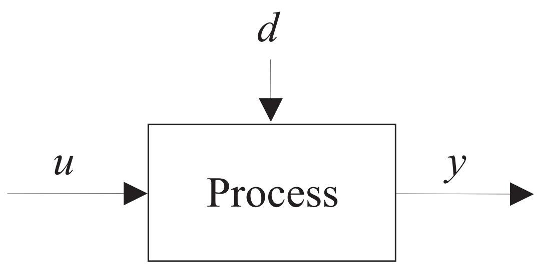
Conventional Control

A Refresher

Process to Be Controlled



y : variable to be controlled (output)

u : manipulated variable (control input)

d : disturbance (input that cannot be influenced)

dynamic system

Examples of "Processes"

- technical (man-made) system

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- natural environment

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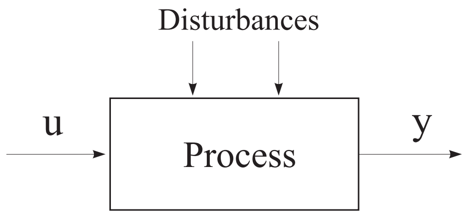
Classical Control Design



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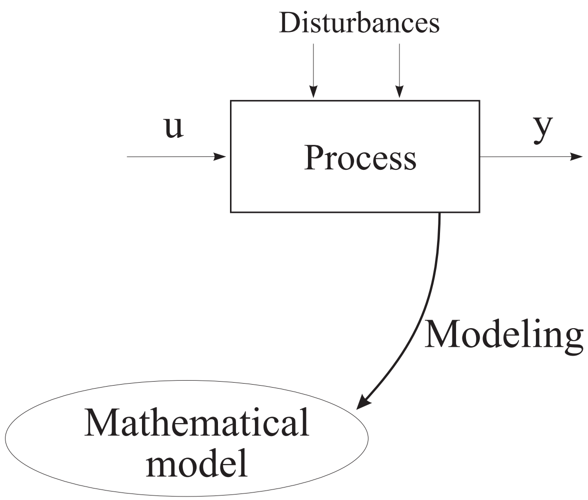

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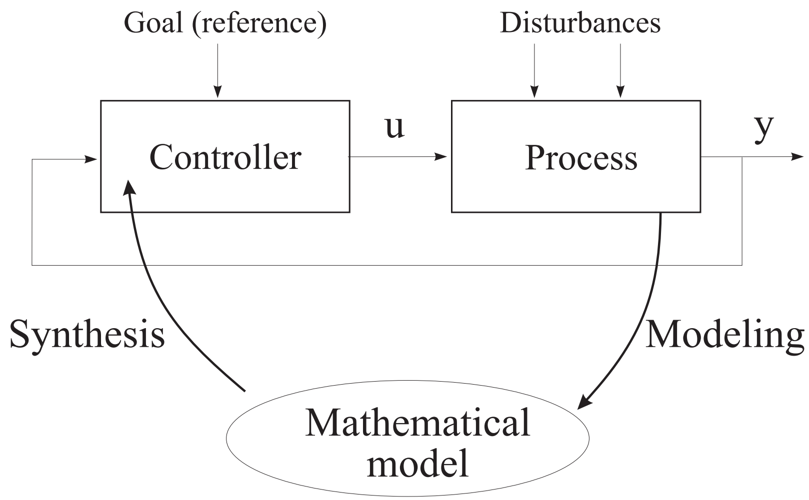

How to Obtain Models?

- physical (mechanistic) modeling
  1. first principles → differential equations (linear or nonlinear)
  2. linearization around an operating point
- system identification
  1. measure input–output data
  2. postulate model structure (linear–nonlinear)
  3. estimate model parameters from data (least squares)

