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```
% Hinf example problem

w=logspace(-3,3);

s=tf('s');

%
Gtf=Gp;

Gtf=minreal(Gtf);
Gtfss=ss(Gtf);
[Ag,Bg,Cg,Dg]=ssdata(Gtfss);
[Ag,Bg,Cg,Dg]=minreal(Ag,Bg,Cg,Dg);

% Hinf does not work well, as Hinf norm is not defined on the jw-axis,
% with poles and zeros of Gp on the jw-axis,
% So we use a simple shifting trick to make the Ag BIBO stable.

Ag1=Ag-0.05*eye(6);

%define Wd (Robust uncertainty filter)

Wdtf=[makeweight(0.01,5,1000) 0 0 0 0 0; 0 makeweight(0.01,5,1000) 0 0
0 0; 0 0 makeweight(0.01,5,1000) 0 0 0; 0 0 0 makeweight(0.01,5,1000)
0 0; 0 0 0 0 makeweight(0.01,5,1000) 0; 0 0 0 0 0
makeweight(0.01,5,1000)];

3 states removed.
```

By students, define a new robust uncertainty filter

```
Wdss=ss(Wdtf);
[Ad,Bd,Cd,Dd]=ssdata(Wdss);
[Ad,Bd,Cd,Dd]=minreal(Ad,Bd,Cd,Dd);

%define Wu (Actuator filter)

Wutf=[0.01 0 0; 0 0.01 0; 0 0 0.01];
Wuss=ss(Wutf);
[Au,Bu,Cu,Du]=ssdata(Wuss);
```

```

[Au,Bu,Cu,Du]=minreal(Au,Bu,Cu,Du);

%define Wp (Performance filter)

Wptf=[makeweight(1000,0.5,0.1) 0 0 0 0 0; 0 makeweight(1000,0.5,0.1)
0 0 0 0; 0 0 makeweight(1000,0.5,0.1) 0 0 0; 0 0 0
makeweight(1000,0.5,0.1) 0 0; 0 0 0 0 makeweight(1000,0.5,0.1) 0; 0 0
0 0 0 makeweight(1000,0.5,0.1)];

```

By students, defina a new performance filter

```

Wpss=ss(Wptf); [Ap,Bp,Cp,Dp]=ssdata(Wpss);
[Ap,Bp,Cp,Dp]=minreal(Ap,Bp,Cp,Dp);

%compute augmented plant
[A,B1,B2,C1,C2,D11,D12,D21,D22]=...
    augss(Ag1,Bg,Cg,Dg,...
        Ap,Bp,Cp,Dp,...
        Au,Bu,Cu,Du,...
        Ad,Bd,Cd,Dd);

%Compute Hinf controller
[Gamma,acp,bcp,ccp,dcg,ac1,bc1,cc1,dc1]=...
    hinfopt(A,B1,B2,C1,C2,D11,D12,D21,D22);

% We have to shift back the A matrix of the controller to make this
% approach work properly.
acp1=acp+0.05*eye(size(acp));

```

<< H-Infinity Optimal Control Synthesis >>

No	Gamma	D11<=1	P-Exist	P>=0	S-Exist	S>=0	lam(PS)<1
C.L.							
1	1.0000e+00	OK	FAIL	FAIL	OK	OK	OK
STAB							
2	5.0000e-01	OK	FAIL	FAIL	OK	OK	OK
STAB							
3	2.5000e-01	OK	FAIL	FAIL	OK	OK	OK
UNST							
4	1.2500e-01	OK	FAIL	FAIL	OK	OK	OK
STAB							
5	6.2500e-02	OK	FAIL	OK	OK	OK	OK
STAB							
6	3.1250e-02	OK	FAIL	OK	OK	OK	OK
STAB							
7	1.5625e-02	OK	FAIL	OK	OK	OK	OK
STAB							
8	7.8125e-03	OK	FAIL	OK	OK	OK	OK
STAB							

9	3.9062e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
10	1.9531e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
11	9.7656e-04	OK	OK	OK	OK	OK	OK
	STAB						
12	1.4648e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
13	1.2207e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
14	1.0986e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
15	1.0376e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
16	1.0071e-03	OK	FAIL	OK	OK	OK	OK
	STAB						
17	9.9182e-04	OK	OK	OK	OK	OK	OK
	STAB						
18	9.9945e-04	OK	OK	OK	OK	OK	OK
	STAB						

Iteration no. 18 is your best answer under the tolerance:
0.0100 .

By students, compute Tzw using lft command

