For the past few decades, the problem of constraint management in control systems has received significant attention. It is well-known that this problem cannot be solved systematically using classical linear control theory. Thus, many techniques from predictive control and geometric control have evolved in recent years to address this problem. One such predictive method is the so-called Reference Governor (RG), which was initially proposed by Kapasouris et al. and later investigated thoroughly by researchers at the University of Michigan. RG is an add-on control scheme which enforces state and control constraints on pre-stabilized systems by modifying, whenever necessary, the reference signal (instead of actuator commands). The benefit of RG is that it is numerically efficient and real-time implementable, even on slow processors or systems with fast dynamics. In this talk, I will first review the theory of RG, and then focus on our recent advancements in RG for periodic systems and RG for MIMO systems.

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