CDS 101/110a: Lecture 7-1
Loop Analysis of Feedback Systems

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9 November 2015

Goals:

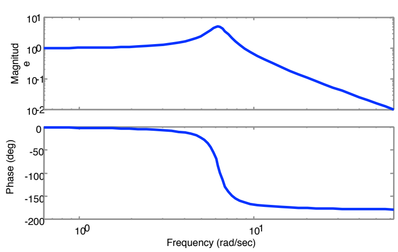
- Show how to compute closed loop stability from open loop properties
- Describe the Nyquist stability criterion for stability of feedback systems
- Define gain and phase margin and determine it from Nyquist and Bode plots

Reading:

- Åström and Murray, Feedback Systems, Ch 10

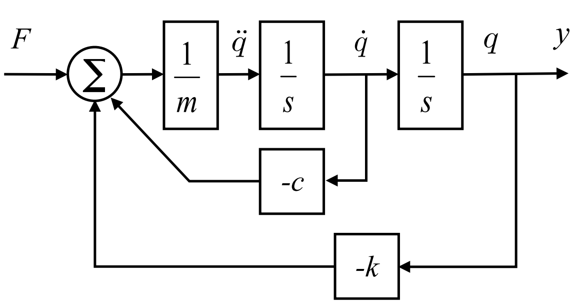
Review From Last Week

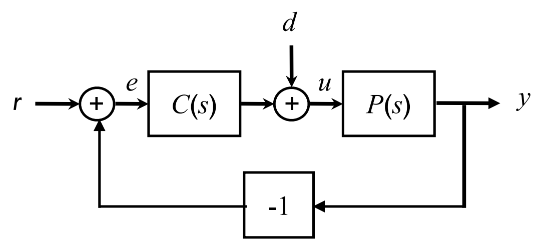
$$u = A\sin(\omega t) \rightarrow \begin{array}{c} \dot{x} = Ax + Bu \\ y = Cx + Du \\ x(0) = 0 \end{array} \rightarrow y_{ss} = A \cdot |G(i\omega)| \times \sin(\omega t + \arg G(i\omega))$$



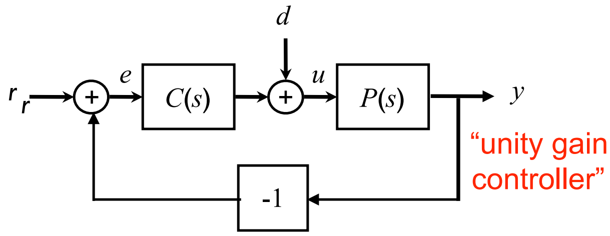
$$G(s) = C(sI - A)^{-1}B + D$$

$$G_{y_2 u_1} = G_{y_2 u_2} G_{y_1 u_1} = \frac{n_1 n_2}{d_1 d_2}$$





Closed Loop Stability



Q: how do open loop dynamics affect the closed loop stability?

- Given open loop transfer function $C(s)P(s)$ determine when system is stable

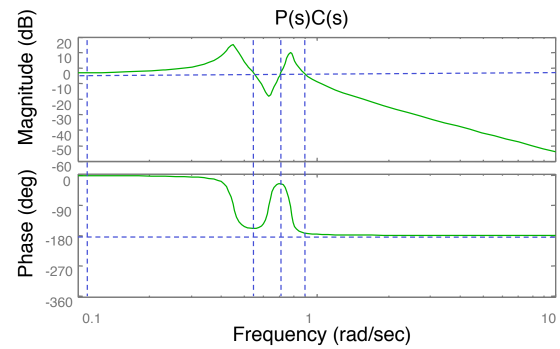
Brute force answer: compute poles closed loop transfer function

$$H_{yr} = \frac{PC}{1+PC} = \frac{n_p n_c}{d_p d_c + n_p n_c}$$

- Poles of H_{yr} = zeros of 1 + PC
- Easy to compute, but not so good for design

Alternative: look for conditions on *PC* that lead to instability

- Example: if $PC(s) = -1$ for some $s = i\omega$, then system is *not* asymptotically stable
- Condition on *PC* is much nicer because we can *design* $PC(s)$ by choice of $C(s)$
- However, checking $PC(s) = -1$ is not enough; need more sophisticated check