```
% open loop
[aly,bly,clly,dly]=series(Ag,Bg,Cg,Dg,acp1,bcp,ccp,dcp);
[aly,bly,clly,dly]=minreal(aly,bly,clly,dly);

%closed loop
[at,bt,ct,dt]=cloop(aly,bly,clly,dly,-1);
[at,bt,ct,dt]=minreal(at,bt,ct,dt);
as=at;
bs=bt;
cs=-ct;
ds=eye(3)-dt;

[ay,by,cy,dy]=series(acp1,bcp,ccp,dcp,as,bs,cs,ds);
[ay,by,cy,dy]=minreal(ay,by,cy,dy);

figure(1);
sigma(aly,bly,clly,dly)
hold on
sigma(inv(Wdtf(2,2)),w)
hold on
sigma(Wptf(1,1),w)
legend('Ly singular values','1/Wd','Wp')

figure(2)
sigma(at,bt,ct,dt,w)
hold on
```

```
sigma(as,bs,cs,ds,w)
hold on
sigma(inv(Wdtf(2,2)),w)
hold on
sigma(inv(Wptf(1,1)),w)
legend('T','S','1/Wd','1/Wp')
hold off

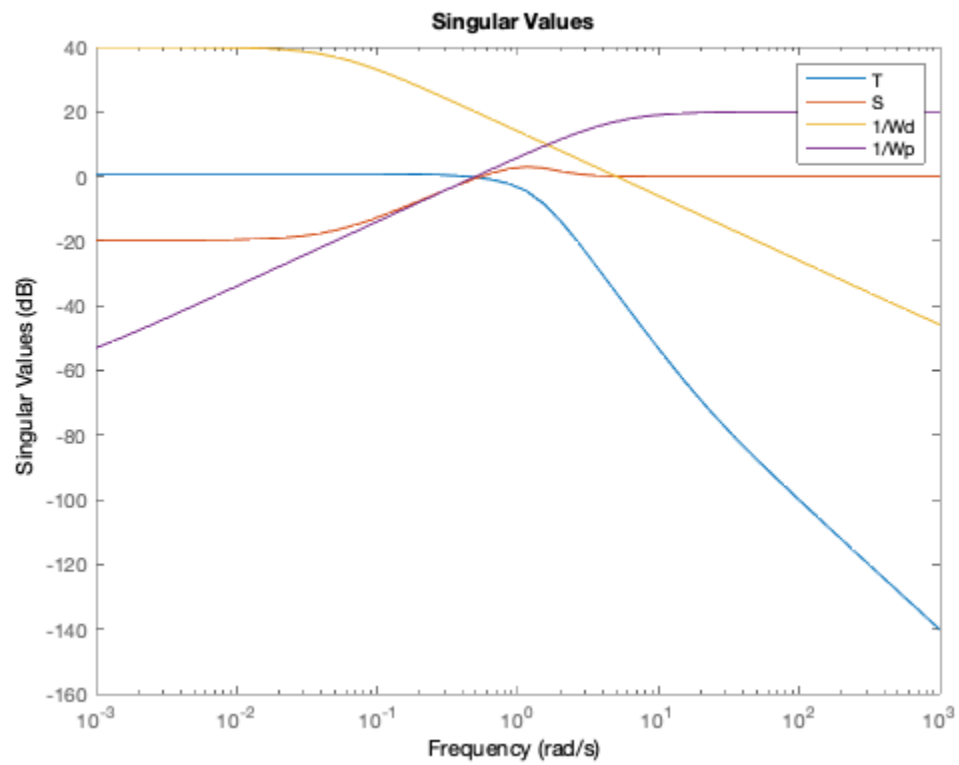
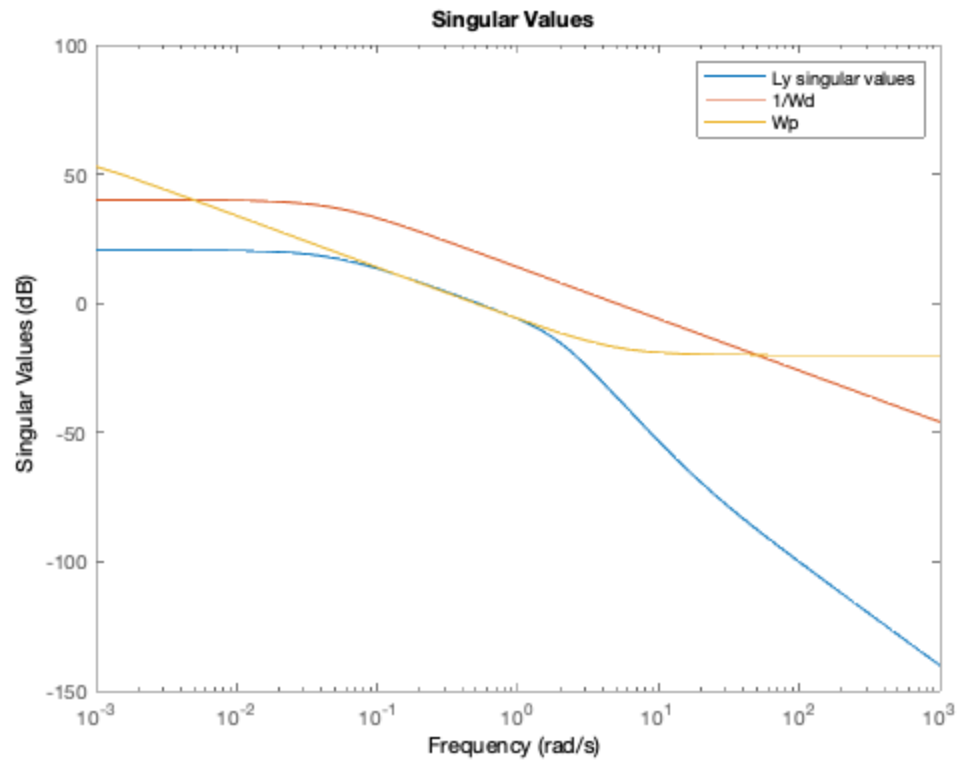
figure(3)
sigma(ay,by,cy,dy,w)
legend('Youla singular values')

