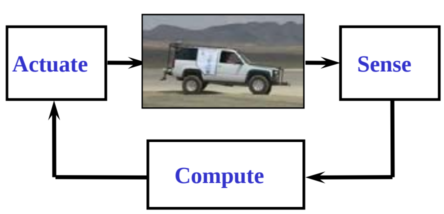
CDS 101/110a: Lecture 1.2
System Modeling

Douglas G. MacMynowski

Goals:
- Define a "model" and its use in answering questions about a system
- Introduce the concepts of state, dynamics, inputs and outputs
- Review modeling using ordinary differential equations (ODEs)

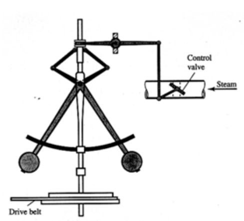
Reading:
- Åström and Murray, *Feedback Systems*, Sections 2.1–2.3, [40 min]
- Advanced: Lewis, *A Mathematical Approach to Classical Control*, Ch. 1

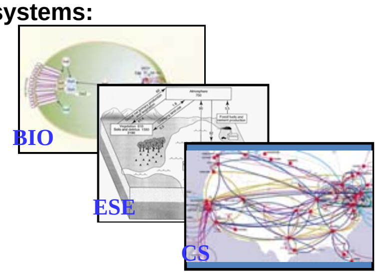
Summary: Introduction to Feedback and Control

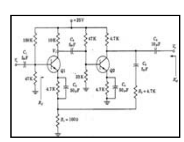


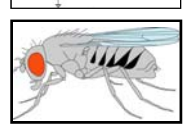
- Control =
  - Sensing + Computation + Actuation
- Feedback Principles
  - Robustness to Uncertainty
  - Design of Dynamics

Many examples of feedback and control in natural & engineered systems:









Model-Based Analysis of Feedback Systems

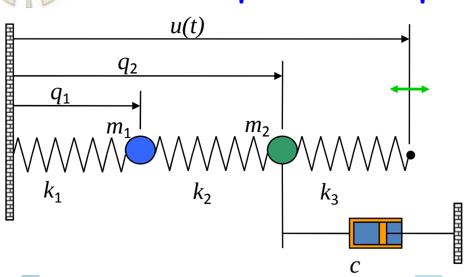
- Analysis and design based on models
  - A model provides a prediction of how the system will behave
  - Feedback can give counter-intuitive behavior; models help sort out what is going on
  - For control design, models don't have to be exact: feedback provides robustness
- The model you use depends on the questions you want to answer
  - A single system may have many models
  - Time and spatial scale must be chosen to suit the questions you want to answer
  - Formulate questions before building a model
- Control-oriented models: inputs and outputs
  - Capture input/output behaviour "sufficiently" well

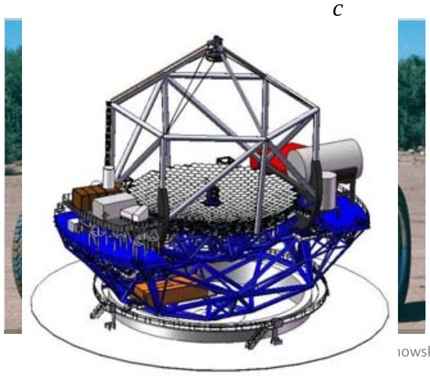
Weather Forecasting

- **Question 1: how much will it rain tomorrow?**
- **Question 2: will it rain in the next 5-10 days?**
- **Question 3: will we have a drought next summer?**

Different questions lead to different models

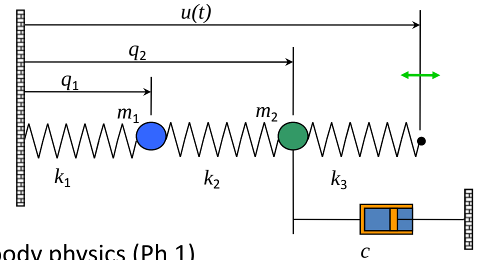
Example #1: Spring Mass System





- Applications
  - Flexible structures (many apps)
  - Suspension systems (eg, "Bob")
  - Molecular and quantum dynamics
- Questions we want to answer
  - How much do masses move as a function of the forcing frequency?
  - What happens if I change the values of the masses?
  - Will Bob fly into the air if I take that speed bump at 25 mph?
- Modeling assumptions
  - Mass, spring, and damper constants are fixed and known
  - Springs satisfy Hooke's law
  - Damper is (linear) viscous force, proportional to velocity

