Control Systems - 7 Semester DCSE - Week 9

Observer based state feedback controller design

Controller Design Techniques

Recalling again, we know that there are 3 types of techniques to design controllers which are:

- Full-state feedback controller or state feedback controller
- Observer-based state feedback controller
- PID Controller

Last week, we studied (and then simulated) the design of full-state feedback controller and its pre-requisites.

Today, we will study the design and pre-requisites of observer-based state feedback controller.

Controller Design Techniques

What is the difference between state feedback and observer-based state feedback controller?

It depends on matrix C whether it is identity matrix or not. What is meant by matrix C?

$$\frac{dx}{dt} = Ax(t) + Bu(t)$$
$$y = Cx(t) + Du(t)$$

What is meant by $y = Cx + Du$?

Controller Design Techniques

When we can measure all the state-space variables using sensors or devices, then we write the following:

$$\frac{dx}{dt} = Ax(t) + Bu(t)$$
$$y = x(t) + Du(t)$$

Can we measure or sense all the state-space variables?

- The sensors may be highly priced (or not economical/competetive to buy) e.g. camera in washing machine
- The sensors may require long wires and cables (or support mechanisms)
- The sensors may not be highly reliable e.g. a temperate sensor may not indicate a change of 2° temperature
- The sensor may not be available in market

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Controller Design Techniques

When we can NOT measure or sense all the state-space variables, but some of the state-space variables, then we write the following:

$$\frac{dx}{dt} = Ax(t) + Bu(t)$$
$$y = Cx(t) + Du(t)$$

For example:

$$\begin{bmatrix} \frac{dx_1}{dt} \\ \frac{dx_2}{dt} \end{bmatrix} = A \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + Bu(t)$$
$$y = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

If such a system is unstable, how can we stabilize it using controller? Observer-based state feedback controller may be the possible solution in such a scenario

Observer based state feedback controller

There are 3 pre-requisites to full-fill before we can proceed to design of observer-based state feedback controller.

- Matrix C must NOT be equal to identity and matrix D must be equal to zero (or absent)
- The system must pass controllability test.
- The system must pass observability test.

The first 2 pre-requisites seem easy or familiar but what is observability test. Let us study observability test.

Pre-req 3: Observability Test

A system is observable or it passes observability test if the following criteria is satisfied:

- First, determine the order of the system and call it n.
- Second, using n, construct matrix Q follows:

$$Q = \begin{bmatrix} C \\ CA \\ CA^2 \\ \vdots \\ CA^{n-1} \end{bmatrix} \quad (1)$$

- Third, compute rank of matrix Q
- Finally, check if rank of matrix Q is equal to n or not.

If $rank(Q) = n$, then the system is observable and we can proceed to design of controller, otherwise STOP. No controller can be designed.

Observer Design

An observer is also called estimator - it estimates the unmeasured state-space variables.

What is estimate called in urdu?

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So, if you are doing Andaza, it must be good andaza. In control systems literature good andaza means observer must be stable.

Example

Check whether do we need to design a controller for the following system:

$$\begin{bmatrix} \frac{dx_1}{dt} \\ \frac{dx_2}{dt} \end{bmatrix} = \begin{bmatrix} 2 & 3 \\ 0 & 5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 1 \\ 2 \end{bmatrix} u(t)$$

$$y = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

If we need a controller, identify which controller to design, and then design it and place the eigenvalues at $(-3, -5)$. If you need observer, then place observer eigen values at $(-10, -20)$.

Checking Stability to know whether we require a controller

First, we check stability of this system. The eigenvalues of this system can be obtained from $det(\lambda I - A) = 0$

$$\begin{aligned} det(\lambda I - A) &= det \begin{bmatrix} \lambda & 0 \\ 0 & \lambda \end{bmatrix} - \begin{bmatrix} 2 & 3 \\ 0 & 5 \end{bmatrix} \\ &= det \begin{bmatrix} \lambda - 2 & -3 \\ 0 & \lambda - 5 \end{bmatrix} \\ &= (\lambda - 2)(\lambda - 5) - (0)(-3) \\ &= (\lambda - 2)(\lambda - 5) - (0) \\ &= (\lambda - 2)(\lambda - 5) \end{aligned}$$

The eigenvalues of matrix A are at 2 and 5, which indicates it is an unstable system.

Deciding controller type

Now, which controller to choose?

$$\begin{bmatrix} \frac{dx_1}{dt} \\ \frac{dx_2}{dt} \end{bmatrix} = \begin{bmatrix} 2 & 3 \\ 0 & 5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 1 \\ 2 \end{bmatrix} u(t)$$

$$y = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

As matrix C is NOT equal to identity matrix, we proceed to design of observer-based state feedback controller.

