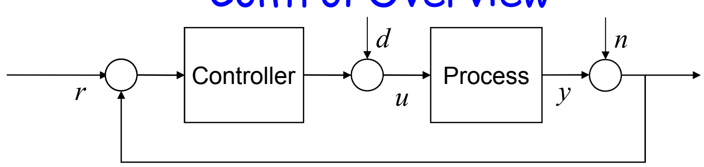
CDS 101/110: Lecture 4-1
State Feedback

Douglas G. MacMartin

- Goals:
  - Define reachability of a control system
  - Give test(s) for reachability of linear systems and apply to examples
  - Describe the design of state feedback controllers for linear systems
- Reading:
  - Åström and Murray, Feedback Systems, Ch 6

Control Overview



- Design controller so that:
  - i) System is stable
  - ii) Performance:
    - Keep close to equilibrium despite disturbances (disturbance rejection)
    - Move system to desired state (track reference)
  - iii) Robust to modeling errors
- Design framework:
  - Use time-domain (state-space) model (week 4-5, and cds112/212)
  - Use frequency-domain information (weeks 5-10)

State space controller design for linear systems

$$\begin{aligned} \dot{x} &= Ax + Bu \quad x \in \mathbb{R}^n,\ x(0) \text{ given} \\ y &= Cx + Du \quad u \in \mathbb{R},\ y \in \mathbb{R} \end{aligned}$$

$$x(T) = e^{AT}x_0 + \int_{\tau=0}^{T} e^{A(T-\tau)}Bu(\tau)\mathrm{d}\tau$$

- **Goal:** find a linear control law $u = -K\,x$ such that the closed loop system

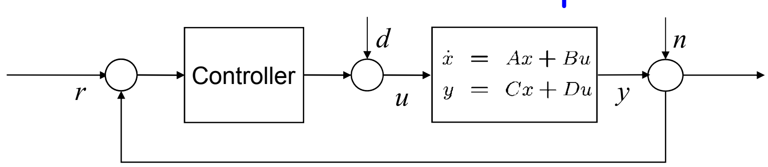
$$\dot{x} = Ax - BKx = (A - BK)x$$

  is stable at x_e=0.

- Remarks
  - Minus sign is by convention
  - Stability based on eigenvalues $\Rightarrow$ use K to make eigenvalues of $(A - BK)$ stable
  - Can also link eigenvalues to *performance* (e.g., initial condition response)
  - Question: when can we place the eigenvalues any place that we want?
  - Requires knowledge of entire state vector… need to estimate *x* from *y*

- **Theorem:** The eigenvalues of $(A - BK)$ can be set to arbitrary values if and only if the pair (A, B) is reachable.

Non-reachable example



1) Can the input *u* affect the dynamics?

e.g.
$$\begin{aligned} \dot{x}_1 &= x_1 + u \\ \dot{x}_2 &= x_2 \end{aligned}$$
$\Rightarrow$ Can't change x_2

Equivalent to asking whether there is a *u* that allows us to <u>*reach*</u> any point in the state-space

$\Rightarrow$ Reachability (today), depends on A, B

$\Rightarrow$ Related to the design of state feedback *u* = -K*x*

2) Does the measurement *y* contain enough information about the system?

e.g.
$$\begin{aligned} \dot{x}_1 &= x_1 \qquad y = x_1 \\ \dot{x}_2 &= x_2 \end{aligned}$$
$\Rightarrow$ Can't measure x_2

$\Rightarrow$ Observability (Wednesday), depends on A, C

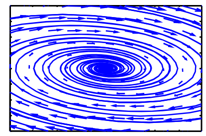
$\Rightarrow$ Related to the design of observers to estimate state from measurement

Control Design Concepts

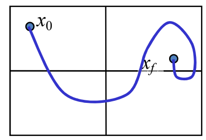
- System description: often single input, single output (MIMO also OK)

$$\begin{aligned} \dot{x} &= f(x,u) \qquad x \in \mathbb{R}^n,\ x(0) \text{ given} \\ y &= h(x,u) \qquad u \in \mathbb{R},\ y \in \mathbb{R} \end{aligned}$$

