CDS 101/110a: Lecture 1.1
Introduction to Feedback & Control

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29 September 2008

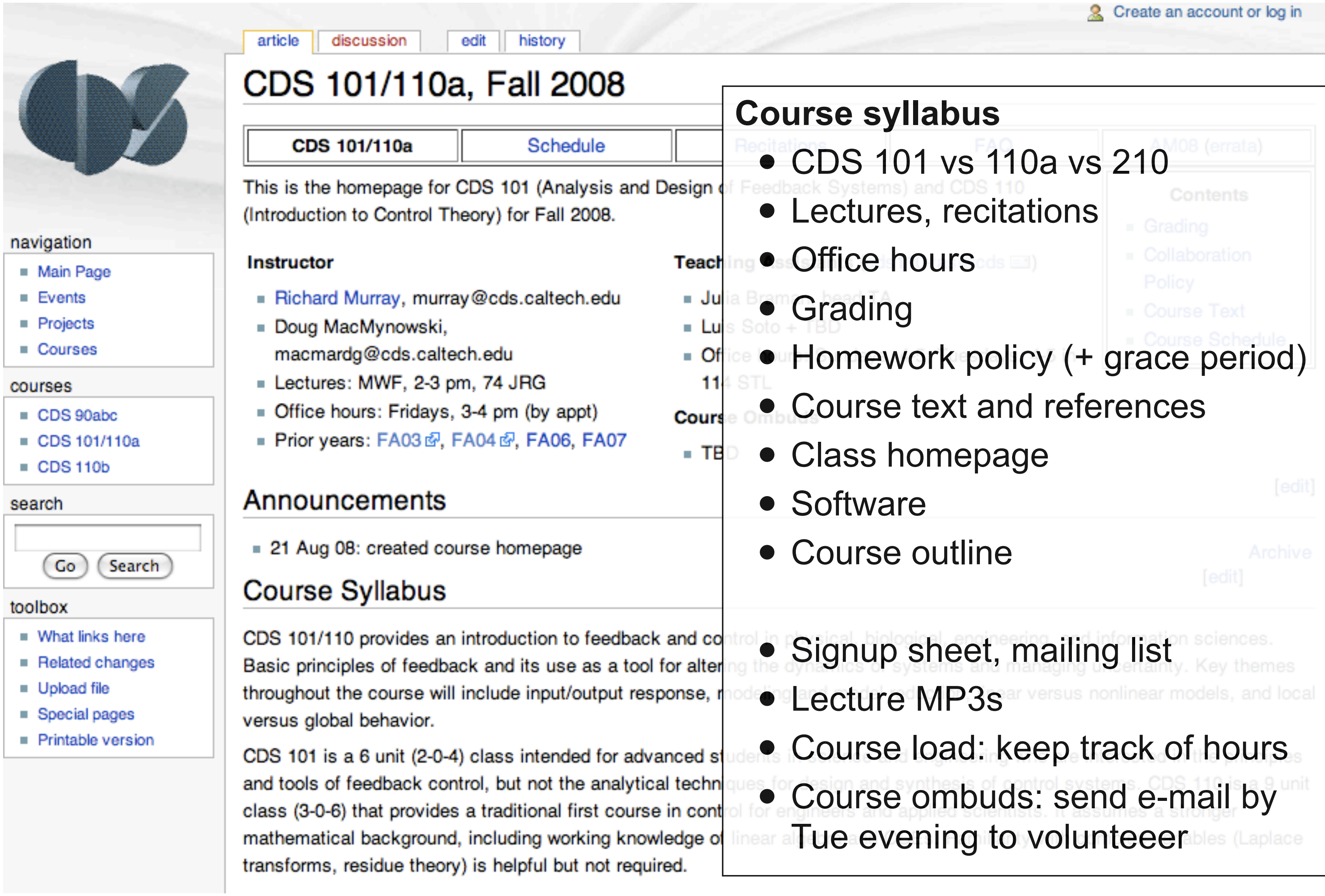
Goals:

- Give an overview of CDS 101/110/210: course structure & administration
- Define feedback systems and learn how to recognize main features
- Describe what control systems do and the primary principles of feedback

Reading:

- Åström and Murray, *Feedback Systems: An Introduction for Scientists and Engineers*, Chapter 1 [30 min]

Course Administration



Course syllabus

- CDS 101 vs 110a vs 210
- Lectures, recitations
- Office hours
- Grading
- Homework policy (+ grace period)
- Course text and references
- Class homepage
- Software
- Course outline

- Signup sheet, mailing list
- Lecture MP3s
- Course load: keep track of hours
- Course ombuds: send e-mail by Tue evening to volunteeer

CDS 101/110 Instructional Staff

Lecturer: Richard Murray (CDS)

- Professor of Control & Dynamical Systems
- Research in networked control systems, autonomous systems, biological systems

Lecturer Doug MacMynowski (CDS)

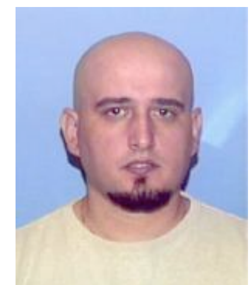
- Senior Research Associated in CDS
- Research in climate modeling, fluid dynamics, and telescope control

Head TA: Julia Braman

- ME, fault-toleran control and verification

TAs

- Shuo Han (EE) - bio-inspired flight control
- Gentian Buzi (CDS) - biological dynamics
- Max Merfeld (ME) - undergraduate
- Luis Soto (CDS) - ecosystems



Mud Cards

Mud cards

- 3 x 5 cards passed out at beginning of each lecture
- Describe "muddiest" part of the lecture (or other questions)
- Turn in cards at end of class
- Responses posted on FAQ list by 8 pm on the day of the lecture (make sure to look!)

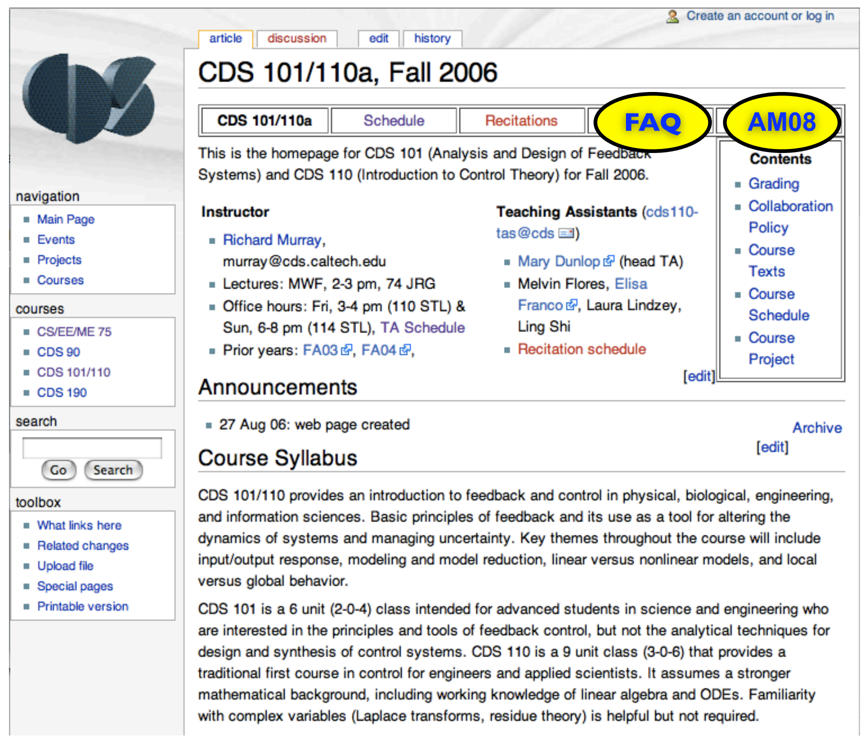
What does closed loop mean? You used this term without defining it.

