

# Adaptive Control

$$\dot{x} = Ax + Bu + Cv$$

$$x \in R^m, \quad u \in P \subset R, \quad v \in R$$

$$t \in [0, \theta]$$

Ganebnyi S.A, Kumkov S.S. and V.S.Patsko. **Control design in problems with an unknown level of dynamical disturbance**, *Journal of Applied Mathematics and Mechanics*, 2006, vol. 70, issue 5, pp. 680–695;  
transl. from *Prikl. Math. Mekh.*, 2006, vol. 70, issue 5, pp. 753–770 (in Russian).