- Stability: stabilize the system around an equilibrium point
  - Given equilibrium point $x_e \in \mathbb{R}^n$, find control "law" $u = \alpha(x)$ such that $\lim_{t\to\infty} x(t) = x_e \ \forall x(0) \in \mathbb{R}^n$

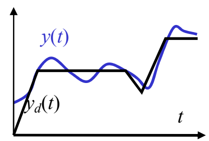


- Reachability: steer the system between two points
  - Given $x_0, x_f \in \mathbb{R}^n$, and any T>0, find an input $u(t)$ such that $\dot{x} = f(x, u(t))$ takes $x(t_0) = x_0 \rightarrow x(T) = x_f$



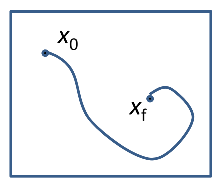
- Tracking: track a given output trajectory
  - Given $y_d(t)$, find $u = \alpha(x,t)$ such that

$$\lim_{t\to\infty} (y(t) - y_d(t)) = 0,\ \forall x(0) \in \mathbb{R}^n$$



Reachability of Input/Output Systems

$$\begin{aligned} \dot{x} &= f(x,u) \qquad x \in \mathbb{R}^n,\ x(0) \text{ given} \\ y &= h(x,u) \qquad u \in \mathbb{R},\ y \in \mathbb{R} \end{aligned}$$



- **Def'n**: An input/output system is *reachable* if for any $x_0, x_f \in \mathbb{R}^n$ and any time $T > 0$ there exists an input $u_{[0,T]} \in \mathbb{R}^n$ such that the solution of the dynamics starting from $x(0)=x_0$ and applying input $u(t)$ gives $x(T)=x_f$.

- Remarks
  - In the definition, x_0 and x_f do not have to be equilibrium points $\Rightarrow$ we don't necessarily stay at x_f after time T.
  - Reachability is defined in terms of states $\Rightarrow$ doesn't depend on output
  - For *linear systems,* can characterize reachability by looking at the general solution:

$$\begin{aligned} \boxed{\dot{x} = Ax + Bu} \\ y = Cx + Du \end{aligned} \qquad x(T) = e^{AT}x_0 + \int_{\tau=0}^{T} e^{A(T-\tau)}Bu(\tau)\mathrm{d}\tau$$

Tests for Reachability

$$\begin{aligned} \dot{x} &= Ax + Bu \quad x \in \mathbb{R}^n,\ x(0) \text{ given} \\ y &= Cx + Du \quad u \in \mathbb{R},\ y \in \mathbb{R} \end{aligned} \qquad x(T) = e^{AT}x_0 + \int_{\tau=0}^{T} e^{A(T-\tau)}Bu(\tau)\mathrm{d}\tau$$

- **Thm**: A linear system is reachable if and only if the $n \times n$ *reachability matrix*
  $$\begin{bmatrix} B & AB & A^2B & \cdots & A^{n-1}B \end{bmatrix}$$
  is full rank.

- Remarks
  - *Very* simple test to apply. In MATLAB, use ctrb(A,B) and check rank w/ det()
  - If this test is satisfied, we say "the pair (A,B) is reachable"
  - Some insight into the proof can be seen by expanding the matrix exponential

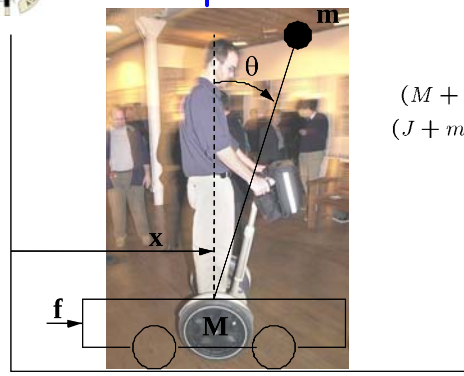
$$\begin{aligned} e^{A(T-\tau)}B &= \left(I + A(T-\tau) + \frac{1}{2}A^2(T-\tau)^2 + \cdots + \frac{1}{(n-1)!}A^{n-1}(T-\tau)^{n-1} + \cdots\right)B \\ &= B + AB(T-\tau) + \frac{1}{2}A^2B(T-\tau)^2 + \cdots + \frac{1}{(n-1)!}A^{n-1}B(T-\tau)^{n-1} + \cdots \end{aligned}$$

