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Other Publications (Unrefereed)

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Invited Talks

[1] Talk.

[2] M. G. Safonov. The frequency-domain analysis of feedback system robustness. Talk, Honeywell Systems and Research Center, Minneapolis, MN, July 27, 1978.

[3] M. G. Safonov. Frequency-domain analysis of feedback system robustness. Talk, Aerospace Corp., El Segundo, CA, April 19, 1979. Keynote talk at regular meeting of Los Angeles Chapter of IEEE Control Systems Society.

[4] M. G. Safonov. Frequency-domain analysis of multivariable feedback system robustness. Talk, Office of Naval Research Conference on Recent Developments in the Robustness Theory of Multivariable Systems, MIT, Cambridge, MA, April 25-27, 1979.

[5] M. G. Safonov. Robustness and decentralized hierarchical control of large systems. Talk, Laboratory for Information and Decision Systems, MIT, Cambridge, MA, April 2, 1979.

[6] M. G. Safonov. Robustness and decentralized, hierarchical control of large systems. Talk, University of Southern California, Los Angeles, CA, October 15, 1979.

[7] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, Control and Management Systems Div., Engineering Dept., Cambridge University, Cambridge, England, June 12, 1980.

[8] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, Department of Aerospace Engineering and Mechanics, University of Minnesota, Minneapolis, MN, August 6, 1980.

[9] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, Dept. of Electrical Engineering, University of New Brunswick, Canada, October 17, 1980.

[10] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, University of Southern California, Los Angeles, CA, October 13, 1980.

[11] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, Department of Aerospace and Mechanical Enginering, Princeton University, New Jersey, November 3, 1980.

[12] M. G. Safonov. Robustness in feedback systems. Talk, National Science Foundation sponsored CAS Conf. on Nonlinear Circuits and Systems, Rice University, Houston, TX, January 4-5, 1980.

[13] M. G. Safonov. Stability margins of multivariable systems with diagonal perturbation matrices. Talk, Honeywell Systems and Research Center, Minneapolis, MN, August 8, 1980.

[14] M. G. Safonov. Feedback properties of multivariable systems: The role and use of the return difference matrix. Talk, Department of Electrical Engineering, SUNY, Stony Brook, NY, December 23, 1981.

[15] M. G. Safonov. Fractional representation approach to robust feedback synthesis. Talk, Honeywell Systems and Research Center, Minneapolis, MN, July 15 and 16, 1981.

[16] M. G. Safonov. Propagation of conic model uncertainty in interconnected systems. Talk, Engineering Department, Oxford University, Oxford, England, July 22, 1982.

[17] M. G. Safonov. Singular value response shaping and H^∞ optimization: The MIMO case. Talk, Honeywell Systems and Research Center, Minneapolis, MN, August 20, 1982.

[18] M. G. Safonov. Improved stability margin estimates for systems with multiple nonlinearities. Talk, Honeywell Systems and Research Center, Minneapolis, MN, July 29, 1983.

[19] M. G. Safonov. Optimal scaling for multivariable stability margin analysis. Talk, Imperial College of Science and Technology, London, England, November 10, 1983.

[20] M. G. Safonov. Robust feedback control of multivariable systems. Talk, USC Industrial Associates, Los Angeles, May 12, 1983.

[21] M. G. Safonov. Robust multivariable feedback design: The state of the art. Talk, Bristol Polytechnic, Bristol, England, November 17, 1983.

[22] M. G. Safonov. Robustness issues in multivariable feedback design. Talk, University of Strathclyde, Glasgow, Scotland, October 14, 1983.

[23] M. G. Safonov. All solutions 'homotopy' methods for feedback performance analysis and optimization. Talk, ONR/Honeywell Conf. on Advances in Multivariable Control, Minneapolis, MN, October 8-10, 1984.

[24] M. G. Safonov. L^∞ sensitivity vs. stability margin. Talk, Oxford University Engineering Dept., Oxford, England, January 23, 1984.

[25] M. G. Safonov. L^∞ singular value optimization techniques and robust multiloop control design. Talk, Aerospace Corp., El Segundo, CA, July 1984.

[26] M. G. Safonov. Optimal scaling for multivariable stability margins. Talk, Warwick University, Coventry, England, February 1, 1984.