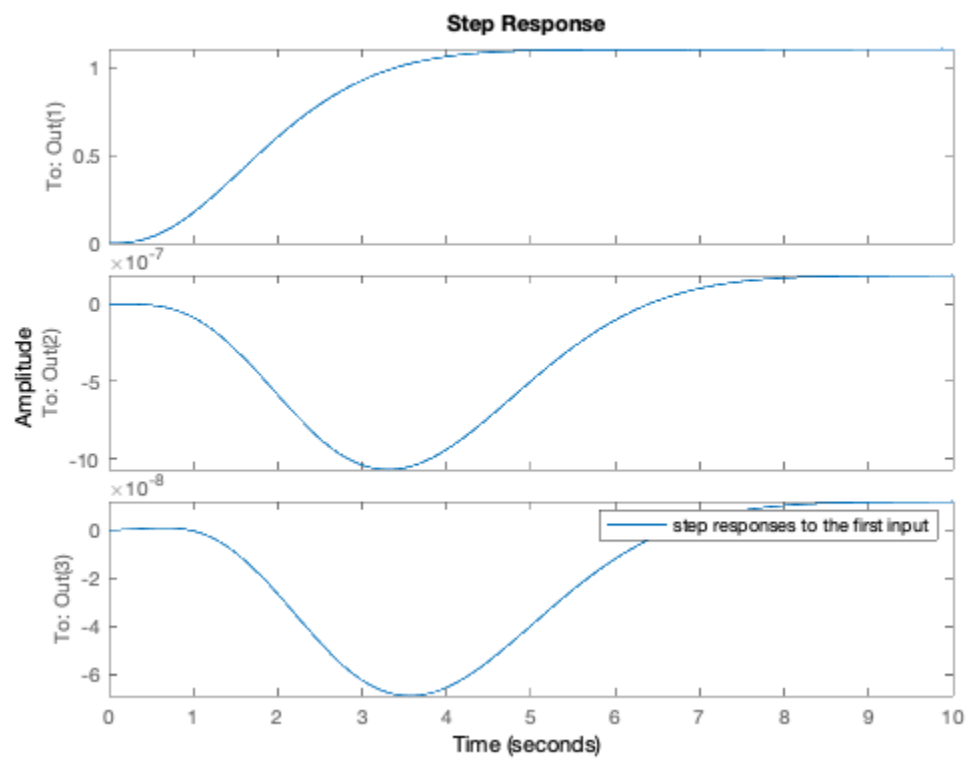
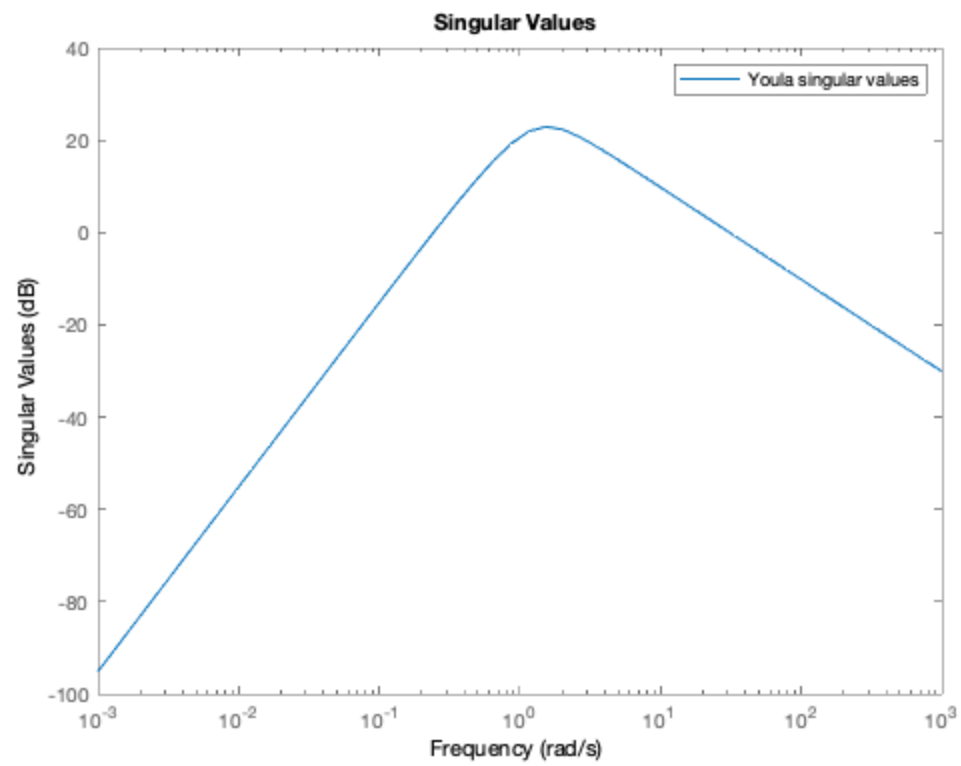
%closed loop time response
t=0:0.01:10;
figure(4)
step(at,bt,ct,dt,1,t)
legend('step responses to the first input')
figure(5)
step(at,bt,ct,dt,2,t)
legend('step responses to the second input')