Class FAQ list

- Responses to mud cards and other frequently asked questions in the class
- Previous FAQs available on AM wiki

AMwiki

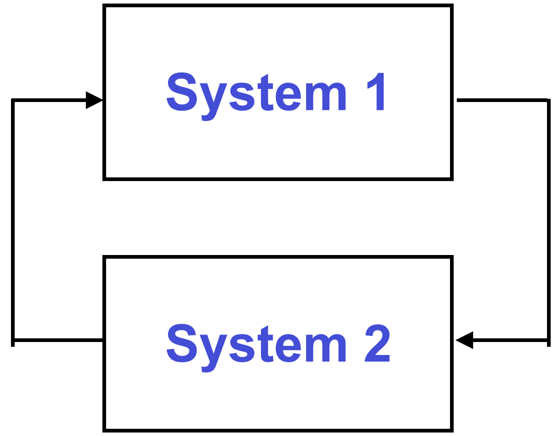
- Additional exercises, FAQs, examples



What is Feedback?

Merriam Webster:

the return to the input of a part of the output of a machine, system, or process (as for producing changes in an electronic circuit that improve performance or in an automatic control device that provide self-corrective action) [1920]

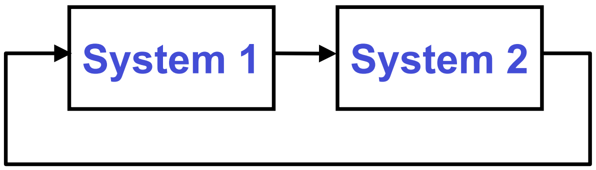


Feedback = mutual interconnection of two (or more) systems

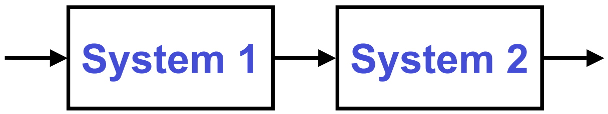
- System 1 affects system 2
- System 2 affects system 1
- Cause and effect is tricky; systems are mutually dependent