[27] M. G. Safonov. Optimal scaling for multivariable stability margins. Talk, University of Reading, Reading, England, April 11, 1984.

[28] M. G. Safonov. Robust multivariable control. Talk, Scottish-American Symp. on New Developments in Control Engineering, Glasgow, Scotland, June 26-27, 1984.

[29] M. G. Safonov. L^∞ optimal robust control methods. Talk, United Technologies Research Center, East Hartford, CT, August 8, 1986.

[30] M. G. Safonov. L^∞ robust control methods. Talk, Scientific Systems, Inc., Cambridge, MA, August 7, 1986.

[31] M. G. Safonov. Robust control. Talk, USC, Los Angeles, CA, May 5, 1986.

[32] M. G. Safonov. Robust control. Talk, Industrial Assoc. Research Review, University of Southern California, Los Angeles, CA, May 6, 1986.

[33] M. G. Safonov. Robust control methods. Talk, Lawrence Livermore National Laboratory, Livermore, CA, March 25, 1986. With E. A. Jonckheere.

[34] M. G. Safonov. Robust feedback synthesis via diagonally scaled L^∞ optimal control. Talk, Cambridge University, Cambridge, England, August 21, 1986.

[35] M. G. Safonov. The role and use of singular values in multiloop feedback design. Talk, Northrop Technical Center, Hawthorne, CA, November 7, 1986.

[36] M. G. Safonov. The role and use of singular values in multiloop feedback design. Talk, Northrop Technical Center, Hawthorne, CA, November 14, 1986.

[37] M. G. Safonov. H^∞ robust multivariable control design. Talk, UCLA, Los Angeles, CA, May 18, 1987.

[38] M. G. Safonov. Issues in H^∞ design. Talk, Imperial College, London, England, August 7, 1987.

[39] M. G. Safonov. JOSE structure control design. Talk, TRW Space and Technology Group, Redondo Beach, CA, April 23, 1987.

[40] M. G. Safonov. Optimal H^∞ synthesis of robust controllers for systems with structured uncertainty. Talk, Caltech, Pasadena, CA, April 28, 1987.

[41] M. G. Safonov. Robust identification: Basis free Hankel and balanced model reduction. Talk, Symp. on Robust and Adaptive Control, Oaxaca, Mexico, December 2-4, 1987.

[42] M. G. Safonov. Nonconservative calculation of the multiloop stability margin. Talk, International Conf. on Identification and Control, Turin, Italy, June 10-12, 1988.

[43] M. G. Safonov. Modeling and robustness issues in control design for flexible structures. Talk, Caltech Jet Propulsion Laboratory, Pasadena, CA, July 11, 1989.

[44] M. G. Safonov. Modelling and robustness issues in control design for flexible structures. Talk, Honeywell Systems and Research Center, Minneapolis, MN, September 28, 1989.

[45] M. G. Safonov. The role and use of singular values in robust multiloop control design. Talk, Northrop Aircraft, Hawthorne, CA, September 19 and September 26, 1989.

[46] M. G. Safonov. H^∞ control design for a flexible space structure. Talk, Dept. of Electrical Engineering, Imperial College, London, England, August 7, 1990.

[47] M. G. Safonov. H^∞ control design for a flexible space structure. Talk, Leicester University, Leicester, England, August 10, 1990.

[48] M. G. Safonov. Model reduction for robust control. Talk, Caltech, Pasadena, CA, November 26, 1990.

[49] M. G. Safonov. Relative-error model reduction via balanced stochastic truncation and error bounds. Talk, Cambridge University Engineering Department, Cambridge, England, August 2, 1990.

[50] M. G. Safonov. Relative error model reduction via balanced stochastic truncation and error bounds. Talk, Dept. of Electrical Engineering, Imperial College, London, England, August 6, 1990.

[51] M. G. Safonov. Robust control. Talk, First Annual Rockwell Advanced Control Systems Conference, Anaheim, CA, January 10, 1990.

[52] M. G. Safonov and V. X. Le. Constant compensators for squaring down and output feedback stabilization: A matrix factorization viewpoint. Talk, SIAM Conf. on Applied Multivariable Linear Algebra, Minneapolis, MN, September 11-14, 1991.