Modeling a Spring Mass System



- Model: rigid body physics (Ph 1)
  - Sum of forces = mass * acceleration
  - Hooke's law: $F = k(x - x_{rest})$
  - Viscous friction: $F = c\, v$

$$m_1 \ddot{q}_1 = k_2(q_2 - q_1) - k_1 q_1$$
$$m_2 \ddot{q}_2 = k_3(u - q_2) - k_2(q_2 - q_1) - c\dot{q}_2$$

Can always re-write in first-order form:

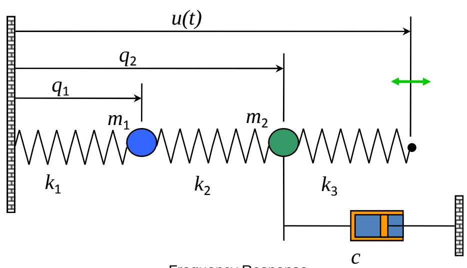
$$\dot{x} = f(x,u) \qquad y = h(x)$$

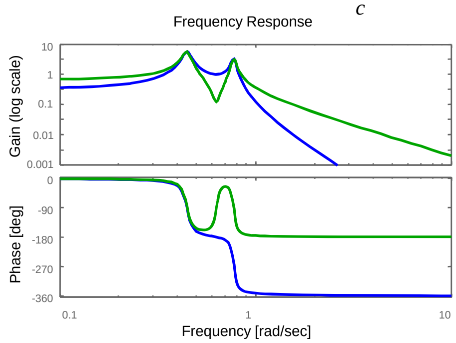
$$\frac{d}{dt}\begin{bmatrix} q_1 \\ q_2 \\ \dot{q}_1 \\ \dot{q}_2 \end{bmatrix} = \begin{bmatrix} \dot{q}_1 \\ \dot{q}_2 \\ \frac{k_2}{m}(q_2 - q_1) - \frac{k_1}{m} q_1 \\ \frac{k_3}{m}(u - q_2) - \frac{k_2}{m}(q_2 - q_1) - \frac{c}{m}\dot{q}_2 \end{bmatrix}$$

$$y = \begin{bmatrix} q_1 \\ q_2 \end{bmatrix}$$

"State space form"

Simulation of a Mass Spring System





- Steady state frequency response
  - Force the system with a sinusoid
  - Plot the "steady state" response, after transients have died out
  - Plot relative magnitude and phase of output versus input (more later)

Matlab simulation (see handout)

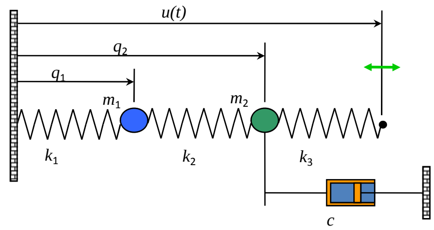
```
function dydt = f(t, y, ...)
u = 0.00315*cos(omega*t);
dydt = [
  y(3);
  y(4);
  -(k1+k2)/m1*y(1) + k2/m1*y(2);
  k2/m2*y(1) - (k2+k3)/m2*y(2)
      - c/m2*y(4) + k3/m2*u ];

[t,y] = ode45(dydt,tspan,y0,[],
k1, k2, k3, m1, m2, c, omega);
```

Modeling Terminology

$$\dot{x} = f(x, u)$$
$$y = h(x, u)$$

- State captures effects of the past
  - independent physical quantities that determines future evolution (absent external excitation)
- Inputs describe external excitation
  - Inputs are extrinsic to the system dynamics (externally specified)
  - Disturbances & control inputs
- Dynamics describes state evolution
  - update rule for system state
  - function of current state and any external inputs
- Outputs describe measured quantities
  - Outputs are function of state and inputs; not independent variables
  - Outputs are often subset of state



Example: spring mass system

- State: position and velocity of each mass: $q_1, q_2, \dot{q}_1, \dot{q}_2$
- Input: position of spring at right end of chain: $u(t)$
- Dynamics: basic mechanics
- Output: measured positions of the masses: q_1, q_2