Feedback is ubiquitous in natural and engineered systems

Terminology



Closed Loop

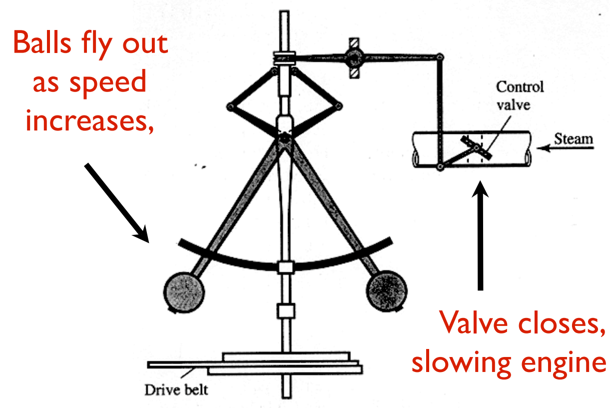


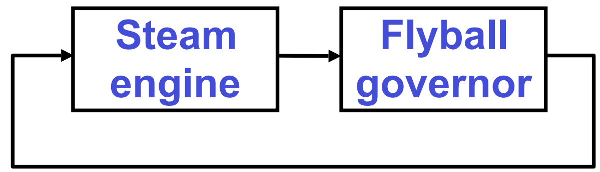
Open Loop

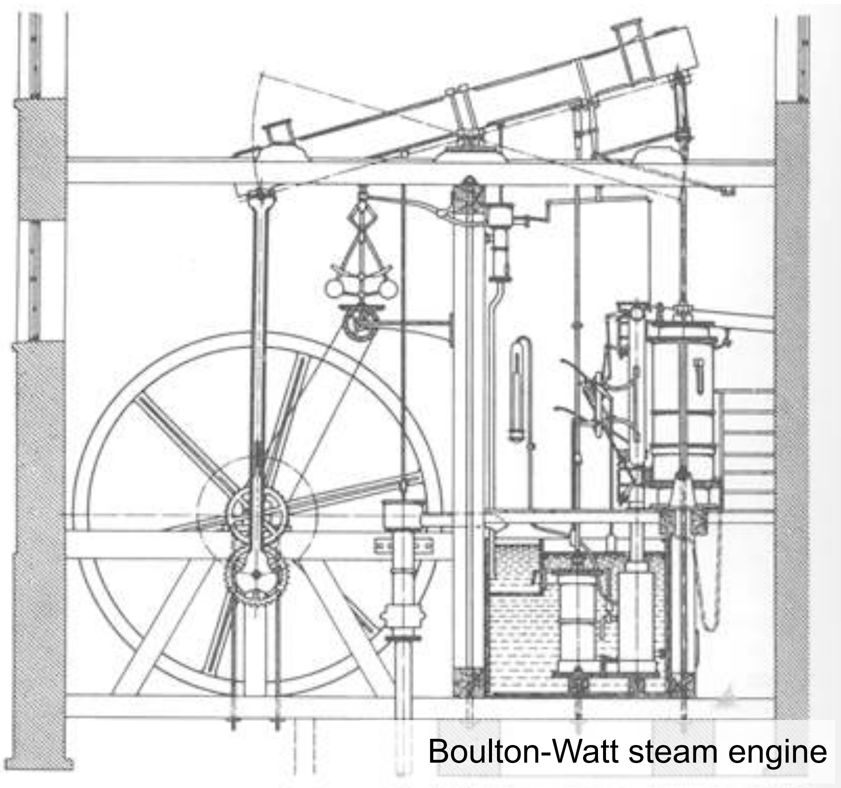
Example #1: Flyball Governor

"Flyball" Governor (1788)

- Regulate speed of steam engine
- Reduce effects of variations in load (disturbance rejection)
- Major advance of industrial revolution







Boulton-Watt steam engine

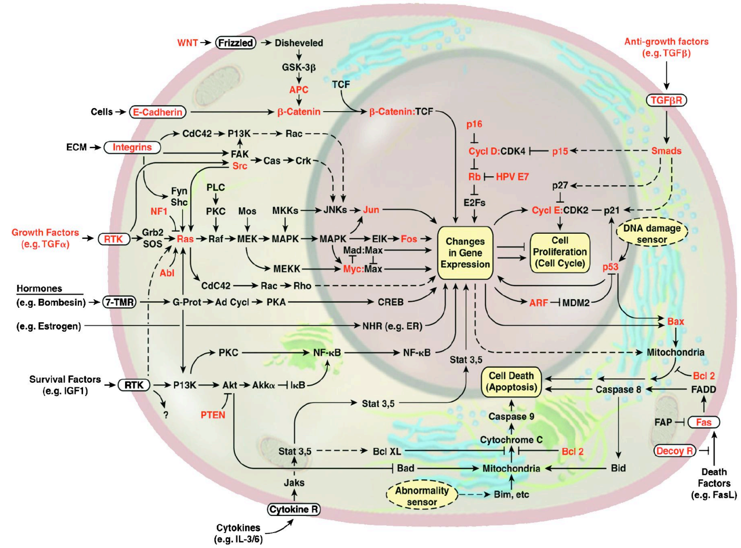
Courtesy Eric Klavins, U. Washington (2008)

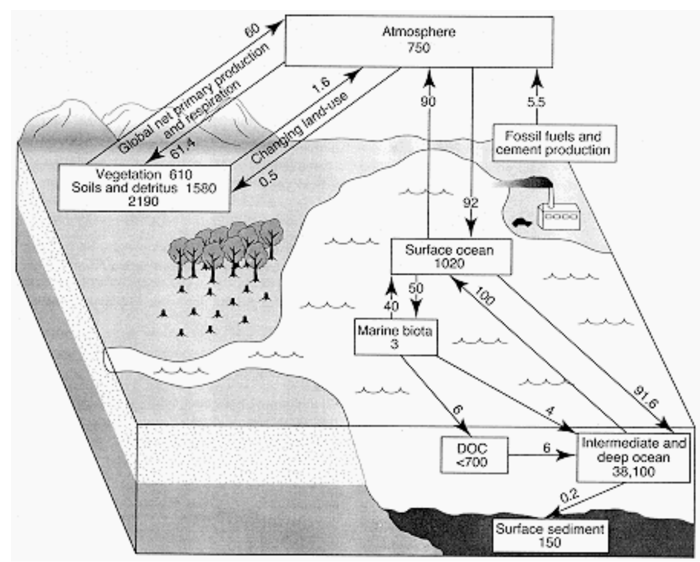
Other Examples of Feedback

Biological Systems
- Physiological regulation (homeostasis)
- Bio-molecular regulatory networks

