Some Specific Design Information

$$\dot{x} = \sum_{i=1}^{2} u_i \overline{B}_i x$$

$$y = Cx$$

with inputs L, V_s and outputs x_1, x_{N_T}.
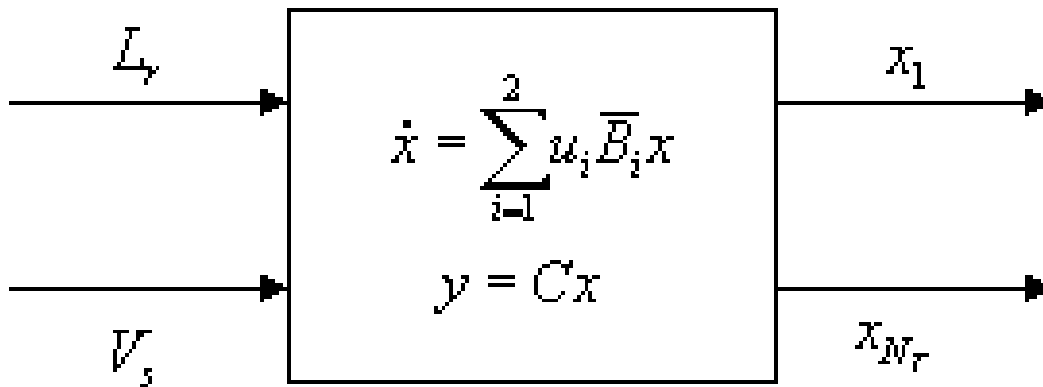
- ODE model for the above process is bilinear (see Yoon et al. for model equations).

- Recursive least-square estimation technique is employed for parameter adpatation

- No input and state constraints are imposed.

- The following horizons for objective and control are used:
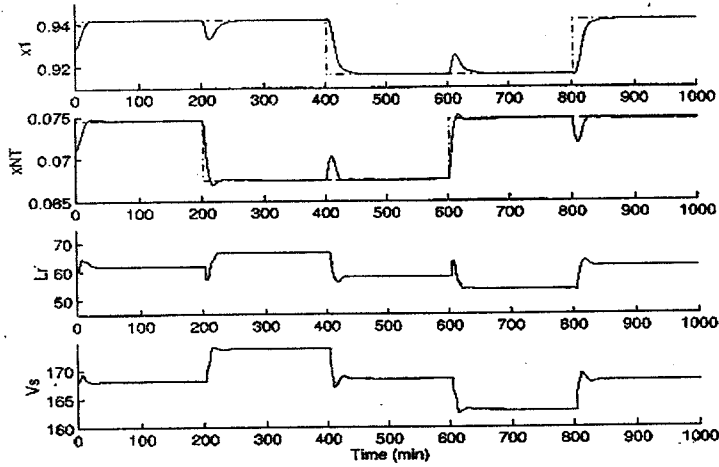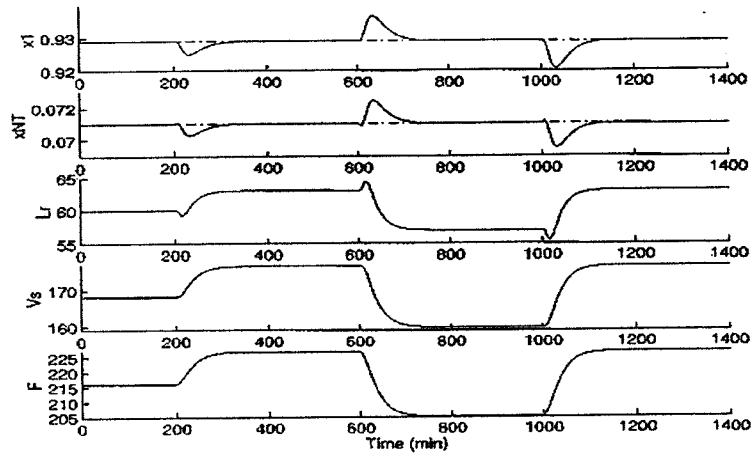
$$p = 22, \quad m = 20$$

Simulations

Figure 2.1: Responses to varying set-points

Figure 2.2: Responses to feed change