  - Test does not give a measure of how much control effort is required
  - Other tests for reachability also exist

Cayley-Hamilton Theorem

- For $x \in \mathbb{R}^n$ (so $A \in \mathbb{R}^{n\times n}$)
- The rank of
  $$\begin{bmatrix} B & AB & A^2B & \cdots & A^{n-1}B \end{bmatrix} \in \mathbb{R}^{n\times n}$$
  is the same as the rank of
  $$\begin{bmatrix} B & AB & A^2B & \cdots & A^{n-1}B & A^nB \end{bmatrix} \in \mathbb{R}^{n\times(n+1)}$$
- Cayley-Hamilton theorem: for any $A \in \mathbb{R}^{n\times n}$
  - the characteristic polynomial is
    $$\det(sI - A) = s^n + a_1 s^{n-1} + \ldots + a_{n-1}s + a_n = 0$$
  - the matrix satisfies
    $$A^n + a_1A^{n-1} + \ldots + a_{n-1}A + a_nI = 0$$
  - which implies that for any $k \geq n$ then $A^k = \sum_{j=0}^{n-1} \alpha_j A^j$
- *If controllability matrix is rank-deficient, adding more terms doesn't help*

Example: Inverted Pendulum on a Cart



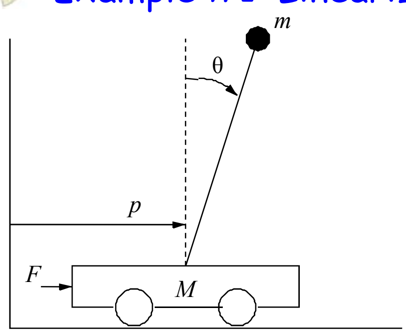
$$(M+m)\ddot{x} + ml\cos\theta\ddot{\theta} = -b\dot{x} + ml\sin\theta\dot{\theta}^2 + f$$
$$(J+ml^2)\ddot{\theta} + ml\cos\theta\ddot{x} = -mgl\sin\theta$$

- State: $x,\ \theta,\ \dot{x},\ \dot{\theta}$
- Input: $u = F$
- Output: $y = x$
- Linearize according to previous formula around θ = 0

$$\frac{d}{dt}\begin{bmatrix} x \\ \theta \\ \dot{x} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & \dfrac{m^2gl^2}{J(M+m)+Mml^2} & \dfrac{-(J+ml^2)b}{J(M+m)+Mml^2} & 0 \\ 0 & \dfrac{mgl(M+m)}{J(M+m)+Mml^2} & \dfrac{-mlb}{J(M+m)+Mml^2} & 0 \end{bmatrix} x + \begin{bmatrix} 0 \\ 0 \\ \dfrac{J+ml^2}{J(M+m)+Mml^2} \\ \dfrac{ml}{J(M+m)+Mml^2} \end{bmatrix} u$$

$$y = \begin{bmatrix} 1 & 0 & 0 & 0 \end{bmatrix} x$$

Example #1: Linearized pendulum on a cart



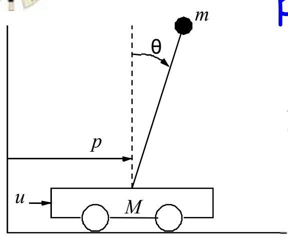
- Question: can we locally control the position of the cart by proper choice of input?
- Approach: look at the linearization around the upright position (good approximation to the full dynamics if θ remains small)

$$\frac{d}{dt}\begin{bmatrix} p \\ \theta \\ \dot{p} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & \frac{m^2l^2g}{M_tJ_t - m^2l^2} & \frac{-cJ_t}{M_tJ_t - m^2l^2} & \frac{-\gamma J_t lm}{M_tJ_t - m^2l^2} \\ 0 & \frac{M_tmgl}{M_tJ_t - m^2l^2} & \frac{-clm}{M_tJ_t - m^2l^2} & \frac{-\gamma M_t}{M_tJ_t - m^2l^2} \end{bmatrix} \begin{bmatrix} p \\ \theta \\ \dot{p} \\ \dot{\theta} \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ \frac{J_t}{M_tJ_t - m^2l^2} \\ \frac{lm}{M_tJ_t - m^2l^2} \end{bmatrix} u$$