Environmental Systems
- Microbial ecosystems
- Global carbon cycle

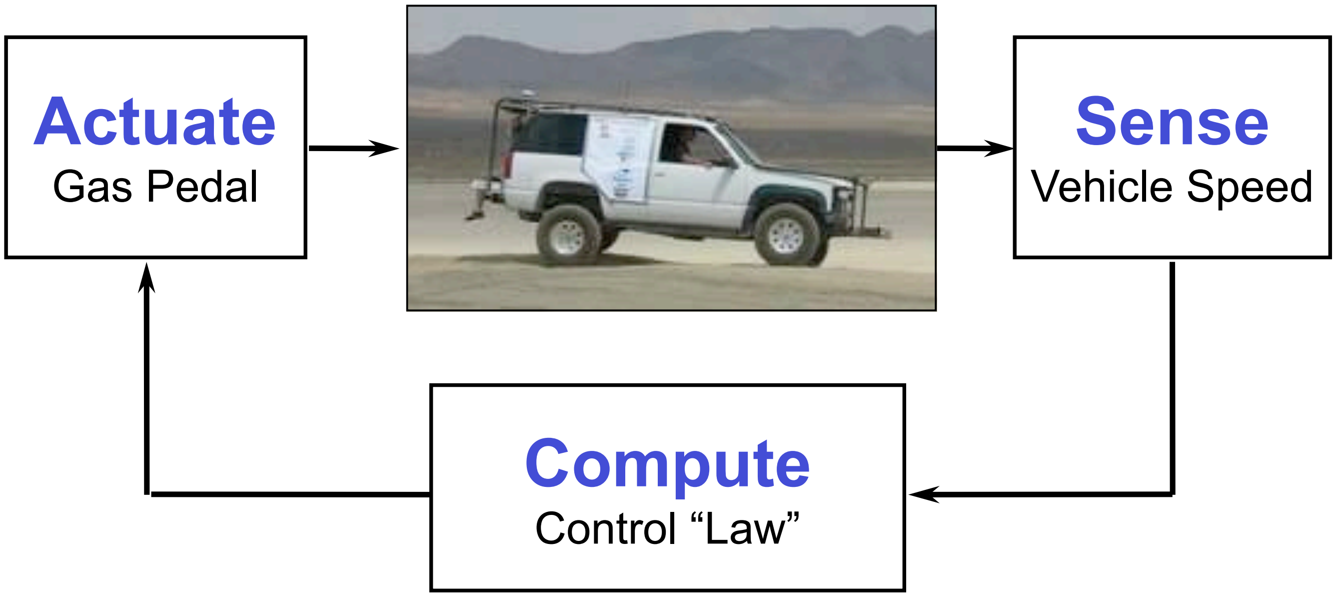
Financial Systems
- Markets and exchanges
- Supply and service chains





Control = Sensing + Computation + Actuation

In Feedback "Loop"



