that propagate

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throughout the whole plant.

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An adaptive system for linear
systems with unknown parameters
is a nonlinear system. The
analysis of such adaptive systems

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requires similar techniques to
analyse nonlinear systems.

Therefore it is natural to treat
adaptive control as a part of
nonlinear control systems.

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and adaptive control in a unified

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framework, presenting the ...

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Nonlinear control theory is the

area of control theory which deals
with systems that are nonlinear,
time-variant, or both. Control

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theory is an interdisciplinary

branch of engineering and

mathematics that is concerned

with the behavior of dynamical

systems with inputs, and how to

modify the output by changes in

the input using feedback,

feedforward, or signal filtering.

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The system to be controlled is called the "plant". One way to make the output of a system follow a desired reference signal is

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Abstract. In the previous chapter,
the control design principle and
algorithm for SISO affine nonlinear

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systems are elaborated. This type of systems has only one input, i.e. control variable u and one output $y(t)$. As we know, however, multi-machine power systems are large nonlinear ones with multiple inputs and multiple outputs (MIMO).

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Design Principles of Multi-Input
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Optimal approaches are discussed
in Chapter 8 with retarded control
of nonlinear system in singular
situation, and Chapter 9 extends
optimal theory to H-infinity control
for a nonlinear control

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system. Chapters 10 and 11 present the control of nonlinear dynamic systems, twin-rotor helicopter and 3D crane system, which are both underactuated, cascaded dynamic systems.

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The presented control strategy results in a multi-loop, nonlinear controller which is conceived to meet two control objectives: (i) speed reference optimization, in order to extract maximum wind energy despite the uncertainty and

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variations wind speed, and
mechanical parameters; (ii) Power
Factor Correction (PFC) to avoid
net harmonic pollution.

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Thus, nonlinear PID control

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applied to wind turbines can be
find in [7], [8] and [9] as well as
fractional-order PID (FOPID)
applied to the control of a
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