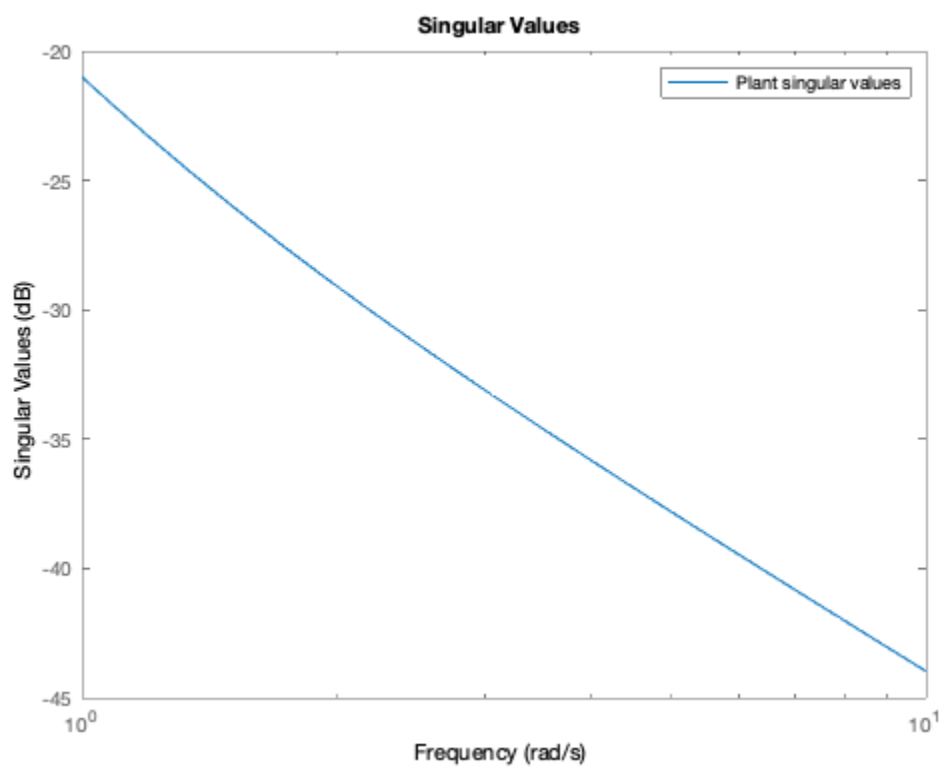
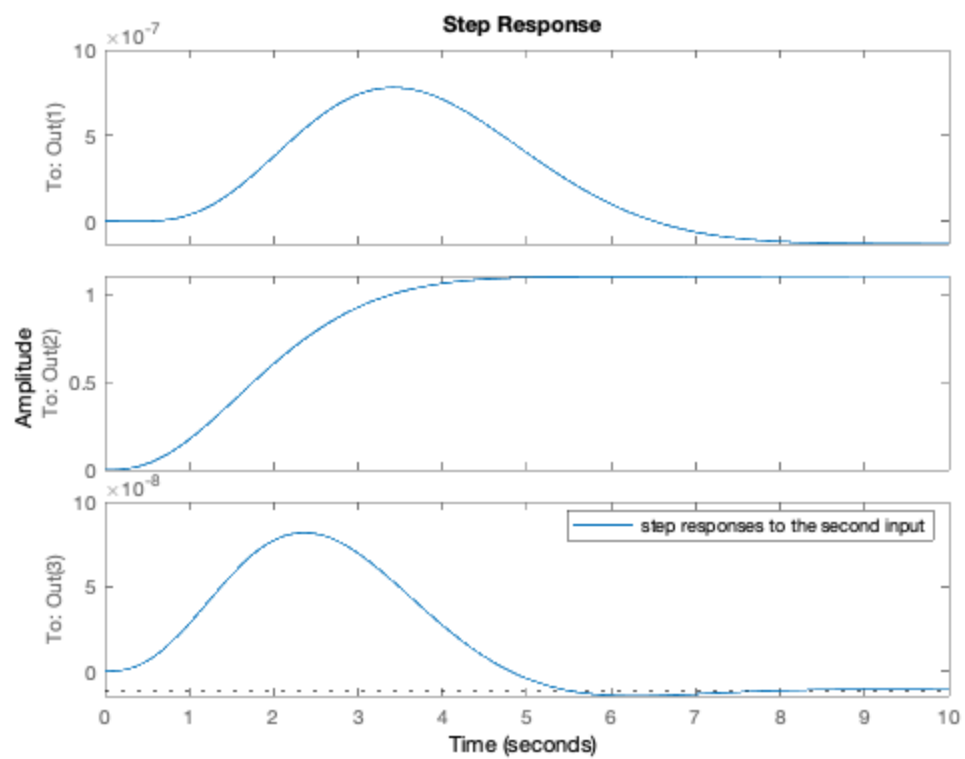
figure(6)
sigma(Gtf)
legend('Plant singular values')