$$y = \begin{bmatrix} 1 & 0 & 0 & 0 \end{bmatrix} x,$$

Note: equations on previous slide did not include damping on angular rate

Example #1, con't: Linearized pendulum on a cart



$$\frac{d}{dt}\begin{bmatrix} p \\ \theta \\ \dot{p} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & \frac{m^2 l^2 g}{\mu} & \overset{0}{\cancel{\frac{-cJ_t}{\mu}}} & \overset{0}{\cancel{\frac{-\gamma J_t lm}{\mu}}} \\ 0 & \frac{M_t m g l}{\mu} & \overset{0}{\cancel{\frac{-clm}{\mu}}} & \overset{0}{\cancel{\frac{-\gamma M_t}{\mu}}} \end{bmatrix} \begin{bmatrix} p \\ \theta \\ \dot{p} \\ \dot{\theta} \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ \frac{J_t}{\mu} \\ \frac{lm}{\mu} \end{bmatrix} u$$

$$\mu = M_t J_t - m^2 l^2$$

- Simplify by setting c, γ = 0

- Reachability matrix

$$W_r = \begin{array}{cccc} \left[\begin{matrix} 0 \\ 0 \\ \frac{J_t}{\mu} \\ \frac{lm}{\mu} \end{matrix} \right. & \begin{matrix} \frac{J_t}{\mu} \\ \frac{lm}{\mu} \\ 0 \\ 0 \end{matrix} & \begin{matrix} 0 \\ 0 \\ \frac{gl^3m^3}{\mu^2} \\ \frac{gl^2m^2(m+M)}{\mu^2} \end{matrix} & \left. \begin{matrix} \frac{gl^3m^3}{\mu^2} \\ \frac{gl^2m^2(m+M)}{\mu^2} \\ 0 \\ 0 \end{matrix} \right] \\ B & AB & A^2B & A^3B \end{array}$$

- Full rank as long as constants are such that columns 1 and 3 are not multiples of each other
- Reachable as long as $\det(W_r) = \frac{g^2 \ell^4 m^4}{\mu^4} \neq 0$
- Can "steer" linearization between points by proper choice of input

Control Design Concepts

- System description: often single input, single output (MIMO also OK)

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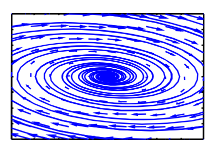

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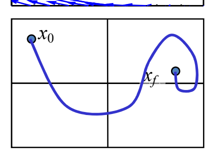
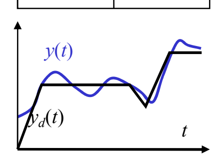
- Reachability: steer the system between two points
  - Given $x_0, x_f \in \mathbb{R}^n$, find an input $u(t)$ such that $\dot{x} = f(x, u(t))$ takes $x(t_0) = x_0 \to x(T) = x_f$



- Tracking: track a given output trajectory
  - Given $y_d(t)$, find $u = \alpha(x,t)$ such that

$$\lim_{t\to\infty} (y(t) - y_d(t)) = 0,\ \forall x(0) \in \mathbb{R}^n$$



Reachable Canonical Form and State Feedback

- If the system is reachable, then there exists a transformation $z = Tx$ such that:

$$\dot{z} = \begin{bmatrix} -a_1 & -a_2 & -a_3 & \cdots & -a_n \\ 1 & 0 & 0 & \cdots & 0 \\ 0 & 1 & 0\cdots & 0 & \\ \vdots & & \ddots & \ddots & \vdots \\ 0 & & & 1 & 0 \end{bmatrix} z + \begin{bmatrix} 1 \\ 0 \\ 0 \\ \vdots \\ 0 \end{bmatrix} u$$