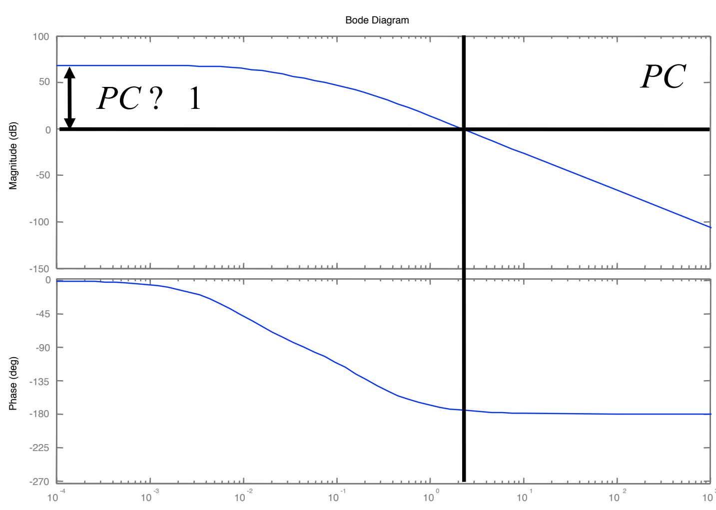


Game Plan: Frequency Domain Design

Goal: figure out how to *design* $C(s)$ so that $1+C(s)P(s)$ is stable *and* we get good performance

$$H_{yr} = \frac{PC}{1+PC}$$

- Poles of H_{yr} = zeros of 1 + *PC*
- Would also like to "shape" H_{yr} to specify performance at differenct frequencies



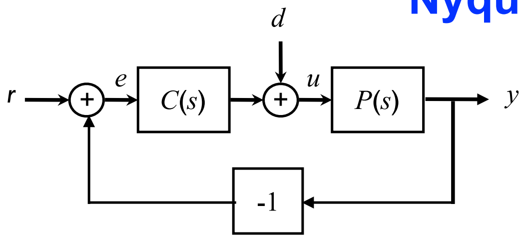
- Low frequency range:

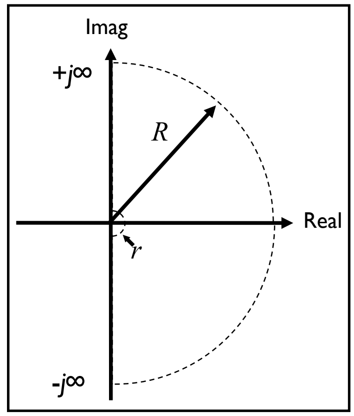
$$PC ? 1 \Rightarrow \frac{PC}{1+PC} \approx 1$$

(good tracking)

- Bandwidth: frequency at which closed loop gain = ½ ⇒ open loop gain ≈ 1
- Idea: use $C(s)$ to *shape PC* (under certain constraints)
- Need tools to analyze stability and performance for closed loop given *PC*

Nyquist Criterion





- Nyquist "D" contour
- Take limit as $r \to 0$, $R \to \infty$
- Trace from −1 to +1 along imaginary axis

Determine stability from (open) loop transfer function, L(s) = P(s)C(s).

- Use "principle of the argument" from complex variable theory (see reading)

Thm (Nyquist). Consider the Nyquist plot for loop transfer function $L(s)$. Let

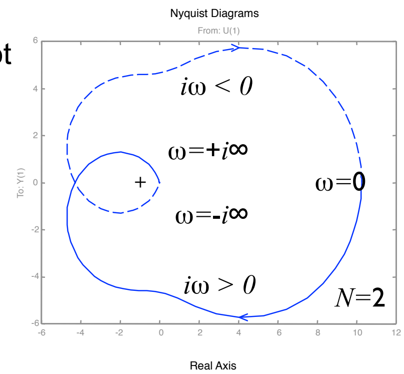
P # RHP poles of $L(s)$

N # clockwise encirclements of -1

Z # RHP zeros of $1 + L(s)$

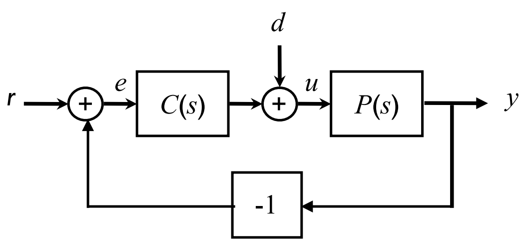
Then

$$Z = N + P$$



- Trace frequency response for $L(s)$ along the Nyquist "D" contour
- Count net # of clockwise encirclements of the -1 point