Modeling Properties

- Choice of state is not unique
  - There may be many choices of variables that can act as the state
  - Trivial example: different choices of units (scaling factor)
  - Less trivial example: sums and differences of the mass positions
- Choice of inputs and outputs depends on point of view
  - Inputs: what factors are external to the model that you are building
  - Inputs in one model might be outputs of another model (eg, the output of a cruise controller provides the input to the vehicle model)
  - Outputs: what physical variables (often states) can you measure
  - Choice of outputs depends on what you can sense and what parts of the component model interact with other component models
- Can also have different types of models
  - Ordinary differential equations for rigid body mechanics
  - Difference equations
  - Finite state machines for manufacturing, Internet, information flow
  - Partial differential equations for fluid flow, solid mechanics, etc

More General Forms of Differential Equations

$$\frac{dx}{dt} = f(x,u) \qquad y = h(x,u)$$

General form

$$\frac{dx}{dt} = Ax + Bu \qquad y = Cx + Du$$

Linear system

$$x \in \mathbb{R}^n,\ u \in \mathbb{R}^p \qquad y \in \mathbb{R}^q$$

x = state; n^{th} order

u = input; in 101/110a, usually p = 1

y = output; in 101/110a, usually q = 1

$$\frac{d^n q}{dt^n} + a_1 \frac{d^{n-1}q}{dt^{n-1}} + \cdots + a_n q = u$$

$$y = b_1 \frac{d^{n-1}q}{dt^{n-1}} + \cdots + b_{n-1}\dot{q} + b_n q$$

$$x = \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_{n-1} \\ x_n \end{bmatrix} = \begin{bmatrix} d^{n-1}q/dt^{n-1} \\ d^{n-2}q/dt^{n-2} \\ \vdots \\ dq/dt \\ q \end{bmatrix}$$

$$\frac{d}{dt}\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ \vdots \\ x_n \end{bmatrix} = \begin{bmatrix} -a_1 & -a_2 & \dots & -a_{n-1} & -a_n \\ 1 & 0 & \dots & 0 & 0 \\ 0 & 1 & & 0 & 0 \\ \vdots & & \ddots & & \vdots \\ 0 & 0 & & 1 & 0 \end{bmatrix} x + \begin{bmatrix} 1 \\ 0 \\ 0 \\ \vdots \\ 0 \end{bmatrix} u$$

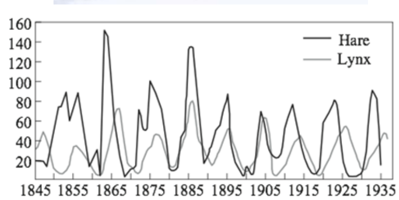
$$y = \begin{bmatrix} b_1 & b_2 & \dots & b_n \end{bmatrix} x$$

Difference Equations

- Difference equations model discrete transitions between continuous variables
  - "Discrete time" description (clocked transitions)
  - New state is function of current state + inputs
  - State is represented as a *continuous* variable

$$x[k+1] = f(x[k], u[k]) \qquad y[k] = h(x[k])$$

Example: predator prey dynamics



Questions we want to answer

- Given the current population of hares and lynxes, what will it be next year?
- If we hunt down lots of lynx in a given year, how will the populations be affected?
- How do long term changes in the amount of food available affect the populations?

Modeling assumptions

- Track population annual (discrete time)
- The predator species is totally dependent on the prey species as its only food supply
- The prey species has an external food supply and no threat to its growth other than the specific predator.

Example #2: Predator Prey Modeling

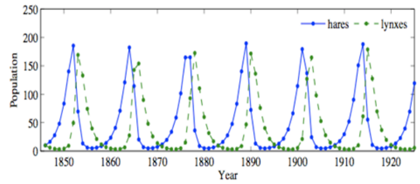
- Discrete Lotka-Volterra model
  - State
    - $H[k]$ # of hares in period k
    - $L[k]$ # of lynx in period k
  - Inputs (optional)
    - $u[k]$ amount of hares' food
  - Outputs: # of hares and lynx
  - Dynamics: Lotka-Volterra eqs

$$H[k+1] = H[k] + b_r(u)H[k] - aL[k]H[k]$$
$$L[k+1] = L[k] + cL[k]H[k] - d_f L[k]$$

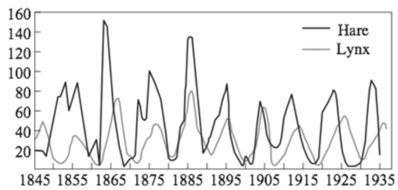
  - Parameters/functions
    - $b_r(u)$ hare birth rate (per period); depends on food supply
    - d_f lynx mortality rate (per period)
    - a, c interaction terms

MATLAB simulation (see handout)