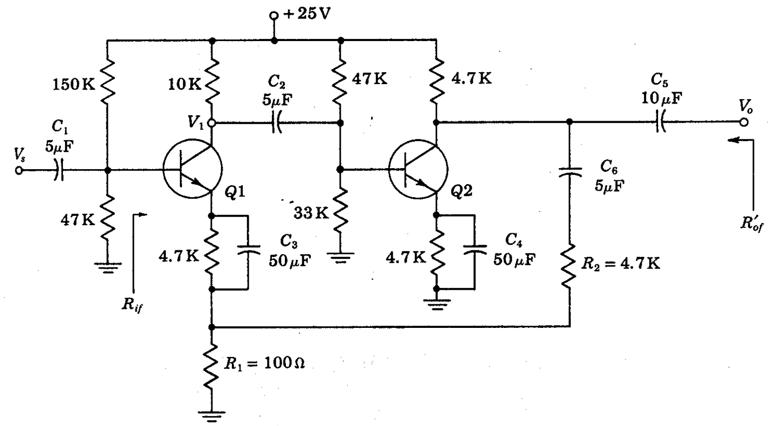
Goals

- Stability: system maintains desired operating point (hold steady speed)
- Performance: system responds rapidly to changes (accelerate to 6 m/sec)
- Robustness: system tolerates perturbations in dynamics (mass, drag, etc)

Two Main Principles of Feedback

Robustness to Uncertainty through Feedback

- Feedback allows high performance in the presence of uncertainty
- Example: repeatable performance of amplifiers with 5X component variation
- Key idea: accurate *sensing* to compare actual to desired, correction through *computation* and *actuation*



Design of Dynamics through Feedback

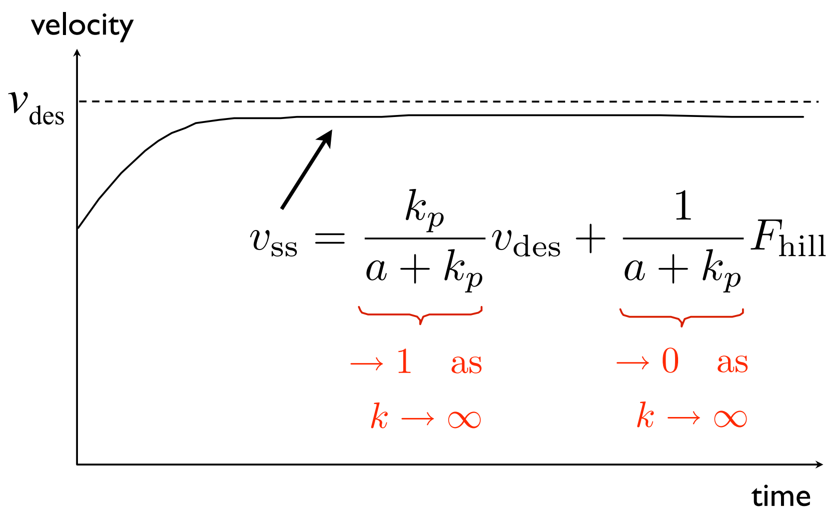
- Feedback allows the dynamics (behavior) of a system to be modified
- Example: stability augmentation for highly agile, unstable aircraft
- Key idea: interconnection gives *closed loop* that modifies natural behavior

X-29 experimental aircraft (NASA)

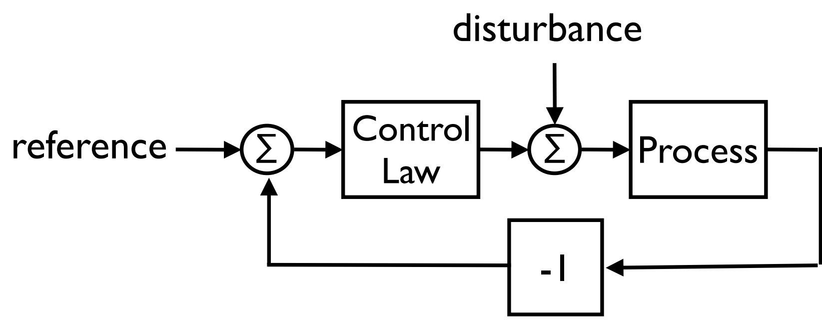
Example #2: Speed Control

$$m\dot{v} = -av + F_{\text{eng}} + F_{\text{hill}}$$

$$F_{\text{eng}} = k_p(v_{\text{des}} - v)$$



$$v_{ss} = \underbrace{\frac{k_p}{a + k_p}}_{\to 1 \text{ as } k \to \infty} v_{\text{des}} + \underbrace{\frac{1}{a + k_p}}_{\to 0 \text{ as } k \to \infty} F_{\text{hill}}$$