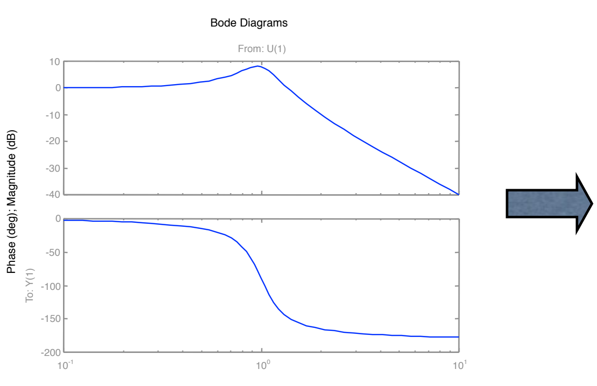
Simple Interpretation of Nyquist



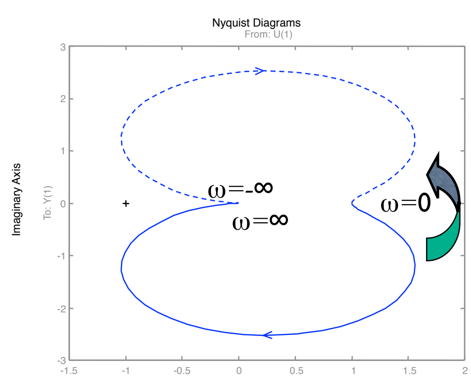
Basic idea: avoid positive feedback

- If L(s) has 180˚ phase (or greater) and gain greater than 1, then signals are amplified around loop
- Use when phase is monotonic
- General case requires Nyquist

Can generate Nyquist plot from Bode plot + reflection around real axis

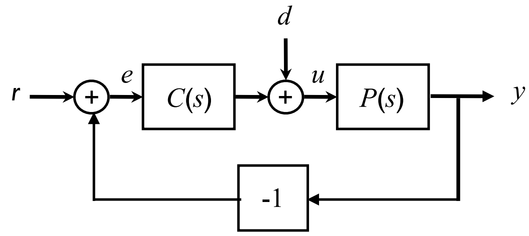


ambode(sys) [or bode(sys) in dB]



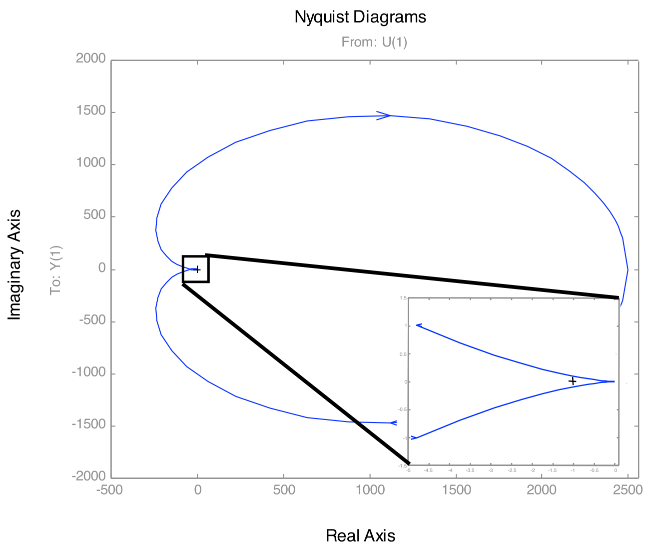
amnyquist(sys)

