

$$\dot{x} = f(x, u), \quad x(0) = x_0$$

$$y = g(x, u)$$

$$s\mathcal{X}(s) = (\mathcal{A} - \mathcal{N})\mathcal{X}(s) + \mathcal{L}u(s)$$

$$\mathcal{Y}(s) = \mathcal{C}\mathcal{X}(s) + \mathcal{D}u(s)$$

$$\dot{\Phi}(t, t_0) = A(t)\Phi(t, t_0)$$

Incremental Control and Allocation for Power-Optimal Flight of Transition Aircraft

Ole Pfeifle, M.Sc.



$$\|y\|_{rms}^2 \leq \sup_{\omega \in \mathbb{R}} |G(j\omega)|^2 \frac{1}{2\pi} \int_{-\infty}^{\infty} S_{uu}(\omega) d\omega$$

Incremental Control and Allocation for Power-Optimal Flight of Transition Aircraft

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by

Ole Frieder Pfeifle

born in Ludwigsburg, Germany

Main referee:	Prof. Dr.-Ing. Walter Fichter
Co-referee:	Prof. Dr. Erik-Jan van Kampen
Co-referee:	Prof. Dr.-Ing. Flavio Silvestre
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