- (Check [B AB A^2B … A^{n-1}B]… is this system reachable?)
- Characteristic polynomial is: $\lambda(s) = s^n + a_1 s^{n-1} + \cdots + a_{n-1}s + a_n$
- Choose state feedback: $u = -Kz = -\begin{bmatrix} k_1 & k_2 & \cdots & k_n \end{bmatrix} z$
- Then closed-loop system is:

$$\dot{z} = \begin{bmatrix} -a_1 - k_1 & -a_2 - k_2 & -a_3 - k_3 & \cdots & -a_n - k_n \\ 1 & 0 & 0 & \cdots & 0 \\ 0 & 1 & 0\cdots & 0 & \\ \vdots & & \ddots & \ddots & \vdots \\ 0 & & & 1 & 0 \end{bmatrix} z$$

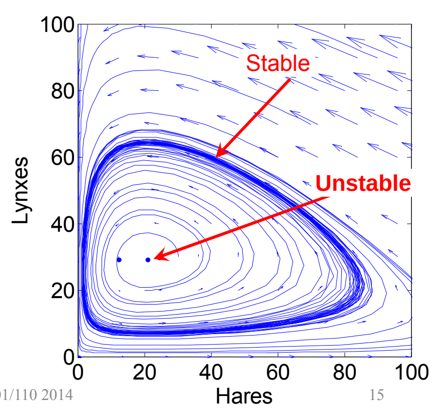
Example #2: Predator prey

$$\begin{aligned} \frac{dH}{dt} &= rH\left(1 - \frac{H}{k_c}\right) - \frac{aHL}{c+H}, \qquad H \geq 0 \\ \frac{dL}{dt} &= b\frac{aHL}{c+H} - dL, \qquad L \geq 0 \end{aligned}$$

- Controlled dynamics: modulate food supply

$$\begin{aligned} \frac{dH}{dt} &= (r+u)H\left(1 - \frac{H}{k_c}\right) - \frac{aHL}{c+H} \\ \frac{dL}{dt} &= b\frac{aHL}{c+H} - dL, \end{aligned}$$

- Q1: can we move from some initial population of lynxes and hares to a specified one in time T by modulation of the food supply?
- Q2: can we stabilize the population around the desired equilibrium point
- Approach: try to answer this question locally, around the natural equilibrium point



Example #2: Problem setup

- Equilibrium point calculation

$$\frac{\mathrm{d}H}{\mathrm{d}t} = (r+u)H\left(1-\frac{H}{kc}\right) - \frac{aHL}{c+H}$$
$$\frac{\mathrm{d}L}{\mathrm{d}t} = b\frac{aHL}{c+H} - dL,$$

  – x_e = (20.5,29.5), u_e = 0
- Linearization
  – Compute linearization around equil. point, x_e:

$$A = \left.\frac{\partial f}{\partial x}\right|_{x_e,u_e} \qquad B = \left.\frac{\partial f}{\partial u}\right|_{x_e,u_e}$$

  – Redefine local variables: $z = x - x_e$ $v = u - u_e$

$$\frac{d}{dt}(x - x_e) = A(x-x_e) + B(u-u_e)$$

$$\frac{d}{dt}\begin{bmatrix} z_1 \\ z_2 \end{bmatrix} = \begin{bmatrix} r - \frac{2H_0 r}{k} - \frac{aL_0}{c+H_0} + \frac{aL_0H_0}{(c+H_0)^2} & -\frac{aH_0}{c+H_0} \\ baL_0\left(\frac{1}{c+H_0} - \frac{H_0}{(c+H_0)^2}\right) & ba\frac{H_0}{c+H_0} - d \end{bmatrix}\begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + \begin{bmatrix} H_0\left(1 - \frac{H_0}{k}\right) \\ 0 \end{bmatrix} v$$

  – Reachable? YES, if $ba \neq 0$ (check [B AB]) $\Rightarrow$ can locally steer to any point

```
% Compute the equil point
% predprey.m contains dynamics
f = inline('predprey(0,x)');
xeq = fsolve(f, [20, 30]);

% Compute linearization
A = [...];
B = [H0*(1 - H0/K); 0];
p = [-1;-2];
K = place(A,B,p)
```


