

Contents

1	Introduction	1
	References	5
2	Preliminaries	7
2.1	Linear Algebra and Matrix Theory	7
2.1.1	Vectors and Matrices	7
2.1.2	Linear Spaces	10
2.1.3	Eigenvalues and Eigenvectors	11
2.1.4	Matrix Inversion and Pseudoinverse	12
2.1.5	Vector Norms and Matrix Norms	14
2.1.6	Singular Value Decomposition	15
2.2	Function Spaces and Signals	16
2.2.1	Function Spaces	16
2.2.2	Norms for Signals and Systems	19
2.3	Linear System Theory	22
2.3.1	Linear Systems	22
2.3.2	State Similarity Transformation	23
2.3.3	Stability, Controllability, and Observability	24
2.3.4	Minimal State-Space Realization	26
2.3.5	State-Space Algebra	27
2.3.6	State-Space Formula for Parallel Systems	28
2.3.7	State-Space Formula for Cascaded Systems	29
2.3.8	State-Space Formula for Similarity Transformation	29
2.4	Linear Fractional Transformations and Chain Scattering-Matrix Description	31
	Exercises	34
	References	35
3	Two-Port Networks	37
3.1	One-Port and Two-Port Networks	37
3.2	Impedance and Admittance Parameters (Z and Y Parameters)	40
3.3	Hybrid Parameters (H Parameters)	43

3.4	Transmission Parameters ($ABCD$ Parameters)	44
3.5	Scattering Parameters (S Parameters)	48
3.6	Chain Scattering Parameters (T Parameters).....	51
3.7	Conversions Between ($ABCD$) and (S, T) Matrix Parameters.....	54
3.8	Lossless Networks.....	55
	Exercises	61
	References.....	63
4	Linear Fractional Transformations	65
4.1	Linear Fractional Transformations	65
4.2	Application of LFT in State-Space Realizations.....	69
4.3	Examples of Determining LFT Matrices.....	74
4.3.1	Canonical Form	75
4.3.2	Cascade Form	76
4.3.3	Parallel Form.....	76
4.4	Relationship Between Mason's Gain Formulae and LFT	80
4.5	LFT Description and Feedback Controllers.....	89
4.6	Inner and Co-inner Systems	92
	Exercises	95
	References.....	97
5	Chain Scattering Descriptions	99
5.1	CSD Definitions and Manipulations.....	99
5.2	Cascaded Connection of Two CSD Matrices	103
5.3	Transformation from LFT to CSD Matrix	107
5.4	Transformation from LFT to Cascaded CSDs	110
5.5	Transformation from CSD to LFT matrix	115
5.6	Applications of CSDs in State-Space Realizations	121
5.7	An Application of CSDs to Similarity Transformations.....	127
5.8	State-Space Formulae of CSD Matrix Transformed from LFT Matrix	128
5.9	State-Space Formulae of LFT Matrix Transformed from CSD Matrix.....	131
5.10	Star Connection	134
5.11	J-Lossless and Dual J-Lossless Systems	136
	Exercises	141
	References.....	143
6	Coprime Factorizations	145
6.1	Coprimeness and Coprime Factorization.....	145
6.2	Coprime Factorization over RH_∞	148
6.3	Normalized Coprime Factorization.....	168
	Exercises	170
	References.....	170

