LIST OF FIGURES

Figure No.	Figure captions	Page No.
2.1	Stability in the sense of Lyapunov	24
2.2	Asymptotic stability in the sense of Lyapunov	25
2.3	Monotonic stability in the sense of Lyapunov	26
2.4	Four Stages of Optimization Process	31
2.5	Architecture of Fuzzy Logic Control	35
3.1	Closed-loop structure of magnetic levitation system	38
3.2	Open-loop response of magnetic levitation system	41
3.3	Step response of magnetic levitation system with PID controller tuned with T&E method	43
3.4	Bode plot of magnetic levitation system with PID controller tuned using T&E method	44
3.5	Distribution of marks obtained by learners taught by two different teachers	46
3.6	Model for the distribution of marks obtained for a group of learners	47
3.7	Block diagram for optimum search using TLBO	49
3.8	Step response of magnetic levitation system with parameters of PID controller tuned using TLBO algorithm	53
3.9	Bode diagram of magnetic levitation system with parameters of PID controller tuned using TLBO	54

	algorithm	
4.1	Step response of nonminimum phase system with and without Pade's first order approximation	60
4.2	Step response of Nonminimum Phase System with PID Controller	63
4.3	Bode Response of Nonminimum Phase System with PID Controller	64
4.4	Step Response of Nonminimum Phase System with Smith Predictor	68
4.5	Bode response of nonminimum phase system with Smith Predictor	69
4.6	Hierarchy of GWO	70
4.7	Flowchart for obtaining parameters of PID controller using GWO	75
4.8	Step Response of Nonminimum Phase System with GWO algorithm	76
4.9	Bode Response of Nonminimum Phase System with GWO algorithm	77
5.1	Free-body diagram of Inverted pendulum	83
5.2	Open-loop response of cart's position	89
5.3	Open-loop response of pendulum's angle	89
5.4	Block diagram of closed-loop control system	91
5.5	Closed-loop response of cart's position with PID controller	93
5.6	Closed-loop response of pendulum's angle with PID	93

	controller	
5.7	Closed-loop response of cart's position with LQR controller	97
5.8	Closed-loop response of pendulum's angle with LQR controller	97
5.9	Conceptual Mechanism of Fuzzy logic control	100
5.10	Movement of Inverted-pendulum system mounted on a cart	101
5.11	Membership function of error and change in error for cart's position	101
5.12	Output membership function for cart's position	102
5.13	Membership function of error and change in error for pendulum's angle	103
5.14	Output membership function for pendulum's angle	103
5.15	Simulink model of inverted-pendulum system with fuzzy logic control	104
5.16	Closed-loop response of cart's position with Fuzzy Logic controller	105
5.17	Closed-loop response of pendulum's angle with Fuzzy Logic controller	105