Modeling of Dynamic Systems

$x(t)$ . . . state of the system

summarizes all history such that if we know $x(t)$ we can predict its development in time, $\dot{x}(t)$, for any input $u(t)$

linear state-space model:

$$\dot{x}(t) = Ax(t) + Bu(t)$$

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

Continuous-Time State-Space Model

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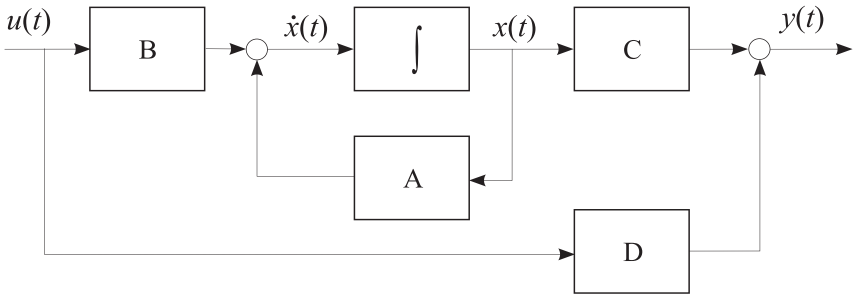

Discrete-Time State-Space Model

$$\begin{aligned}x(k+1) &= \Phi x(k) + \Gamma u(k)\\ y(k) &= Cx(k) + Du(k)\end{aligned}$$

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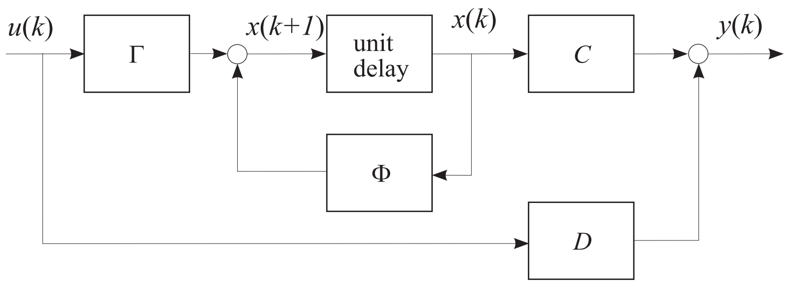


Input–Output Models

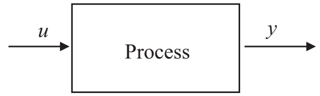
Continuous time:

$$y^{(n)}(t) = f\left(y^{(n-1)}(t), \ldots, y^{(1)}(t), y(t), u^{(n-1)}(t), \ldots, u^{(1)}(t), u(t)\right)$$

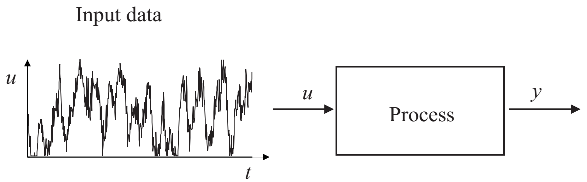
Discrete time:

$$\begin{aligned} y(k+1) \; = \; & f(y(k), y(k-1), \ldots, y(k-n_y+1), \ldots, \\ & u(k), u(k-1), \ldots, u(k-n_u+1)) \end{aligned}$$

System Identification



System Identification



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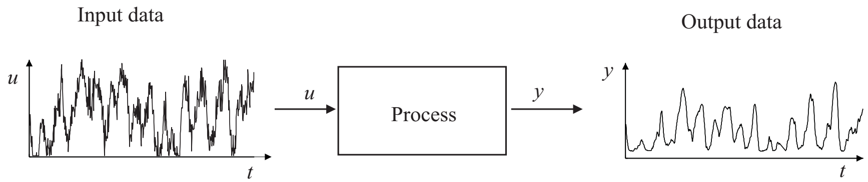

$u(1), u(2), \ldots, u(N)$ $\qquad$ $y(1), y(2), \ldots, y(N)$

System Identification

Given data set $\{(u(k), y(k)) \mid k = 1, 2, \ldots, N\}$**:**

1. Postulate model structure, e.g.:

$$\hat{y}(k+1) = ay(k) + bu(k)$$

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2. Form regression equations:

$$\begin{aligned} y(2) &= ay(1) + bu(1) \\ y(3) &= ay(2) + bu(2) \\ &\vdots \\ y(N) &= ay(N-1) + bu(N-1) \end{aligned}$$