figure (7)

12 states removed.
12 states removed.
```







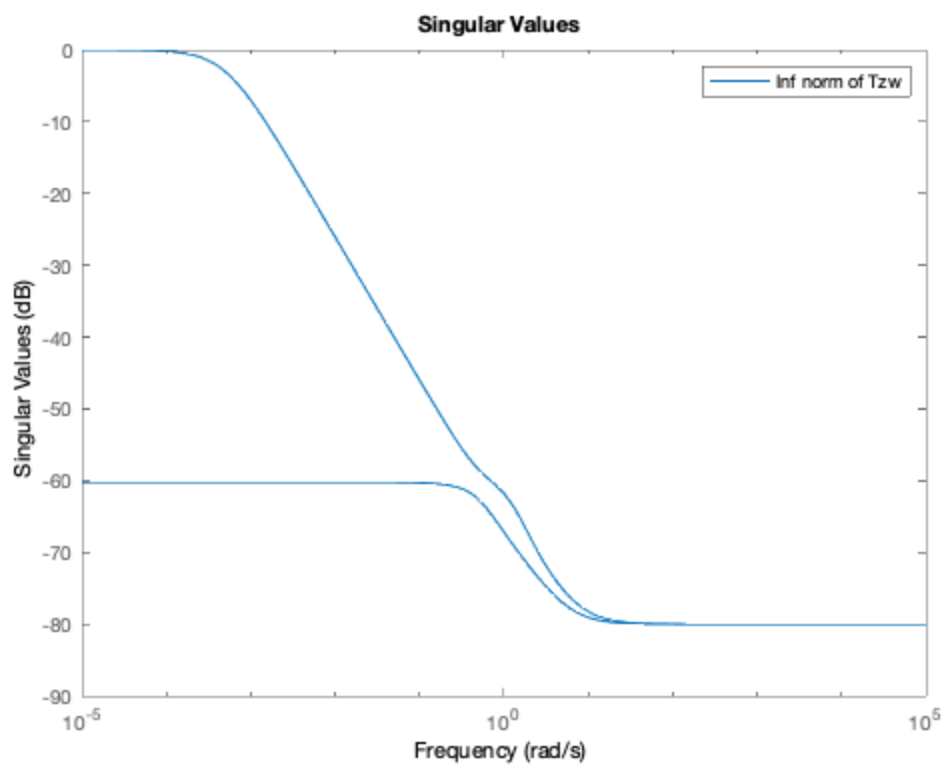
By students, compute the maximum singular value of Tzw from lft computation

```
%sigma(Tzw)
hold on
sigma(acl,bcl,ccl,dcl)
legend('Inf norm of Tzw')

Gc_ss=ss(acp,bcp,ccp,dcg);
Gc_tf=tf(Gc_ss);
Gc_tf=minreal(Gc_tf);

% save('Gc_Hinf_ss.mat','Gc_ss') % function form
%
% save('Gc_Hinf_tf.mat','Gc_tf') % function form

% Y = minreal(inv(eye(3) + Lu) * Gc);
% Ty = minreal(inv(eye(6) + Ly) * Ly);
% Sy = minreal(inv(eye(6) + Ly), 1e-02);
```

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