- Discrete time model, "simulated" through repeated addition



Comparison with data



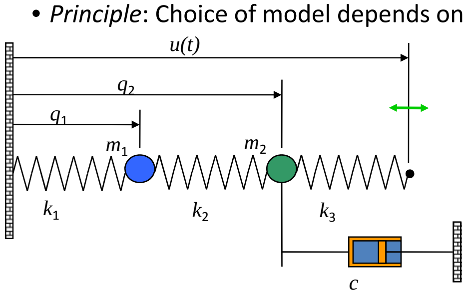
Summary: System Modeling

- Model = state, inputs, outputs, dynamics

$$\frac{dx}{dt} = f(x,u)$$
$$y = h(x)$$

$$x[k+1] = f(x[k], u[k])$$
$$y[k] = h(x[k])$$

- *Principle*: Choice of model depends on the questions you want to answer




```
function dydt = f(t,y, k1, k2,
k3,   m1, m2, c, omega)
u = 0.00315*cos(omega*t);
dydt = [
  y(3);
  y(4);
  -(k1+k2)/m1*y(1) +
      k2/m1*y(2);
  k2/m2*y(1) - (k2+k3)/m2*y(2)
      - b/m2*y(4) + k3/m2*u ];
```

```
% L1_2_modeling.m - Lecture 1.2 MATLAB calculations
% RMM, 6 Oct 03

%
% Spring mass system
%

% Spring mass system parameters
m = 250; m1=m; m2=m;            % masses (all equal)
k = 50; k1=k; k2=k; k3=k;       % spring constants
b = 10;                 % damping
A = 0.00315; omega = 0.75;      % forcing function

% Call ode45 routine (MATLAB 6 format; help ode45 for details)
tspan=[0 500];              % time range for simulation
y0 = [0; 0; 0; 0];          % initial conditions
[t,y] = ode45(@springmass, tspan, y0, [], k1, k2, k3, m1, m2, b, A, omega);

% Plot the input and outputs over entire period
figure(1); clf
plot(t, A*cos(omega*t), t, y(:,1), t, y(:,2));

% Now plot the data for the final 10% (assuming this is long enough...)
endlen = round(length(t)/10);       % last 10% of data record
range = [length(t)-endlen:length(t)]';  % create vector of indices (note ')
tend = t(range);

figure(2); clf
plot(tend, A*cos(omega*tend), tend, y(range,1), tend, y(range,2));

% Compute the relative phase and amplitude of the signals
%
% We make use of the fact that we have a sinusoid in steady state,
% as well as its derivative.  This allows us to compute the magnitude
% of the sinusoid using simple trigonometry ( sin^2 + cos^2 = 1).

u = A*cos(omega*tend); udot = -A*omega*sin(omega*tend);
ampu = mean( sqrt((u .* u) + (udot/omega .* udot/omega)) );
fprintf(1, 'Amplitude = %0.5e cm', ampu*100);

%
% Predator prey system
%

% Set up the initial state
clear H L year
H(1) = 10; L(1) = 10;

% For simplicity, keep track of the year as well
year(1) = 1845;

% Set up parameters (note that c = a in the model below)
```

```
br = 0.6; df = 0.7; a = 0.014;
nperiods = 365;             % simulate each day
duration = 90;              % number of years for simulation

% Iterate the model
for k = 1:duration*nperiods
  b = br;                   % constant food supply
% b = br*(1+0.5*sin(2*pi*k/(4*nperiods)));  % varying food supply (try it!)
  H(k+1) = H(k) + (b*H(k) - a*L(k)*H(k))/nperiods;
  L(k+1) = L(k) + (a*L(k)*H(k) - df*L(k))/nperiods;
  year(k+1) = year(k) + 1/nperiods;

  if (mod(k, nperiods) == 1)
    % Store the annual population
    Ha((k-1)/nperiods + 1) = H(k);
    La((k-1)/nperiods + 1) = L(k);
  end;
end;

% Store the final population
Ha(duration) = H(duration*nperiods+1);
La(duration) = L(duration*nperiods+1);

% Plot the populations of rabbits and foxes versus time
figure(3); clf;
plot(1845 + [1:duration], Ha, '.-', 1845 + [1:duration], La, '.--');

% Adjust the parameters of the plot
axis([1845 1925 0 250]);
xlabel('Year');
ylabel('Population');

% Now reset the parameters to look like we want
lgh = legend(gca, 'hares', 'lynxes', 'Location', 'NorthEast', ...
  'Orientation', 'Horizontal');
legend(lgh, 'boxoff');
```