[53] M. G. Safonov. Quantifying the modeling accuracy needed for control design. Talk, International Workshop on Robust Control, San Antonio, TX, March 13-15, 1991.

[54] M. G. Safonov. Quantifying the modeling accuracy needed for control system design. Talk, Third Rockwell Advanced Control Systems/Neural Network/Signal Processing Conference, Anaheim, CA, January 22, 1991.

[55] M. G. Safonov. Robust control: The theory and its application to a flexible space structure. Talk, University of California, Berkeley, CA, February 22, 1991.

[56] M. G. Safonov. Pencil system matrices for reliable computation. Talk, Fourth Rockwell International Control/Signal Processing Conference, Anaheim, CA, January 21-22, 1992.

[57] M. G. Safonov. Real/complex K_m-synthesis without curve fitting. Talk, Rockwell International Science Center, Anaheim, CA, November 5, 1992.

[58] M. G. Safonov. μ-Synthesis robust control: What's wrong and how to fix it? Talk, Advanced Control Applications Workshop, Hughes Aircraft, El Segundo, CA, February 3, 1993. Plenary talk.

[59] M. G. Safonov. μ-Synthesis robust control: What's wrong and how to fix it? Talk, Department of Aerospace and Mechanical Engineering, University of California, Irvine, CA, February 25, 1993.

[60] M. G. Safonov. Recent progress in μ-Synthesis robust control. Talk, Matlab Conference, Cambridge, MA, October 18–20, 1993.

[61] P. Gahinet and A. Nemirovskii. LMI lab a package for manipulating and solving LMI's. Talk, IFAC Symposium on Robust Control Design, Rio de Janeiro, Brazil, September 14–16, 1994. M. G. Safonov presented paper on behalf of authors.

[62] M. G. Safonov. Robust control methods: From experiments to control systems. Talk, Sixth Rockwell International Control/Signal Processing Conference, Anaheim, CA, March 1–2, 1994.

[63] M. G. Safonov. The unfalsified control concept: A direct path from experiment to controller. Talk, Hughes Aircraft, El Segundo, CA, November 9, 1994.

[64] M. G. Safonov. Focusing on the knowable: Controller invalidation and learning. Talk, MIT Lab for Information and Decision Systems, Cambridge, MA, October 4, 1995.

[65] M. G. Safonov. Robust control research. Talk, USC, Los Angeles, CA, May 22, 1995.

[66] M. G. Safonov. Unfalsified control and learning. Talk, Seventh Rockwell International Control/Signal Processing Conference, Thousand Oaks, CA, May 25–25, 1995.

[67] M. G. Safonov. Focusing on the knowable: Controller invalidation and learning. Talk, Georgia Institute of Technology, Atlanta, GA, April 11, 1996. Detinguished Lecture Series in Systems and Controls.

[68] M. G. Safonov. Focusing on the knowable: Controller invalidation and learning. Talk, Advanced Research Seminar on Systems Theory, Econometrics and Probability, Sophia Antipolis, Nice, France, June 2–4, 1997. Invited talk at high-level international research workshop organized by R. E. Kalman of ETH, Zurich.

[69] M. G. Safonov. Focusing on the knowable: Controller invalidation and learning. Talk, Imperial College, London, England, June 23, 1997.

[70] M. G. Safonov. Multivariable stability margin analysis. Talk, Hughes Aircraft, El Segundo, CA, May 27, 1997.

[71] M. G. Safonov. Robust control, feedback and learning. Talk, Workshop for Michael Athans, Tampa, FL, December 19, 1998, 1998. 60th birthday celebration honoring M. Athans.

[72] M. G. Safonov. Synthesis of positive real feedback systems: A simple derivation. Talk, UCSB, Santa, Barbara, CA, October 16, 1998.

[73] M. G. Safonov. CACSD design process. Talk, Panel Discussion on Perspectives on Computer Aided Control Systems Design, IEEE Symp. on Computer Aided Control System Design, Kohala Coast–Island of Hawaii, HI, August 22, 1999. Plenary session.

[74] M. G. Safonov. Robust control, feedback and learning. Talk, IFAC Intl. Workshop on Control of Uncertain Systems, Hong Kong, Univ. of Science & Technology, June 30 – July 2, 1999.