Example: Proportional + Integral* speed controller



$$P(s) = \frac{1/m}{s + b/m} \times \frac{r}{s+a}$$

$$C(s) = K_p + \frac{K_i}{s + 0.01}$$



Remarks

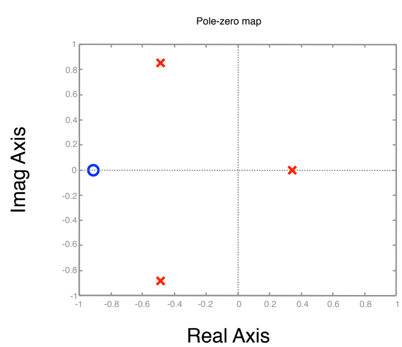
- N = 0, P = 0 ⇒ Z = 0 (stable)
- Need to zoom in to make sure there are no net encirclements
- Note that we don't have to compute closed loop response

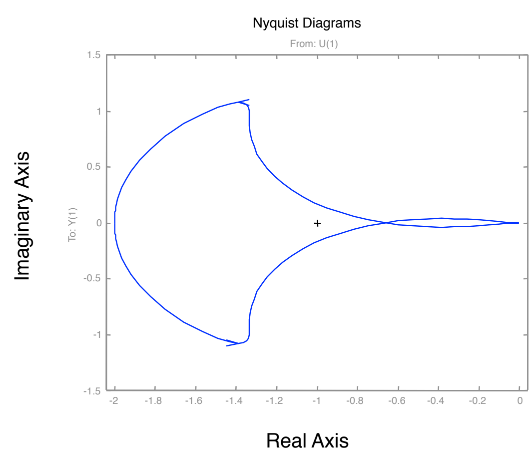
* slightly modified; more on the design of this compensator in next week's lecture

More complicated systems

What happens when open loop plant has RHP poles?

- 1 + PC has singularities inside D contour ⇒ these must be taken into account





$$L(s) = \frac{s+1}{s-0.5} \times \frac{1}{s^2 + s + 1}$$

unstable pole

N = -1, P = 1 ⇒ $Z = N+P$ = 0 (stable)

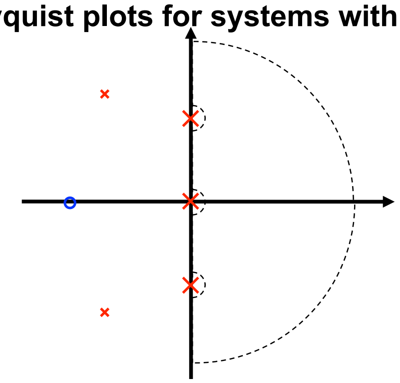
$$\frac{1}{1+L} = \frac{s+1}{(s+0.35)(s+0.07+1.2j)(s+0.07-1.2j)}$$ ✓

Comments and cautions

Why is the Nyquist plot useful?

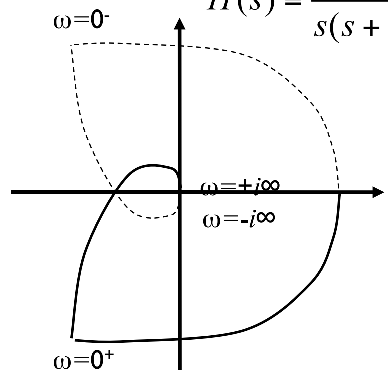
- Old answer: easy way to compute stability (before computers and MATLAB)
- Real answer: gives insight into stability and robustness; very useful for reasoning about stability

Nyquist plots for systems with poles on the jω axis



- chose contour to avoid poles on axis
- need to carefully compute Nyquist plot at these points
- evaluate $H(\varepsilon+0i)$ to determine direction

$$H(s) = \frac{1}{s(s+1)^2}$$

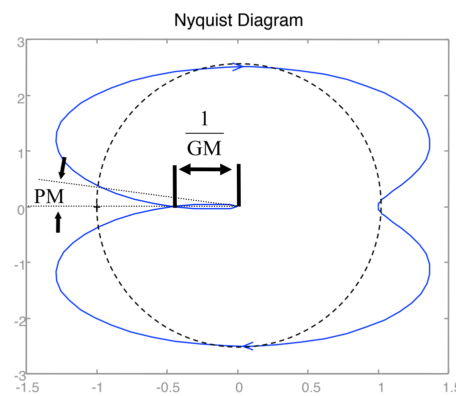


Cautions with using MATLAB

- MATLAB doesn't generate portion of plot for poles on imaginary axis
- These must be drawn in by hand (make sure to get the orientation right!)

