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ADRC, una estrategia de control robusto [

2018

text (article)

Analítica

This paper tries to illustrate the strategy known as Active Disturbance Rejection Control, ADRC, by means of a tracking position of a metallic sphere in a magnetic levitator. This control approach allows to make some estima- tions by means of linear observers of non-modified dynamics reducing in that way the complexity of the control law and providing a considerable robustness to the system. A validation of the control law was performed by simulation obtaining excellent results in the tracking of smooth trajectories even in the presence of parametric model uncertainties and external perturbations
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