[75] M. G. Safonov. Robust control, feedback and learning. Talk, Poster Presentation, AFOSR Workshop on Dynamics and Control, Dayton, OH, August 4–6, 1999. http://routh.usc.edu/pub/safonov/safo99h.ppt

[76] M. G. Safonov. Multiplier IQC's for uncertain time delays. Talk, Tokyo University, Tokyo, Japan, May 22, 2000.

[77] M. G. Safonov. Robust control, feedback and learning. Talk, SICE Conference, Kariya, Japan, May 24, 2000. Invited plenary talk.

[78] M. G. Safonov. Robust control, feedback and learning. Talk, University of California, Santa Barbara, CA, October 13, 2000, 2000.

[79] M. G. Safonov. Robust control, feedback and learning. Talk, Caltech, Pasadena, CA, October 16, 2000, 2000.

[80] M. G. Safonov. Robust control tutorial. Talk, Tokyo University, Tokyo, Japan, May 31, 2000.

[81] M. G. Safonov. Unfalsified direct adaptive control of a two-link robot arm. Talk, Titech, Tokyo, Japan, June 13, 2000.

[82] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, Kyoto University, Kyoto, Japan, June 2, 2000.

[83] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, Osaka University, Osaka, Japan, June 6, 2000.

[84] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, AFOSR Workshop on Dynamics and Control, Dayton, OH, August 21–23, 2000.

[85] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, University of California, Santa Barbara, CA, November 17, 2000.

[86] M. G. Safonov. Data-driven behavioral formulation of the adaptive feedback control problem. Talk, AFOSR Workshop on Dynamics and Control, Dayton, OH, July 30 –August 02, 2001. http://routh.usc.edu/pub/safonov/safo01o.pps

[87] M. G. Safonov. Robust control, feedback and learning. Talk, IEEE Control Society, San Diego Chapter, La Jolla, CA, January 18, 2001.

[88] M. G. Safonov. Robust control, feedback and learning. Talk, Univ. of California, Riverside, CA, November 16, 2001.

[89] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, University of California San Diego, La Jolla, CA, January 18, 2001.

[90] M. G. Safonov. Zames-Falb multipliers for MIMO nonlinearities. Talk, Workshop in honor of Boyd Pearson, Rice University, Houston, TX, March 9–10, 2001.

[91] M. G. Safonov. Data driven methods for robust control and learning. Talk, MIT, Cambridge, MA, March 14, 2002. http://routh.usc.edu/pub/safonov/safo02c.pps

[92] M. G. Safonov. Data driven methods for robust control and learning. Talk, Aerospace and Mechanical Engineering Seminar, USC, Los Angeles, CA, September 25, 2002. http://routh.usc.edu/pub/safonov/safo02c.pps

[93] M. G. Safonov. Myopic unfalsified control: A gradient approach to adaptation. Talk, AFOSR Dynamics and Control Workshop, Pasadena, CA, August 12 –August 14, 2002. http://routh.usc.edu/pub/safonov/safo02e.pps

[94] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, University of Bologna, Forli, Italy, May 8-10, 2003. NATO Lecture Series SCI-142.

[95] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, Escola Superior de Tecnologia, Setubal, Portugal, May 15-16, 2003. NATO Lecture Series SCI-142.

[96] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, USC, Los Angeles, CA, May 29-30, 2003. NATO Lecture Series SCI-142.

[97] M. G. Safonov. Robust control, feedback and learning: Data-driven methods. Talk, AFOSR Workshop and Contractors' Meeting: Dynamics and Control, Destin, Florida, September 8–12, 2003.

[98] M. G. Safonov. Adaptive control: Whats wrong and how to fix it? Talk, AFOSR Workshop and Contractors' Meeting: Dynamics and Control, Pasadena, CA, August 9–11, 2004.

[99] M. G. Safonov. All stability multipliers for repeated mimo nonlinearities. Talk, Cambridge University Engineering Dept., Cambridge, England, September 9, 2004.

[100] M. G. Safonov. Recent advances in robust control theory. Talk, University of Washington, Seattle, WA, June 3, 2004.

