

Θέμα 3, 2019

$$\dot{x} = Ax(t) + bu(t) + d, \quad x \in \mathbb{R}^2, \quad A = \begin{bmatrix} 2 & 1 \\ 0 & 2 \end{bmatrix}, \quad b = \begin{bmatrix} 0 \\ 1 \end{bmatrix}, \quad d = \begin{bmatrix} d_1 \\ d_2 \end{bmatrix}$$

$$y(t) = cx(t)$$

$$c = \begin{bmatrix} 1 & 0 \end{bmatrix}$$

A. $Av \equiv 0$

$$\mathcal{C} = [b \quad Ab] = \begin{bmatrix} 0 & 1 \\ 1 & 2 \end{bmatrix} \Rightarrow \det \mathcal{C} = -1 \neq 0 \text{ ελέγχιμο}$$

$$\mathcal{O} = \begin{bmatrix} c \\ cA \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 2 & 1 \end{bmatrix} \Rightarrow \det \mathcal{O} = 1 \neq 0 \text{ παρατηρήσιμο}$$

ακταδές, διπλή ιδιοτιμή στο $\lambda = 2$

B. $u(t) = \begin{cases} 1, & t \geq 0 \\ 0, & t < 0 \end{cases}, \quad d = \begin{bmatrix} 1 \\ 2 \end{bmatrix}, \quad x(0) = \begin{bmatrix} 1 \\ 1 \end{bmatrix}$

$$\dot{x} = Ax + bu(t) + d$$

$$\begin{cases} \dot{x} = Ax + bu \\ x(t) = e^{At}x(0) + \int_0^t e^{A(t-s)}Bu(s)ds \end{cases}$$

$$\rightarrow x(t) = e^{At}x(0) + \int_0^t e^{A(t-s)} \underbrace{[bu(s) + d]}_{b+d} ds = e^{At}x(0) + \int_0^t e^{A(t-s)} ds (b+d)$$

$$x(t) = e^{At} + e^{At} \int_0^t e^{-As} ds (b+d)$$

$$\quad \quad \quad \hookrightarrow d(-e^{-As}A^{-1})$$

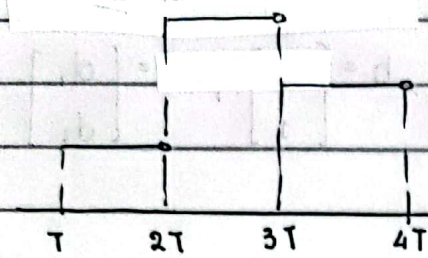
$$x(t) = e^{At}x(0) + e^{At}(\mathbb{I} - e^{-At})A^{-1}(b+d)$$

$$x(t) = e^{At}x(0) + (e^{At} - \mathbb{I})A^{-1}(b+d)$$

$$e^{At} = \begin{bmatrix} e^{2t} & te^{2t} \\ 0 & e^{2t} \end{bmatrix}, \quad e^{At} = \mathcal{L}^{-1}\{(s\mathbb{I} - A)^{-1}\} = \mathcal{L}^{-1}\left\{\begin{bmatrix} s-2 & -1 \\ 0 & s-2 \end{bmatrix}^{-1}\right\} =$$

$$= \mathcal{L}^{-1}\left\{\frac{1}{(s-2)^2} \begin{bmatrix} s-2 & 1 \\ 0 & s-2 \end{bmatrix}\right\} = \mathcal{L}^{-1}\left\{\begin{bmatrix} \frac{1}{s-2} & 1/(s-2)^2 \\ 0 & 1/(s-2) \end{bmatrix}\right\}$$

$$r. \quad u(t) = u_d(kT) \quad \forall t \in [kT, (k+1)T)$$



$$x((k+1)T) = A_d x(kT) + B_d u(kT) + d_d$$

$$y(kT) = C_d x(kT), \quad C_d = C$$

$$\dot{x} = Ax + Bu(t) + d$$

$$x((k+1)T) = \underbrace{e^{A((k+1)T - kT)}}_{A_d} x(kT) + \int_{kT}^{(k+1)T} e^{A((k+1)T - w)} [bu(w) + d] dw$$

$$\left(x(t) = e^{A(t-t_0)} x(t_0) + \int_{t_0}^t e^{A(t-s)} Bu(s) ds \right)$$

$$A_d = e^{AT}$$

$$x((k+1)T) = A_d x(kT) + \int_{kT}^{(k+1)T} e^{A((k+1)T - w)} dw (bu(kT) + 1)$$

$$\int_{kT}^{(k+1)T} e^{A((k+1)T - w)} dw \stackrel{\substack{\lambda = w - kT \\ d\lambda = dw}}{=} \int_0^T e^{A(T - \lambda)} d\lambda =$$