in a matrix form: $\mathbf{y} = \boldsymbol{\varphi}[a\ b]^T$

System Identification

3. Solve the equations for $[a\ b]$ **(least-squares solution):**

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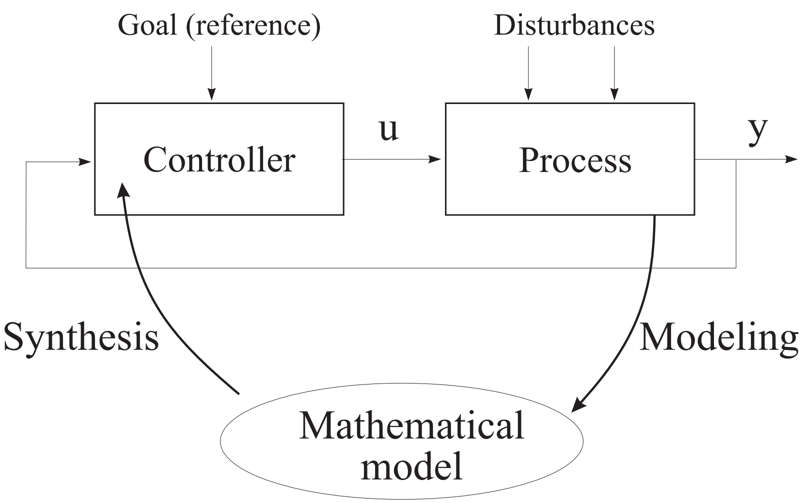
Numerically better methods are available (in MATLAB `[a b] =` φ `\ y`).

Classical Control Design



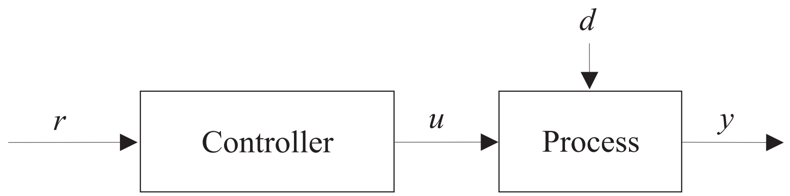
Design Procedure

- Criterion (goal)
  - stabilize an unstable process
  - suppress influence of disturbances
  - improve performance (e.g., speed of response)
- Structure of the controller
- Parameters of the controller (tuning)

Taxonomy of Controllers

- Presence of feedback: feedforward, feedback, 2-DOF
- Type of feedback: output, state
- Presence of dynamics: static, dynamic
- Dependence on time: fixed, adaptive
- Use of models: model-free, model-based

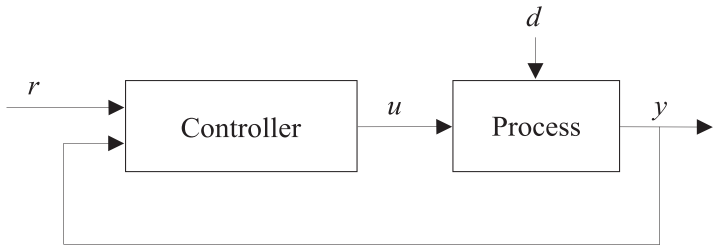
Feedforward Control



Controller:

- (dynamic) inverse of process model
- cannot stabilize unstable processes
- cannot suppress the effect of d
- sensitive to uncertainty in the model

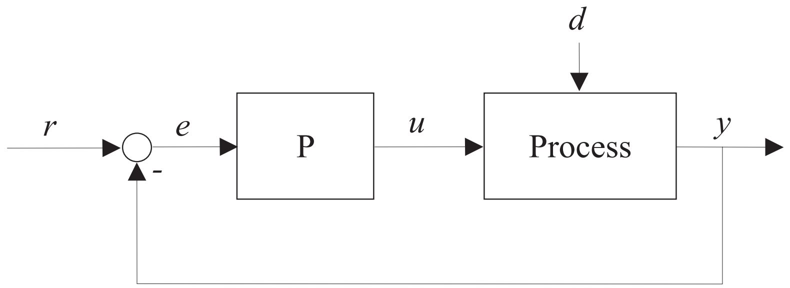
Feedback Control



Controller:

- dynamic or static ($\neq$ inverse of process)
- can stabilize unstable processes (destabilize stable ones!)
- can suppress the effect of d

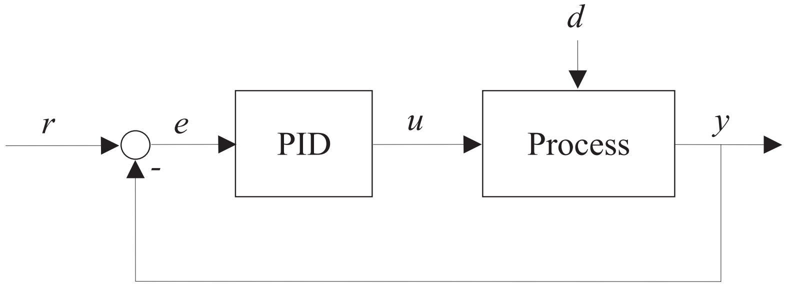
Proportional Control



Controller:

- static gain P: $u(t) = Pe(t)$

PID Control

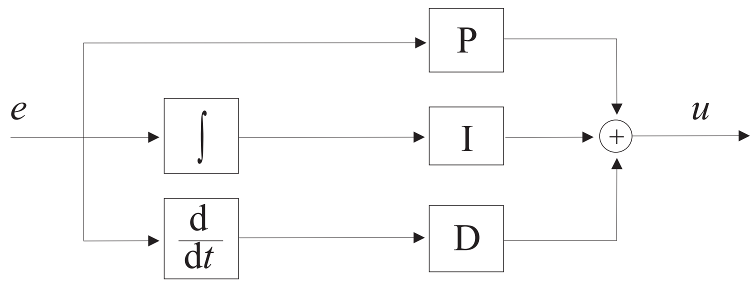


Controller:

- **dynamic:** $u(t) = Pe(t) + I\int_0^t e(\tau)d\tau + D\frac{de(t)}{dt}$
- P, I and D are the **proportional**, **integral** and **derivative** gains, respectively

PID Control: Internal View

$$u(t) = Pe(t) + I\int_0^t e(\tau)d\tau + D\frac{de(t)}{dt}$$



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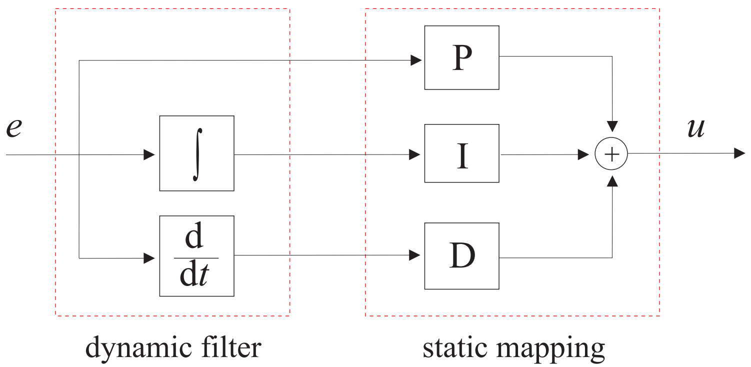
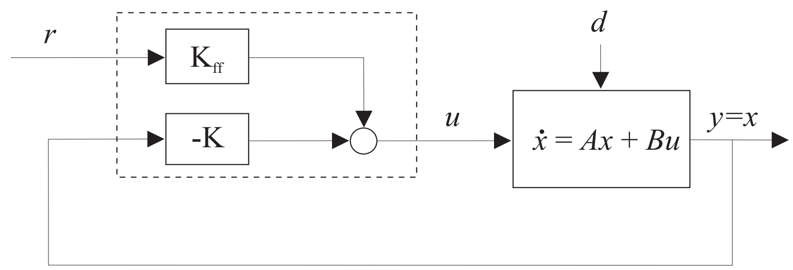


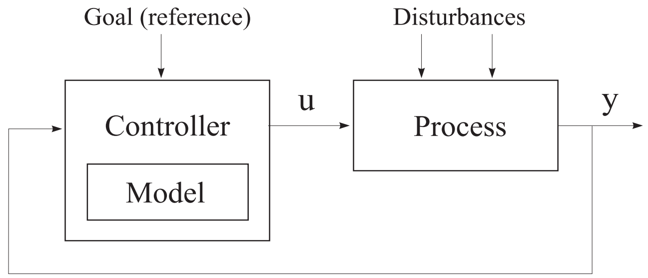
State Feedback



Controller:

- **static:** $u(t) = Kx(t)$
- K **can be computed such that** $(A + BK)$ **is stable**
- K_{ff} **takes care of the (unity) gain from** r **to** y

Model-Based Control



- state observer
- model-based predictive control
- adaptive control

Motivation for Intelligent Control

Pro's and Con's of Conventional Control

+ systematic approach, mathematically elegant
+ theoretical guarantees of stability and robustness

– time-consuming, conceptually difficult
– control engineering expertise necessary
– often insufficient for nonlinear systems

Additional Aspects

- control is a multi-disciplinary subject
- human factor may be very important
  - pilot
  - plant operator
  - user interface (e.g., consumer products)
- quest for higher machine itelligence

When Conventional Design Fails

- no model of the process available
  - $\rightarrow$ mathematical synthesis and analysis impossible
  - $\rightarrow$ experimental tuning may be difficult
- process (highly) nonlinear
  - $\rightarrow$ linear controller cannot stabilize
  - $\rightarrow$ performance limits

Example: Stability Problems

$$\frac{d^3y(t)}{dt^3} + \frac{d^2y(t)}{dt^2} + \frac{dy(t)}{dt} = y^2(t)u(t)$$

Use Simulink to simulate a proportional controller (nlpid.m)

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Conclusions:

- stability and performance depend on process output
- re-tuning the controller does not help
- nonlinear control is the only solution

Intelligent Control

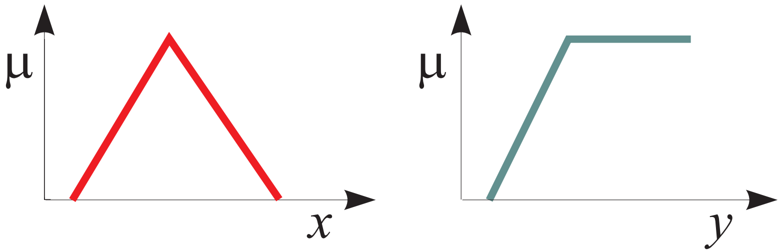
techniques motivated by human intelligence

- fuzzy systems (represent human knowledge, reasoning)
- artificial neural networks (adaptation, learning)
- genetic algorithms (optimization).

$\Rightarrow$ *computational intelligence, soft computing*

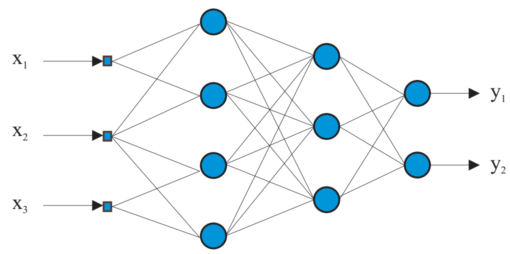
Knowledge Representation by If–Then Rules

If x is *Medium* **then** y is *Large*



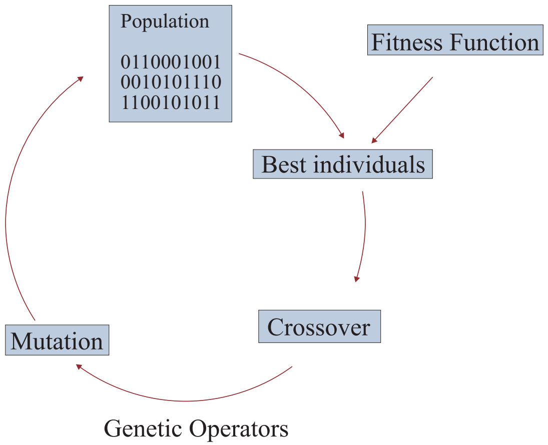
Artificial Neural Networks

Function approximation by imitating biological neural networks.



Learning, adaptation, optimization.