Example #2: Stabilization via eigenvalue assignment

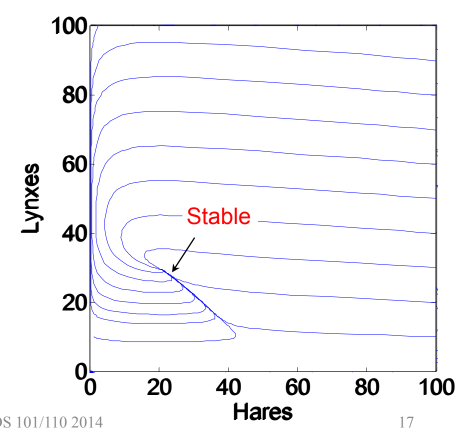
$$\frac{d}{dt}\begin{bmatrix} z_1 \\ z_2 \end{bmatrix} = \begin{bmatrix} r - \frac{2H_0 r}{k} - \frac{aL_0}{c+H_0} + \frac{aL_0H_0}{(c+H_0)^2} & -\frac{aH_0}{c+H_0} \\ baL_0\left(\frac{1}{c+H_0} - \frac{H_0}{(c+H_0)^2}\right) & ba\frac{H_0}{c+H_0} - d \end{bmatrix}\begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + \begin{bmatrix} H_0\left(1 - \frac{H_0}{k}\right) \\ 0 \end{bmatrix} v$$

- Control design:

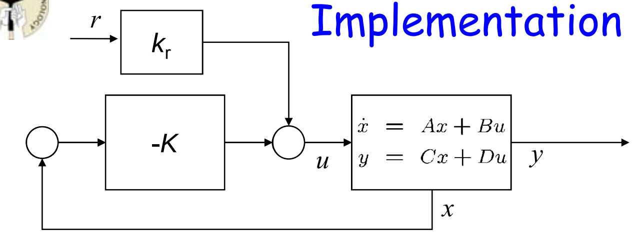
$$v = -Kz + k_r r$$
$$u = u_e - K(x - x_e) + k_r(r - y_e)$$

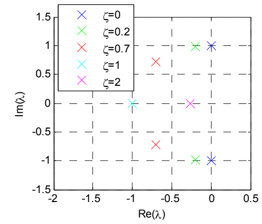
- Place poles at stable values
  – Choose λ = -1, -2
  – K = place(A, B, [-1; -2]);
- Modify NL dynamics to include control

$$\frac{\mathrm{d}H}{\mathrm{d}t} = (r+u)H\left(1-\frac{H}{kc}\right) - \frac{aHL}{c+H}$$
$$\frac{\mathrm{d}L}{\mathrm{d}t} = b\frac{aHL}{c+H} - dL,$$



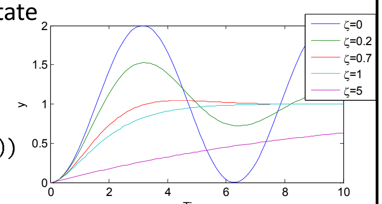
Implementation





Remarks:

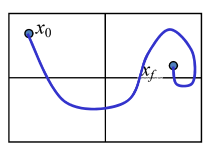
1. In practice, don't always have access to full state
   → estimate state from measurement y
2. What to pick for eigenvalues?
   - For each eigenvalue $\lambda_i = \sigma_i + j\omega_i$, get contribution of the form $y_i(t) = e^{\sigma t}(a\sin(\omega t) + b\cos(\omega t))$
   - Faster response will require more control effort
   - Optimal control: LQR (in text, CDS 110b)

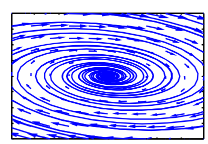


3. How to obtain desired tracking response so that $y_{ss} = r$ for some reference r?
   - Choose $u = -Kx + k_r r$
   - Steady state (if D=0): $y = Cx = C(A - BK)^{-1}Bk_r r \Rightarrow k_r = \mathrm{inv}[C(A - BK)^{-1}B]$

Summary: Reachability and State Space Feedback

$$\begin{aligned}\dot{x} &= Ax + Bu \\ y &= Cx + Du\end{aligned}$$





$$\begin{bmatrix} B & AB & A^2B & \cdots & A^{n-1}B \end{bmatrix}$$

$$u = -Kx + k_r r$$

- Key concepts
  - Reachability: find u s.t. $x_0 \rightarrow x_f$
  - Reachability rank test for linear systems
  - State feedback to assign eigen-values