$$A \text{ αυτίστρ.} := e^{AT} (\mathbf{I} - e^{-AT}) A^{-1} = (e^{AT} - \mathbf{I}) A^{-1}$$

$$x((k+1)T) = \underbrace{e^{AT}}_{A_d} x(kT) + \underbrace{(e^{AT} - \mathbf{I}) A^{-1}}_{b_d} bu(kT) + \underbrace{(e^{AT} - \mathbf{I}) A^{-1} d}_{d_d}$$

$$e^{AT} = \begin{bmatrix} e^{2T} & Te^{2T} \\ 0 & e^{2T} \end{bmatrix}$$

(Για να είναι ευστάθης: $e^{2T} < 1 \Rightarrow \delta\epsilon\upsilon \text{ γί\upsilon\epsilon\tau\alpha\iota} \Rightarrow \alpha\epsilon\sigma\tau\alpha\delta\epsilon\varsigma$)

$$\Delta \cdot A_d = 0 \quad y' T = \ln 2$$

$$u_d(kT) = K x(kT), \quad x(kT) \rightarrow 0 \quad \text{σε πεπερασμένο πλήθος βημάτων}$$

$$A_d = e^{A^T} = \begin{bmatrix} e^{2\ln 2} & \ln 2 e^{2\ln 2} \\ 0 & e^{2\ln 2} \end{bmatrix} = \begin{bmatrix} 4 & 4\ln 2 \\ 0 & 4 \end{bmatrix}$$

$$A^{-1} = \begin{bmatrix} 1/2 & -1/4 \\ 0 & 1/2 \end{bmatrix}$$

$$B_d = (e^{A^T} - I) A^{-1} b = \begin{bmatrix} 3 & 4\ln 2 \\ 0 & 3 \end{bmatrix} \begin{bmatrix} 1/2 & -1/4 \\ 0 & 1/2 \end{bmatrix} \begin{bmatrix} 0 \\ 1 \end{bmatrix} = \begin{bmatrix} 2\ln 2 - 3/4 \\ 3/2 \end{bmatrix}$$

$$C_d = \begin{bmatrix} 2\ln 2 - 3/4 & 14\ln 2 - 3 \\ 3/2 & 6 \end{bmatrix} \Rightarrow \det C = 12\ln 2 - \frac{18}{4} - \frac{21\ln 2 + 9}{2} = -9\ln 2 \neq 0$$

(dead-beat ανούριση: πρέπει οι ιδιοτιμές να πάνε στο 0)

$$\det(\lambda I - (A_d + B_d K_d)) = \lambda^2 \Rightarrow \dots$$

$$K_d = [K_{d1} \quad K_{d2}]$$

$$\left(\begin{array}{l} A_d \text{ stable} \rightarrow A \text{ stable} \\ t \in [kT, (k+1)T), \quad \|x(t)\| = \|e^{A_d(t-kT)}\| \|x(kT)\| \end{array} \right) \begin{matrix} \nearrow \leq 0 \\ \rightarrow 0 \end{matrix}$$

$$E. \quad d \neq 0, T = \ln 2, u_d(kT) = K_1 x(kT) + K_2 \sum_{j=0}^{k-1} (y(jT) - y_d^*) \quad (\text{PI ελεγκτής})$$

$$z(kT) = \sum_{j=0}^{k-1} (y(jT) - y_d^*), \quad x[k] := x(kT)$$

$$x[k+1] = A_d x[k] + B_d (K_1 x[k] + K_2 z[k]) + d_d$$

$$z[k+1] = z[k] + y[k] - y_d^*$$

$$\begin{bmatrix} x[k+1] \\ z[k+1] \end{bmatrix} = \begin{bmatrix} A_d + B_d K_1 & B_d K_2 \\ C_d & I \end{bmatrix} \begin{bmatrix} x[k] \\ z[k] \end{bmatrix} + \begin{bmatrix} d_d \\ -y_d^* \end{bmatrix}$$

$$\begin{bmatrix} A_d - B_d K_1 & B_d K_2 \\ C_d & I_p \end{bmatrix} = \begin{bmatrix} A_d & 0 \\ C_d & I_p \end{bmatrix} + \begin{bmatrix} B_d \\ 0 \end{bmatrix} \begin{bmatrix} K_1 & K_2 \end{bmatrix}$$