Robust stability: gain and phase margins

Nyquist plot tells us if closed loop is stable, but not how stable

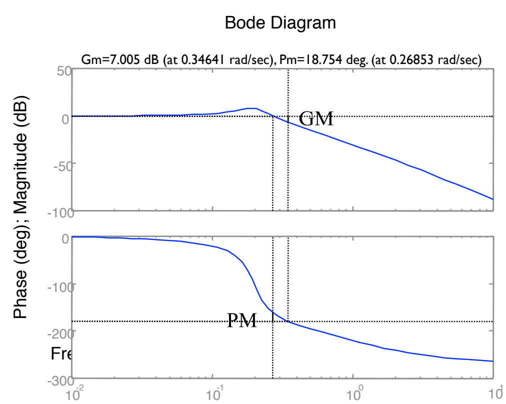


Gain margin

- How much we can modify the loop gain and still have the system be stable
- Determined by the location where the loop transfer function crosses 180˚ phase

Phase margin

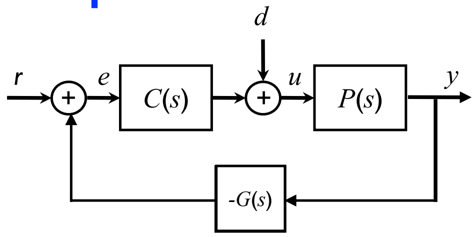
- How much we can add "phase delay" and still have the system be stable
- Determined by the phase at which the loop transfer function has unity gain



Bode plot interpretation

- Look for gain = 1, 180˚ phase crossings
- MATLAB: margin(sys)

Example: cruise control



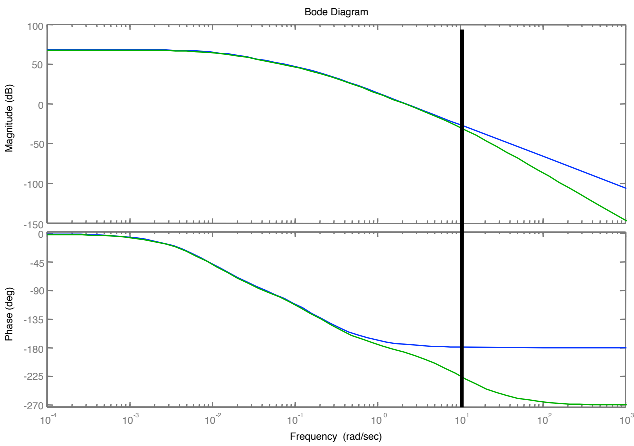
$$P(s) = \frac{1/m}{s + b/m} \times \frac{r}{s+a}$$

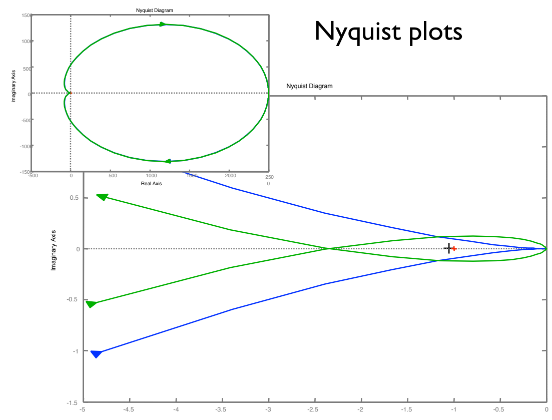
$$C(s) = K_p + \frac{K_i}{s + 0.01}$$

$$G(s) = \frac{10}{s+10}$$

Effect of additional sensor dynamics

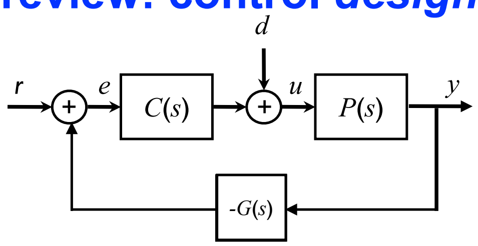
- New speedometer has pole at s = 10 (very fast); problems develop in the field
- What's the problem? A: insufficient phase margin in original design (not robust)





Nyquist plots

Preview: control *design*



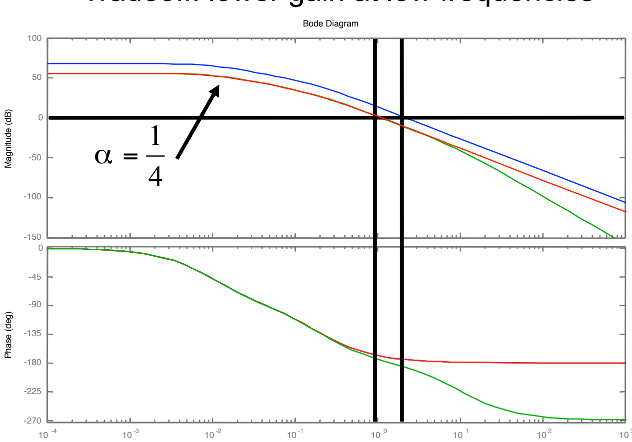
$$P(s) = \frac{1/m}{s + b/m} \times \frac{r}{s+a}$$

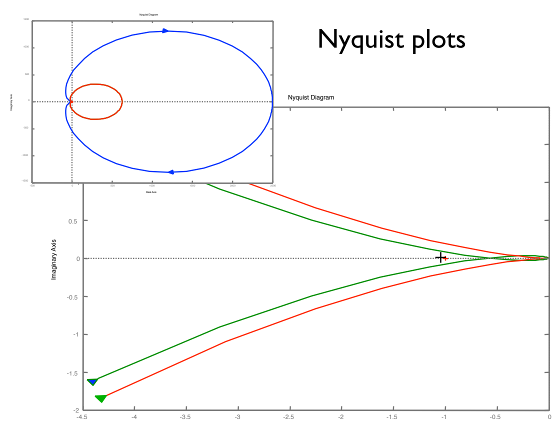
$$C(s) = \alpha\left(K_p + \frac{K_i}{s + 0.01}\right)$$

$$G(s) = \frac{10}{s+10}$$

Approach: Increase phase margin

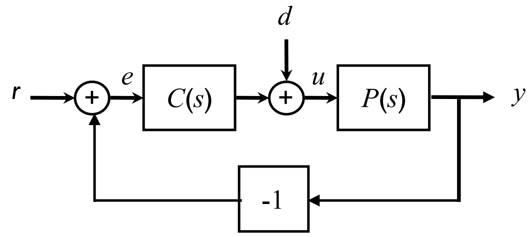
- Increase phase margin by reducing gain ⇒ can accommodate new sensor dynamics
- Tradeoff: lower gain at low frequencies ⇒ less bandwidth, larger steady state error

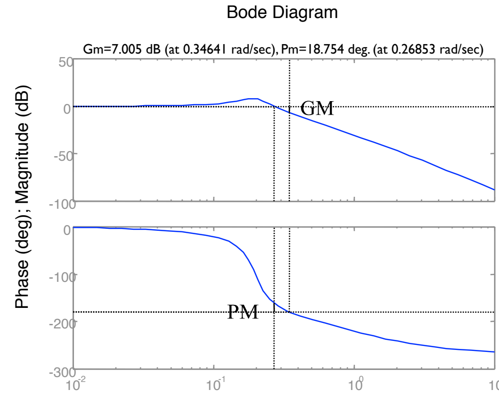




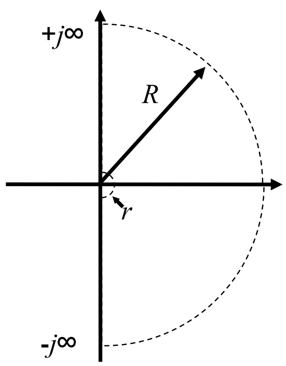
Nyquist plots

Summary: Loop Analysis of Feedback Systems





- Nyquist criteria for loop stability
- Gain, phase margin for robustness



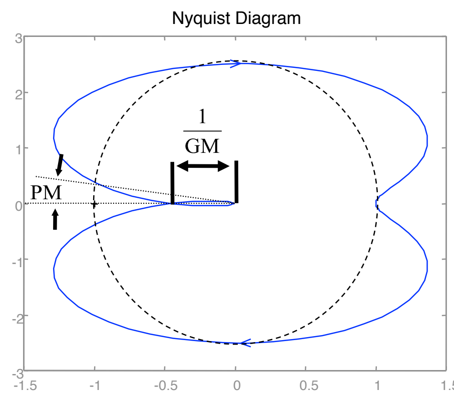
Thm (Nyquist).