Stability/performance

- Steady state velocity approaches desired velocity as $k \to \infty$
- Smooth response; no overshoot or oscillations

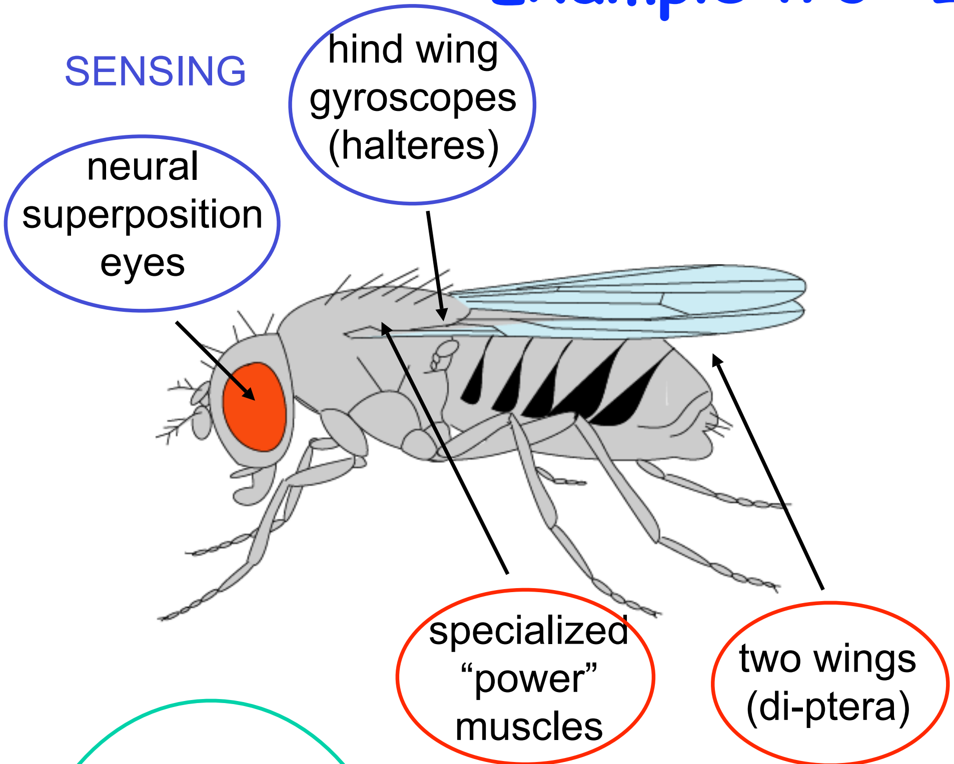
Disturbance rejection

- Effect of disturbances (eg, hills) approaches zero as $k \to \infty$

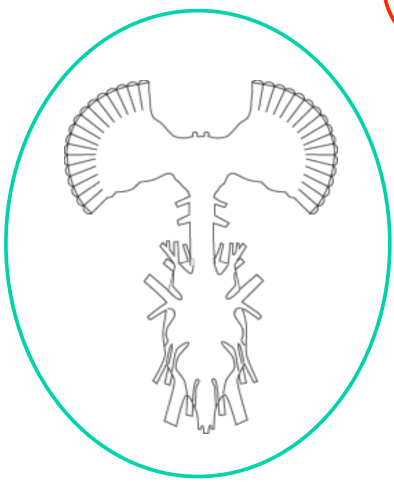
Robustness

- Results don't depend on the specific values of *a, m* or k_p, for k_p sufficiently large