Prerequisite 2- Controllability Test

Let us compute now pre-requisite number 2 which is the controllability test.

In this case $n = 2$, we matrix P would have the following shape:

$$P = [B \quad AB]$$

$$P = \begin{bmatrix} 1 & 8 \\ 2 & 10 \end{bmatrix}$$

$$det(P) = -6$$

As determinant P is non-zero, so $rank(P) = 2$, and it passes controllability test.

Let us proceed to Observability Test.

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Prerequisite 3 - Observability Test

Let us compute now pre-requisite number 3 which is the observability test.

In this case $n = 2$, we matrix Q would have the following shape:

$$Q = \begin{bmatrix} C \\ CA \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 2 & 3 \end{bmatrix} \tag{2}$$

$$det(Q) = 3$$

As determinant Q is non-zero, so $rank(Q) = 2$, and it passes observability test.

Let us proceed to design of controller now.

Design Steps - Observer Design

To design controller, first we need to design observer and then state feedback controller as follows:

Observer:

- Construct matrix L whose size is transpose the size of C
- Populate matrix L with elements starting from l_1, l_2 and so on
- Post-multiply C with L to obtain LC, and then compute $det(sI - (A - LC))$
- Obtain the desired characteristic equation for observer and compare coefficients to obtain the values of l_1, l_2, and so on

Design Steps - Controller Design

State feedback Controller:

- Construct matrix K whose size is transpose the size of B
- Populate matrix K with elements starting from k_1, k_2 and so on
- Pre-multiply B with K to obtain BK, and then compute $det(sI - (A - BK))$
- Obtain the desired characteristic equation and compare coefficients to obtain the values of k_1, k_2, k_3 and so on

Solution - Observer Design Slide 1

$$L = \begin{bmatrix} l_1 \\ l_2 \end{bmatrix}$$

$$LC = \begin{bmatrix} l_1 & 0 \\ l_2 & 0 \end{bmatrix}$$

$$A - LC = \begin{bmatrix} 2 - l_1 & 3 \\ -l_2 & 5 \end{bmatrix}$$

$$sI - (A - LC) = \begin{bmatrix} s & 0 \\ 0 & s \end{bmatrix} - \begin{bmatrix} 2 - l_1 & 3 \\ -l_2 & 5 \end{bmatrix}$$

$$sI - (A - LC) = \begin{bmatrix} l_1 + s - 2 & -3 \\ l_2 & s - 5 \end{bmatrix}$$

Solution - Observer Design Slide 2

$$sI - (A - LC) = \begin{bmatrix} s-2+l_1 & -3+l_2 \\ 2l_1 & 2l_2+s-5 \end{bmatrix}$$

$$det(sI - (A - LC)) = s^2 + (l_1 - 7)s + (3l_2 - 5l_1 + 10)$$

Now lets compare it with desired characteristic equation:

$$(s+10)(s+20) = s^2 + 30s + 20$$

Compare coefficients to obtain values of l_1 and l_2.

Solution - State Feedback Controller - Slide 2

$$sI - (A - BK) = \begin{bmatrix} s-2+k_1 & -3+k_2 \\ 2k_1 & 2k_2+s-5 \end{bmatrix}$$

$$det(sI - (A - BK)) = s^2 + (k_1 + 2k_2 - 7)s + (-4k_2 + 10)$$

Now lets compare it with desired characteristic equation:

$$(s+3)(s+5) = s^2 + 8s + 15$$

Compare coefficients to obtain values of k_1 and k_2.

Solution - State Feedback Controller - Slide 1

$$K = \begin{bmatrix} k_1 & k_2 \end{bmatrix}$$

$$BK = \begin{bmatrix} k_1 & k_2 \\ 2k_1 & 2k_2 \end{bmatrix}$$

$$A - BK = \begin{bmatrix} 2-k_1 & 3-k_2 \\ 0-2k_1 & 5-2k_2 \end{bmatrix}$$

$$sI - (A - BK) = \begin{bmatrix} s & 0 \\ 0 & s \end{bmatrix} - \begin{bmatrix} 2-k_1 & 3-k_2 \\ 0-2k_1 & 5-2k_2 \end{bmatrix}$$

$$sI - (A - BK) = \begin{bmatrix} s-2+k_1 & -3+k_2 \\ 2k_1 & 2k_2+s-5 \end{bmatrix}$$