P # RHP poles of *L*(*s*)

N # CW encirclements

Z # RHP zeros

$$Z = N + P$$



Announcements

Midterm is graded; solutions posted

- CDS 110: average = 59/75, σ = 10.7
- CDS 101: average = 36/40, σ = 2.3

Homework #5 due today at 5 pm

- Remember to put number of hours spent on back of first page
  - MT survey: 12.6 ± 4.0

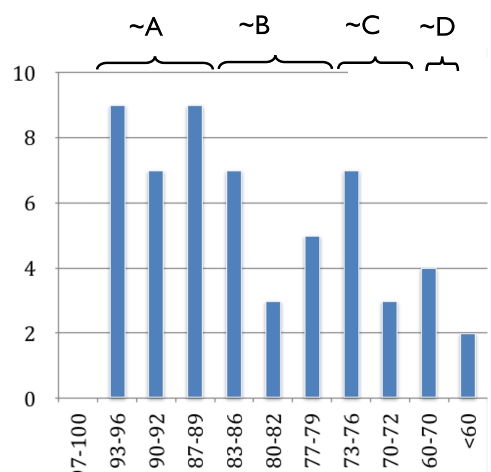
Midterm survey

- Improvement in SIMULINK from previous years
- MP3s, mud cards least useful (< 3)

Homework #6 available on the web

Ombuds meeting

- Adding Sunday office hours (3-4 pm)
- TAs will "clarify" HW in recitation
- More emphasis on explaining all terms used in homework in the lectures



Computing your course grade so far:

$$\text{Grade} = \frac{50\%}{4} \times \sum_{i=1}^{4} \left(\frac{\text{HW}_i}{\text{max}_i} \right) + 50\% \times \frac{\text{MT}}{\text{max}_{\text{mt}}}$$

HW	110	101
1	40	30
2	33	20
3	25	9
4	38	20

```
% L7_1_loopanal.m
% RMM, 8 Nov 02
%
% Required files: none

%%
%% Cruise controller
%%
%% This is the cruise controller that we studied in HW #2, 3, 4.  It
uses
%% a modified PD control law.  The main modification is replacing the
%% integrator with a high gain, low pass filter to make the plots show
%% the features more clearly.
%%

% Parameter definitions
m = 1000;                                   % mass of the car, kg
b = 50;                                     % damping coefficient, N
sec/m
a = 0.2;                           % engine lag coefficient
r = 5;                                      % transmission gain
Ki = 50;                           % integral gain
Kp = 1000;                                  % proportional gain

% Dynamics
veh = tf([1/m], [1 b/m]);          % vehicle
eng = tf([r], [1 a]);                       % engine
ctr = tf([Kp Ki], [1 0.01]);                % control: PI w/ LF pole
cruise = ctr*eng*veh;                       % loop transfer function

%% Plot out the Nyquist plot for the system
global AM_NYQUIST_PLAIN;
figure(1); amnyquist(cruise);                       % standard plot
figure(2); amnyquist(cruise, {1,1e5});              % zoomed plot

%% Speed sensor dynamics (use standard MATLAB command this time)
figure(3); lag = tf([10], [1 10]);                  % G(s) = 10/(s+10)
figure(4); bode(cruise, cruise*lag);                % Plot old and new
Bode
figure(5); nyquist(cruise, cruise*lag);             % Nyquist plots for
old and new
figure(6); nyquist(cruise, cruise*lag, {1,1e5});% Zoomed version

%% Design example - change the gain on the plots
figure(7); bode(cruise, 0.25*cruise*lag, 0.25*cruise);
figure(8); nyquist(cruise, 0.25*cruise*lag, 0.25*cruise*lag);
figure(9); nyquist(0.25*cruise*lag, 0.25*cruise*lag, {0.5,1e5});
```