

# GRADUATE STUDENTS

## Doctoral Theses

- **PhD11** Farkhatdinov, Ildar, 2013; Head stabilization during locomotion of humans.
- **PhD10** Hadzagic, Melita, 2010; Trajectory estimation using Bayesian approaches.
- **PhD09** Ganine, Vladislav, 2010; Model order reduction for prediction of turbine engine rotor vibration response in Presence of Parametric Uncertainties.
- **PhD08** Lu, Mu-Chiao, 2008; Robust and model-predictive control of systems with time delays.
- **PhD07** Nasrallah, Danielle S., 2007; Control of a wheeled robot moving on an inclined plane.
- **PhD06** Cadotte, Patrick, 2006; Robust control design using non-smooth optimization.
- **PhD05** Dionne, Dany, 2005; Methods for state estimation and guidance.
- **PhD04** Haurani, Ammar, 2004; Robust control of retarded systems.
- **PhD03** Torres-Torriti, Miguel, 2003; Stabilizing feedback control for nonlinear systems with drift.
- **PhD02** Ahmadi, Mojtaba, 1998; Stable control of a one-legged robot exploiting passive dynamics.

- **PhD01** Rehman, Fazal-Ur, 1997; Set point feedback stabilization of drift free systems.

## **Postdoctoral Fellows**

- **PDF5** Platkiewicz, Jonathan, 2012; Maximum likelihood estimation in the presence of surprise factor.
- **PDF4** Castanos, Fernando, 2009-2011; Approximate energy shaping and passivity based control of complex mechanical systems.
- **PDF2** Gromov, Dmitri, 2010; Error analysis in symplectic integration of port Hamiltonian systems.
- **PDF2** Raouf, Jamila, 2008-2010; Control of switched linear systems.
- **PDF1** Legrand, Mathias, 2007-2010; Nonlinear model reduction in application to rotor blade systems.

## Masters Theses

- MEng26 Ahmad, Saad, 2012; Modeling of a spatial double pendulum using spatial operator algebra.
- MEng25 Berkani, Samira, 2011; Principles of spatial operator algebra in application to modeling of kinematic chains.
- MEng24 Ni, Jie, 2011; Sliding mode control of a spacial double inverted pendulum
- MEng23 Xinjilefu, Xinjilefu, 2009; Stabilization of the Spatial Double Inverted Pendulum
- MEng22 Sood, Guarav, 2006; Linear quadratic control of a model of a human body in the standing position.
- MEng21 Vanreusel, Stephen, 2005; Linear system identification and robust control.
- MEng20 Haccoun, Laurent, 2004; Fault detection in turbo-jet engines.
- MEng19 Pichette, Alexandre 2003; An IMM state estimator for maneuvering targets.
- MEng18 Wang, Mary, 2003; Summary of data fusion approaches to trajectory estimation.
- MEng17 Hadzagic, Melita, 2002; A comparison of the IMM and JPFD tracking algorithms.

- MEng16 Jarry, Benoit, 2000; An IMM-JVC algorithm for tracking targets in clutter.
- MEng15 Lu, Mu-Chiao., 2000; Model predictive control of systems with delays.
- MEng14 Stachowiak, Jacek, 1998; A survey of control methods for bilinear systems.
- MEng13 Bitton, Michel, 1998; Receding horizon optimal control of a planar aircraft model.
- MEng12 Zia, Lilian, 1997; A deterministic observer for nonlinear descriptor systems.
- MEng11 Wong, Yue-Bong, 1997; Optimization based approach to the synthesis of time varying stabilizing feedback for drift free systems.
- MEng10 Abboud, Salim, 1997; A gradient flow observer for nonlinear systems.
- MEng09 Meng, Xiaodong, 1997; Set-point stabilization of drift free systems of higher degree.
- MEng08 Woo, Kin Sang, 1996; Receding horizon control without terminal constraint on the state.
- MEng07 Cheung, Kam-Ming, 1996; Optimization based trajectory tracking control for a planar model of an aircraft.
- MEng06 Van Loon, J., 1996; Gain scheduling versus fuzzy rule based approaches to control of nonholonomic systems.

- MEng05 De Robillard, Alexandre, 1995; Switching strategies for stabilization of a class of nonlinear systems.
- MEng04 Lee, Tai-Sen, 1996; Construction of piece-wise constant feedback for drift free systems of degree one.
- MEng03 Aleong, Paul, 1995; Tracking control for nonlinear continuous time systems.
- MEng02 Lee, Shui Yin, 1995; Trajectory tracking optimization for a simplified aircraft model
- MEng01 Achkar, Alain, 1994; Four ways to stabilize a nonholonomic system on the example of a mobile robot.