[101] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, University Politehnica, Bucharest, Romania, May 19-20, 2005. NATO Lecture Series SCI-166.

[102] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, KTH University, Stockholm, Sweden, May 12-13, 2005. NATO Lecture Series SCI-166.

[103] M. G. Safonov. Data-driven robust control design: Unfalsified control. Talk, Swiss Federal Institute of Technology (ETH), Zurich, Switzerland, May 23-24, 2005. NATO Lecture Series SCI-166.

[104] M. G. Safonov. Recent advances in robust control. Talk, Irish Signals and Systems Conference, Dublin, Ireland, September 2, 2005. Invited plenary talk.

[105] M. G. Safonov. Adaptation and learning without assumptions. Talk, California Institute of Technology, Pasadena, CA, March 22–23, 2006. Conference on Learning and Information in Games and Control. http://routh.usc.edu/pub/safonov/safo06c.pdf

[106] M. G. Safonov. Robust adaptation and learning: Unfalsified control and cost-detectability. Talk, UCLA, Los Angeles, CA, October 28, 2006.

[107] M. G. Safonov. The origins of robust control in the 1970's. Talk, ATHANS 70 Workshop, Clearwater Beach, FL, November 18, 2007. http://routh.usc.edu/pub/safonov/safo07b.ppt

[108] M. G. Safonov. The origins of robust control in the 1970's. Talk, Institute for Systems and Robotics, Instituto Superior Tecnico, Lisbon, Portugal, March 20, 2008.

[109] M. G. Safonov. The origins of robust control in the 1970's. Talk, Department of Electrical Engineering, Indian Institute of Technology, Kharagpur, India, December 11, 2008.

[110] M. G. Safonov. Robust adaptation and learning: Unfalsified control and cost dectectability. Talk, Institute for Systems and Robotics, Instituto Superior Tecnico, ,Lisbon, Portugal, March 18, 2008.

[111] M. G. Safonov. Robust adaptation and learning: Unfalsified control and cost-detectability. Talk, Texas-Wisconsin-California and Control Consortium Workshop, Los Angeles, CA, September 28, 2008.

[112] M. G. Safonov. Recent advances in robust control. Talk, UCLA, Los Angeles, CA, October 14, 2009.

[113] M. G. Safonov. Recent advances in robust control. Talk, Northrop-Grumman, El Segundo CA, October 15, 2010.

[114] M. G. Safonov. Recent advances in robust control. Talk, Northrop-Grumman, Rancho Bernardo, CA, January 21, 2011.

[115] M. G. Safonov. Origins of robust control: Early history and future speculations. Talk, Plenary Talk: IFAC Symposium on Robust Control Design (ROCOND 12), Aalborg, Denmark, June 20, 2012.

[116] M. G. Safonov. Adaptive control: Fooled by false assumptions? Talk, Sixteenth Yale Workshop on Adaptive and Learning Systems, New Haven, CT, June 5-7, 2013.

[117] M. G. Safonov. Origins of robust control: Early history and future speculations. Talk, UCLA, Los Angeles, CA, April 9, 2014.

[118] M. G. Safonov. Shifting paradigms for robust control then and now. Talk, UCSB, Santa, Barbara, CA, January 17, 2014.

Short Courses Taught

[1] M. G. Safonov. Robustness in control systems. Short Course, Linkoping University, Linkoping, Sweden, August 26-30, 1984. 5 four-hour lectures.

[2] M. G. Safonov. Frequency response methods for multivariable control. Short Course, AIAA, Los Angeles, CA, April 9, 16, 23 30, and, May 7 and 14, 1985. 6 two-hour lectures.

[3] M. G. Safonov. Frequency response methods for multivariate control. Short Course, University of Southern California, Los Angeles, CA, May 19-23, 1986. 10 three-hour lectures.

[4] M. G. Safonov. Robust control. Short Course, AIAA, Los Angeles, CA, April 23, 30 and May 7, 14, 21, 1991. 5 two-hour lectures.

[5] K. Poolla, M. G. Safonov, and R. Smith. Robust identification and control. Short Course, IEEE Regional Conf. on Aerospace Control Systems, Westlake, CA, May 28, 1993. Safonov delivered a two hour introductory tutorial on robust control which was followed by 5 hours of additional material presented by Poolla and Smith.