Example #3: Insect Flight

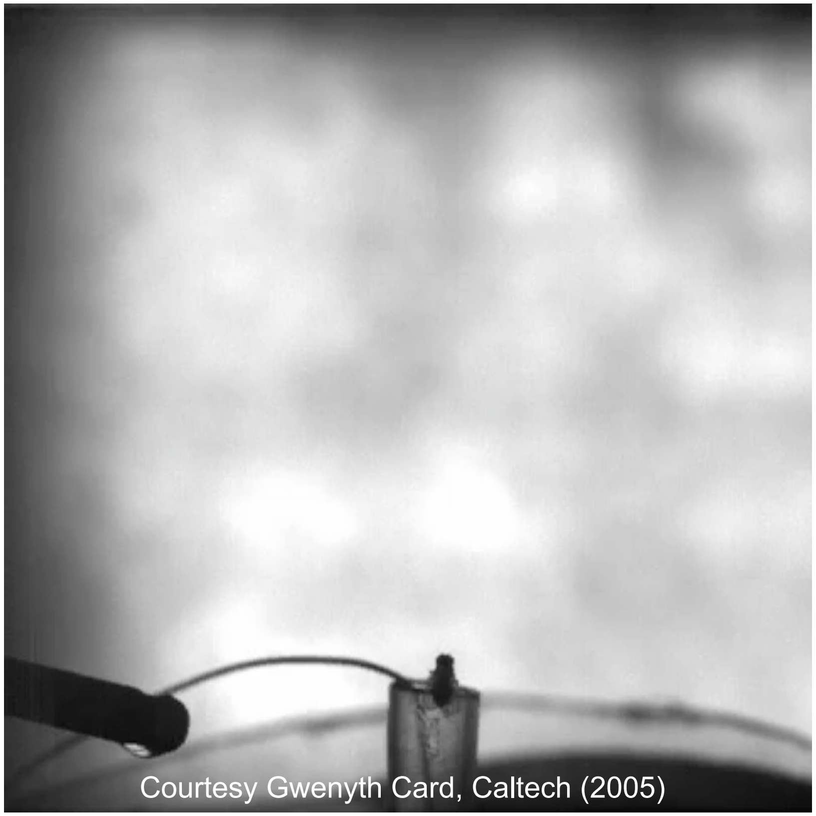


ACTUATION



COMPUTATION

~500,000 neurons



Courtesy Gwenyth Card, Caltech (2005)

More information:

- M. H. Dickinson, Solving the mystery of insect flight, *Scientific American,* June 2001

Control Tools

Modeling

- Input/output representations for subsystems + interconnection rules
- System identification theory and algorithms
- Theory and algorithms for reduced order modeling + model reduction

Analysis

- Stability of feedback systems, including robustness “margins”
- Performance of input/output systems (disturbance rejection, robustness)

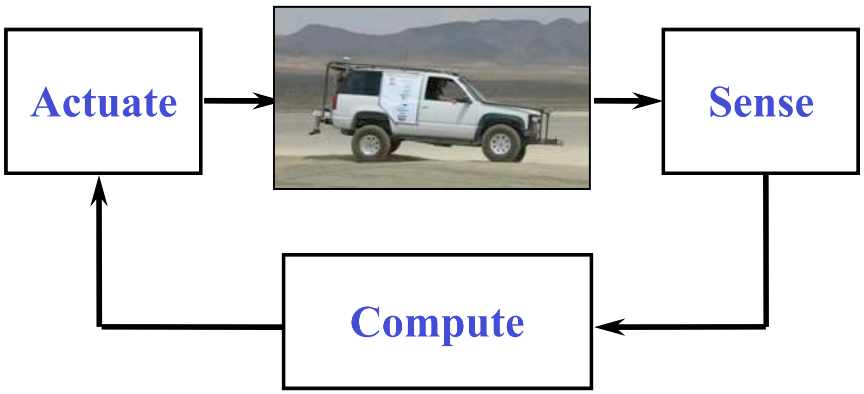
Synthesis

- Constructive tools for design of feedback systems
- Constructive tools for signal processing and estimation (Kalman filters)

MATLAB Toolboxes

- SIMULINK
- Control System
- Neural Network
- Data Acquisition
- Optimization
- Fuzzy Logic
- Robust Control
- Instrument Control
- Signal Processing
- LMI Control
- Statistics
- Model Predictive Control
- System Identification
- μ-Analysis and Synthesis
- Systems biology (SBML)

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: