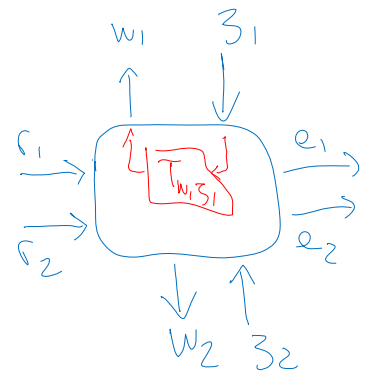
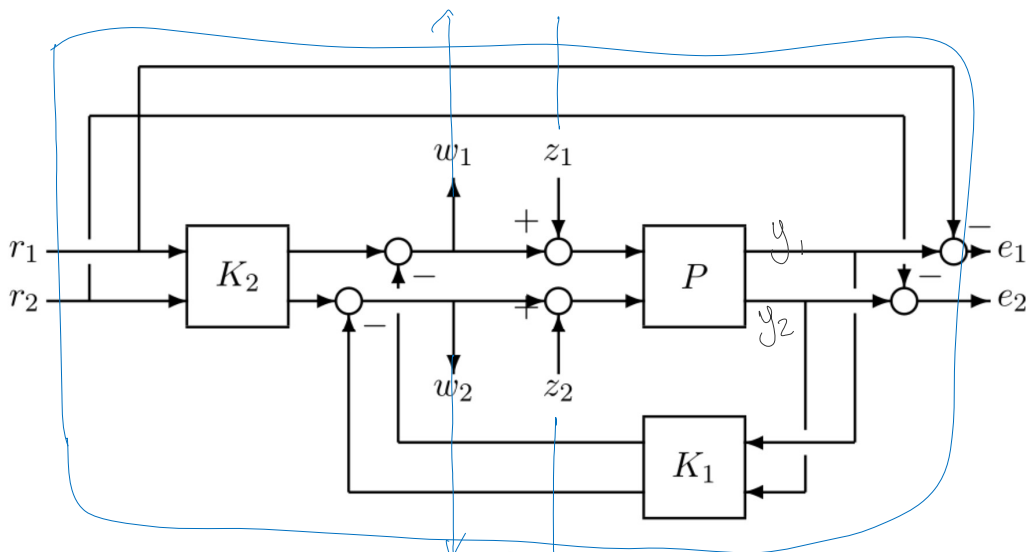


# AA ECE ME 548: Linear Multivariable Control

Prof Burden TA Tinu Spring 2020

today: ☒ ~10 min breakout to discuss - use chat to ask Q's  
- leave breakout room if discussion ends early  
☒ HW2 solution Q's  
☒ HW3 overview & Q's  
☒ lectures on state estimation & observers  
☒ Prof Burden OH

next time: ☐ format / logistics for next week's take-home exam



(b) Analytically show that  $T_{w_1, z_1} = T_{w_2, z_2} = -\frac{1}{s+1}$ .

$$w_1 = \cancel{[K_2]_{1,1}} \cdot r_1 - \underbrace{[K_1]_{1,1}}_1 \cdot y_1$$

$$= [P]_{1,1}(w_1 + z_1) + [P]_{1,2}(w_2 + z_2)$$

$$\dot{x} = Ax \quad y = Cx$$

$$x(t+\Delta) = e^{\Delta \cdot A} \cdot x(t) \Rightarrow y(t+\Delta) = C \cdot e^{\Delta \cdot A} \cdot x(t) \\ = \bar{A} x(t)$$

$$y(t) = C \cdot x(t)$$

$$y(t+\Delta) = C \cdot e^{\Delta \cdot A} x(t)$$

$$\vdots$$

$$y(t+k \cdot \Delta) = C \cdot e^{k \cdot \Delta \cdot A} x(t)$$

$\Updownarrow$

$$y = \underbrace{\begin{bmatrix} C \\ C\bar{A} \\ \vdots \\ C\bar{A}^k \end{bmatrix}}_{\bar{O}_k} x(t)$$

I can solve for  $x(t)$

$$\Leftrightarrow \text{rank } \bar{O}_k = d$$

$$\Leftrightarrow \text{rank } \begin{bmatrix} C \\ C\bar{A} \\ C\bar{A}^2 \\ \vdots \\ C\bar{A}^k \end{bmatrix} = d$$

what happens if  $\text{rank} \begin{bmatrix} C \\ C\bar{A} \\ \vdots \\ C\bar{A}^{d-1} \end{bmatrix} < d$ ?

fact: given  $\dot{x} = Ax$ ,  $y = Cx$ , let  $r = \text{rank} \begin{bmatrix} C \\ CA \\ \vdots \\ CA^{d-1} \end{bmatrix} < d$

there exists invertible  $T$  s.t.

with  $z = Tx \Rightarrow x = T^{-1}z$

we have  $\dot{z} = T\dot{x} = TAx = TAT^{-1}z = \tilde{A}z$

$y = Cx = CT^{-1}z = \tilde{C}z$

and  $\tilde{A} = \begin{bmatrix} \tilde{A}_{11} & 0 \\ \tilde{A}_{21} & \tilde{A}_{22} \end{bmatrix}$ ,  $C = \begin{bmatrix} C_1 & 0 \end{bmatrix}$   
 $\begin{matrix} r & d-r \\ \text{rank } C_1 = r \end{matrix}$