7	Algebraic Riccati Equations and Spectral Factorizations	171
7.1	Algebraic Riccati Equations	171
7.2	Similarity Transformation of Hamiltonian Matrices	178
7.3	Lyapunov Equation	183
7.4	State-Space Formulae for Spectral Factorizations	
	Using Coprime Factorization Approach	185
7.4.1	Spectral Factorization Case I	188
7.4.2	Spectral Factorization Case II	198
7.4.3	Spectral Factorization Case III	203
	Exercises	208
	References	209
8	CSD Approach to Stabilization Control and H_2 Optimal Control	211
8.1	Introduction	212
8.2	Characterization of All Stabilizing Controllers	213
8.2.1	Method I: $\text{CSD}_r \rightleftharpoons \text{CSD}_l$ Using a Right CSD Coupled with a Left CSD	214
8.2.2	Method II: $\text{CSD}_l \rightleftharpoons \text{CSD}_r$ Using a Left CSD Coupled with a Right CSD	217
8.3	State-Space Formulae of Stabilizing Controllers	220
8.3.1	Method I: $\text{CSD}_r \rightleftharpoons \text{CSD}_l$	220
8.3.2	Method II: $\text{CSD}_l \rightleftharpoons \text{CSD}_r$	224
8.4	Example of Finding Stabilizing Controllers	227
8.4.1	Method I: $\text{CSD}_r \rightleftharpoons \text{CSD}_l$ Using a Right CSD Associated with a Left CSD	228
8.4.2	Method II: $\text{CSD}_l \rightleftharpoons \text{CSD}_r$ Using a Left CSD Associated with a Right CSD	232
8.5	Stabilization of Special SCC Formulations	235
8.5.1	Disturbance Feedforward (DF) Case	237
8.5.2	Full Information (FI) Case	238
8.5.3	State Feedback (SF) Case	239
8.5.4	Output Estimation (OE) Case	240
8.5.5	Full Control (FC) Case	242
8.5.6	Output Injection (OI) Case	243
8.6	Optimal H_2 Controller	247
8.6.1	Method I: Using a Right CSD Associated with a Left One	248
8.6.2	Method II: Using a Left CSD Associated with a Right One	251
8.7	Example of the Output Feedback H_2 Optimal Control Problem	252
8.7.1	A Numerical Example	254
8.8	Example of LQR Controller	257
8.9	More Numerical Examples	259
8.10	Summary	264
	References	264

9	A CSD Approach to H-Infinity Controller Synthesis	267
9.1	H_∞ Control Problem	268
9.1.1	Method I: $\text{CSD}_r \rightleftharpoons \text{CSD}_l$ Right CSD Coupled with Left CSD	269
9.1.2	Method II: $\text{CSD}_l \rightleftharpoons \text{CSD}_r$ Left CSD Coupled with Right CSD	271
9.2	State-Space Formulae of H_∞ Controllers	274
9.2.1	Method I: $\text{CSD}_r \rightleftharpoons \text{CSD}_l$	274
9.2.2	Method II: $\text{CSD}_l \rightleftharpoons \text{CSD}_r$	278
9.3	H_∞ Solution of Special SCC Formulations	281
9.3.1	Disturbance Feedforward (DF) Problem	281
9.3.2	Full Information (FI) Problem	283
9.3.3	State Feedback (SF) Problem	285
9.3.4	Output Estimation (OE) Problem	285
9.3.5	Full Control (FC) Problem	287
9.3.6	Output Injection (OI) Problem	289
9.4	H_∞ Controller Synthesis with Coprime Factor Perturbations	290
9.4.1	Robust Stabilization Problem of Left Coprime Factorization Case	291
9.4.2	Robust Stabilization Problem of Right Coprime Factor Case	296
	Exercises	301
	References	301
10	Design Examples	303
10.1	Mathematical Models of DC Servomotor	303
10.2	Two-Port Chain Description Approach to Estimation of Mechanical Loading	304
10.3	Coprime Factorization Approach to System Identification	312
10.4	H_∞ Robust Controller Design for Speed Control	314
10.4.1	PDF Controller	314
10.4.2	PDFF Controller	321
10.4.3	Coprime Factorization Approach to Advanced PDFF Controller	323
10.5	Summary	331
	References	331
	Index	333

Robust and Optimal Control

A Two-port Framework Approach

Tsai, M.-C.; Gu, D.-W.

2014, XVI, 336 p. 223 illus., 128 illus. in color. With
online files/update., Hardcover

ISBN: 978-1-4471-6256-8