Genetic Algorithms

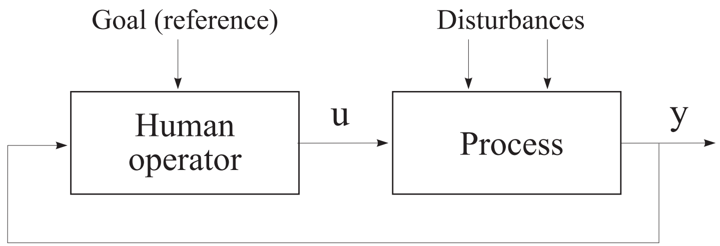


Optimization by imitating natural evolution.

Intelligent Control

- Fuzzy knowledge-based control
- Fuzzy data analysis, modeling, identification
- Learning and adaptive control (neural networks)
- Reinforcement learning

Direct Fuzzy Control



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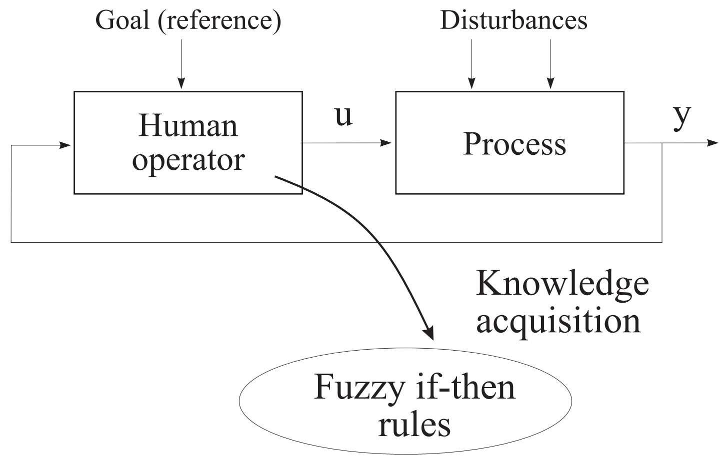

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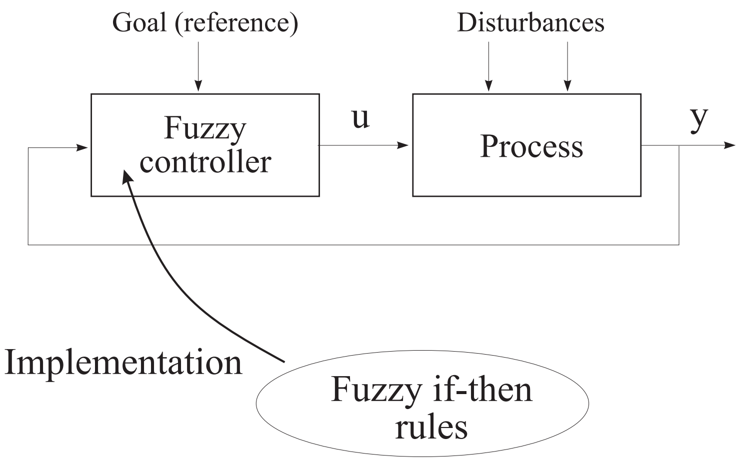

Fuzzy Sets and Fuzzy Logic

Relatively new methods for representing uncertainty and reasoning under uncertainty.

Types of uncertainty:

- chance, randomness (stochastic)
- imprecision, vagueness, ambiguity (non-stochastic)

Vagueness in If–Then Rules

If temperature in the burning zone *is OK*, and
oxygen percentage in the exhaust gases *is Low*, and
temperature at the back-end *is High*,
then reduce fuel *Slightly* and reduce fan speed *Moderately*.

Fuzzy Sets and Fuzzy Logic

Proposed in 1965 by L.A. Zadeh
(Fuzzy Sets, Information Control, vol. 8, pp. 338–353)

- generalization of ordinary set theory
- '70 first applications, fuzzy control (Mamdani)
- '80 industrial applications, train operation, pattern recognition
- '90 consumer products, cars, special HW, SW.

The term "fuzzy logic" often also denotes fuzzy sets theory and its applications (e.g., fuzzy logic control).

Applications of Fuzzy Sets