[6] E. A. Jonckheere and M. G. Safonov. Modern robust control and analysis. Short Course, Sponsored by National Chiao Tung University, National Cheng Kung University, National Adminstration of Education, IEEE Taipei Section, and IEEE Control Society Taipei Chapter, Tainan and Hsinchu, Taiwan, August 15–21, 1994. Ten two-and-one-half hour lectures on current topics in robust control.

Ph.D. Theses Supervised

1. B. S. Chen, "Inverse Problem of LQG Control via Frequency Dependent Cost/Noise Matrices," USC, May 1982.
2. K. Karimlou, "Input Output Stability Analysis with Hysteresis Nonlinearity," USC, May 1984.
3. A. Sideris, "Robust Feedback Synthesis via Conformal Mappings and H^∞ Optimization," USC, July 1985.
4. R. R. E. de Gaston, "Nonconservative Calculation of Multiloop Stability Margin," USC, December 1985.
5. R. Y. Chiang, "Modern Robust Control Theory," USC, December 1988.
6. V. X. Le, "Rational Matrix GCD's and Squaring-Down Compensators," USC, September 1989.
7. W. Wang, "Relative-Error Model Reduction, Identification and Control," USC, September 1990.
8. B. Copeland, "Cheap and Singular H^2 and H^∞ Control Problems: A Generalized Eigenproblem Approach," USC, December 1990.
9. A. Holohan, "Robust Controller Design," USC, June 1992.
10. T. Tsao, "Set Theoretic Adaptor Systems," USC, May 1994. Spectrum Astro, Manhattan Beach, CA. http://routh.usc.edu/pub/safonov/tsao94.pdf
11. J. H. Q. Ly, "A Multiplier Approach to Robust Analysis and Synthesis," USC, August 1995.
12. K. C. Goh, "Robust Control Synthesis via Bilinear Matrix Inequalities," USC, May 1995.
13. C.-H. Huang, "Unstably-Weighted Robust Control Synthesis via Linear matrix Inequalities and Matrix Pencils", USC, August 1996.
14. T. Brozenec, "Controller Invalidation, Identification & Learning", USC, November 1996.
15. F. B. Cabral, "Data Based Control", USC, December 1996.
16. V. Kulkarni, "Multipliers for Memoryless Incrementally Positive MIMO Nonlinearities", USC, May 2001.
17. M. Jun, "Robustness Analysis of Uncertain Time-Delay Systems", USC, October 2001.
18. P. Brugarolas, "Data Driven Control and Identification: An Unfalsification Approach", USC, May 2002.

19. H.-H. Meng, "Stability Analysis and Robust Control Synthesis with Generalized Multipliers", USC, June 2002. http://routh.usc.edu/pub/safonov/meng02.pdf

20. R. Mancera, "Multipliers for MIMO Nonlinearities: Theory and Algorithms", USC, December 2002.

21. A. Paul, "Multi Controller Adaptive Control (MCAC): Cost Detectability, Stability and Some Applications", USC, August 2005. http://routh.usc.edu/pub/safonov/paul05.pdf

22. M. Stefanovic, "Safe Switching Adaptive Control: Stability and Convergence", USC, August 2005. http://routh.usc.edu/pub/safonov/stef05.pdf

23. R. Wang, "Cost Detectability and Safe MCAC", USC, December 2005. http://routh.usc.edu/pub/safonov/wang05.pdf

24. S. Y. Cheong, "Bumpless Transfer and Fading Memory for Adaptive Switching Control", USC, December 2009. http://routh.usc.edu/pub/safonov/cheo09.pdf

25. M. Alharashani, "Relaxing Convergence Assumptions for Continuous Adaptive Control", USC, June 2010. http://routh.usc.edu/pub/safonov/alha10.pdf

26. M. Chang, A Revised Computational Procedure for Calculating Zames-Falb Multipliers", USC, December 2010. http://routh.usc.edu/pub/safonov/chan10.pdf

27. A. Karthikeyan, "LQ Feedback Formulation for H_∞ Output Feeback Control", USC, May 2013. http://routh.usc.edu/pub/safonov/kart13.pdf