Πρέπει $\left(\begin{bmatrix} A_d & 0 \\ C_d & I_p \end{bmatrix}, \begin{bmatrix} B_d \\ 0 \end{bmatrix} \right)$ ελέγχσιμο

$$\text{rank} \begin{bmatrix} A_d - \lambda I_n & 0 & B_d \\ C_d & (1-\lambda)I_p & 0 \end{bmatrix} = n+p \quad \forall \lambda \in \mathbb{C}$$

$$(A_d, B_d) \text{ ελέγχσιμο} \Rightarrow \lambda \neq 1 \quad \text{rank} = n+p \quad \checkmark$$

$$\text{Για } \lambda=1, \quad \text{rank} \begin{bmatrix} A_d - I_n & B_d \\ C_d & 0 \end{bmatrix} = n+p$$

$\Rightarrow \dots$ ισχύει

οπότε $\exists K_1, K_2$

$$\begin{bmatrix} \dot{x}^* \\ \dot{z}^* \end{bmatrix} = \begin{bmatrix} A_d + B_d K_1 & B_d K_2 \\ C_d & I \end{bmatrix} \begin{bmatrix} x^* \\ z^* \end{bmatrix} + \begin{bmatrix} d_d \\ -y_d^* \end{bmatrix}$$

$$\dot{z}^* = \underbrace{C_d x^*}_{y^*} + \dot{z}^* - y_d^* \Rightarrow y^* = y_d^*$$

$$\begin{cases} \dot{x}^* = (A_d + B_d K_1) x^* + B_d K_2 z^* + d_d \\ C_d x^* = y_d^* \end{cases}$$

$$P(s) = a_n s^n + a_{n-1} s^{n-1} + a_{n-2} s^{n-2} + \dots + a_0$$

$$\underline{a}_i \leq a_i \leq \bar{a}_i \quad i = 0, 1, \dots, n$$

είτε πάντα $\underline{a}_i > 0$ είτε πάντα $\bar{a}_i < 0$

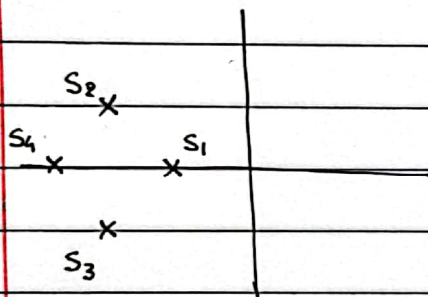
Θεώρημα Kharitonov:

$$P(s; E_1, O_1) = \bar{a}_0 + \bar{a}_1 s + \underline{a}_2 s^2 + \underline{a}_3 s^3 + \bar{a}_4 s^4 + \bar{a}_5 s^5 + \dots$$

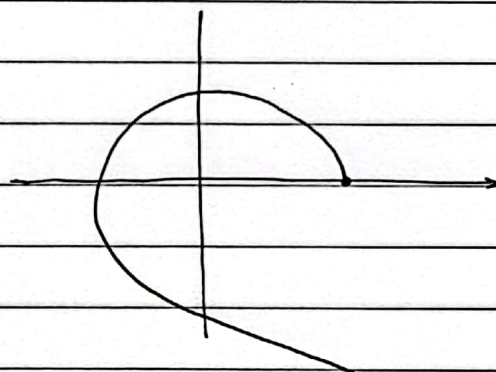
$$P(s; E_1, O_2) = \bar{a}_0 + \underline{a}_1 s + \underline{a}_2 s^2 + \bar{a}_3 s^3 + \bar{a}_4 s^4 + \underline{a}_5 s^5 + \dots$$

$$P(s; E_2, O_1) = \underline{a}_0 + \bar{a}_1 s + \bar{a}_2 s^2 + \underline{a}_3 s^3 + \underline{a}_4 s^4 + \bar{a}_5 s^5 + \dots$$

$$P(s; E_2, O_2) = \underline{a}_0 + \underline{a}_1 s + \bar{a}_2 s^2 + \bar{a}_3 s^3 + \underline{a}_4 s^4 + \underline{a}_5 s^5 + \dots$$



$$P(s) = a_n \prod_{i=1}^n (s - s_i) = a_0 + a_1 s + a_2 s^2 + \dots$$



η φοράς τέμνει

τους άξονες

+

τέμνει εναλλάξ

$$P(j\omega) = (a_0 - a_2 \omega^2 + a_4 \omega^4 - \dots) + j(a_1 \omega - a_3 \omega^3 + a_5 \omega^5 - \dots)$$

$$\frac{1}{2} (P(s) + P(-s)) \rightarrow \text{even}$$

$$\frac{1}{2} (P(s) - P(-s)) \rightarrow \text{odd}$$