Nonlinear Control and Servo systems

Lecture 1

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Dept. of Automatic Control
LTH, Lund University

Overview Lecture 1

- Practical information
- Course contents
- Nonlinear control phenomena
- Nonlinear differential equations

Course Goal

To provide students with a solid theoretical foundation of nonlinear control systems combined with a good engineering ability

You should after the course be able to

- recognize common nonlinear control problems,
- use some powerful analysis methods, and
- use some practical design methods.

Today's Goal

- *Recognize some common nonlinear phenomena*
- *Transform differential equations to autonomous form, first-order form, and feedback form.*
- *Describe saturation, dead-zone, relay with hysteresis, backlash*
- *Calculate equilibrium points*

Course Material

- Textbook
  - Glad and Ljung, *Reglerteori, flervariabla och olinjära metoder*, 2003, Studentlitteratur,ISBN 9-14-403003-7 or the English translation *Control Theory*, 2000, Taylor & Francis Ltd, ISBN 0-74-840878-9. The course covers Chapters 11-16,18. (MPC and optimal control not covered in the other alternative textbooks.)
  - `ALTERNATIVE:` H. Khalil, *Nonlinear Systems* (3rd ed.), 2002, Prentice Hall, ISBN 0-13-122740-8. A good, but a bit more advanced book.
  - `ALTERNATIVE (Hard to get/out of print):` Slotine and Li, *Applied Nonlinear Control*, Prentice Hall, 1991. The course covers chapters 1-3 and 5, and sections 4.7-4.8, 6.2, 7.1-7.3.

Course Material, cont.

- Handouts (Lecture notes + extra material)
- Exercises (can be download from the course home page)
- Lab PMs 1, 2 and 3
- Home page
  `http://www.control.lth.se/course/FRTN05/`
- Matlab/Simulink other simulation software
  see home page

Lectures and labs

The lectures (30 hours) are given as follows:

Mon 10-12,	M:D	Mar 15, Mar 22, Apr 19 – May 17
Wed 10-12,	M:B,	March 17, Mar 24, Apr 21 – May 19
Thu 10-12	M:D	**April 15**

The lectures are given in English.

The three laboratory experiments are mandatory.

Sign-up lists are posted on the web at least one week before the first laboratory experiment. *The lists close one day before the first session.*

The Laboratory PMs are available at the course homepage.

Before the lab sessions some home assignments have to be done. No reports after the labs.

Exercise sessions and TAs

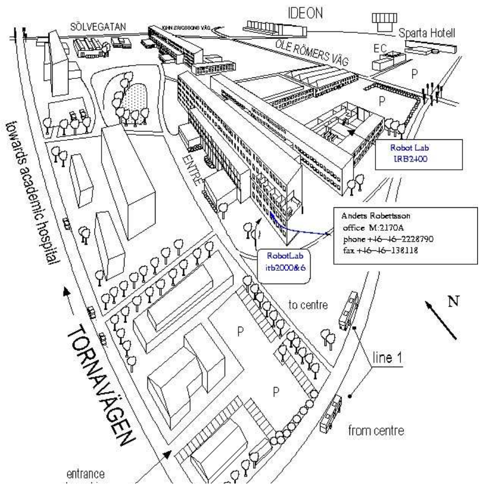
The exercises (28 hours) are taught in two alternative groups;

group 1	Tue 13-15	Wed 13-15
group 2	Tue 15–17	Thu 15–17

NOTE: The exercises are held in either ordinary lecture rooms or the department laboratory on the bottom floor in the south end of the Mechanical Engineering building, **see schedule on home page.**

Karl Berntorp Daria Madjidian



The Course

- 15 lectures
- 14 exercises
- 3 lab exercises.
- 5 hour exam: **May 28, 2010**.
  - Open-book exam: lecture notes but no old exams or exercises allowed. Next exam on August 20, 2010

Contents

- Introduction. Typical nonlinear problems and phenomena.
- Linearization. Simulation.
- Stability theory
- Periodic solutions.
- Compensation for friction, saturation, back-lash etc.
- Optimal control
- Nonlinear control design methods

Todays lecture

Common nonlinear phenomena

- Input-dependent stability
- Stable periodic solutions
- Jump resonances and subresonances
- Peaking

Nonlinear model structures

- Common nonlinear components
- State equations
- Feedback representation

Linear Systems

$$u \longrightarrow \boxed{S} \longrightarrow y = S(u)$$

Definitions: The system S is *linear* if

$$\begin{aligned} S(\alpha u) &= \alpha S(u), && \text{scaling} \\ S(u_1 + u_2) &= S(u_1) + S(u_2), && \text{superposition} \end{aligned}$$

A system is *time-invariant* if delaying the input results in a delayed output:

$$y(t - \tau) = S(u(t - \tau))$$

Linear time-invariant systems are easy to analyze

Different representations of same system/behavior

$$\begin{aligned} \dot{x}(t) &= Ax(t) + Bu(t), \quad y(t) = Cx(t), \quad x(0) = 0 \\ y(t) &= g(t) \star u(t) = \int g(r)u(t - r)dr \\ Y(s) &= G(s)U(s) \end{aligned}$$

Local stability = global stability:

Eigenvalues of A (= poles of $G(s)$) in left half plane

Superposition:

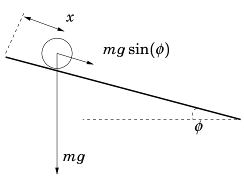
Enough to know step (or impulse) response

Frequency analysis possible:

Sinusoidal inputs give sinusoidal outputs

Linear Models are not always Enough

Example: Ball and beam



Linear model (acceleration along beam) :
Combine $F = m \cdot a = m\frac{d^2x}{dt^2}$ and $F = mg\sin(\phi)$:

$$\ddot{x}(t) = \frac{5g}{7}\phi(t)$$

Linear Models are not Enough

x = position (meter)
ϕ = angle (radians)
$g = 9.81$ (meter/sec^2)

Can the ball move 0.1 meter in 0.1 seconds?

Simple approximations give

$$\begin{aligned} x(t) &\approx \frac{50}{7}\frac{t^2}{2}\phi_0 \approx 0.04\phi_0 \\ \phi_0 &\approx \frac{0.1}{0.04} = 2.5 \text{ radians} \end{aligned}$$

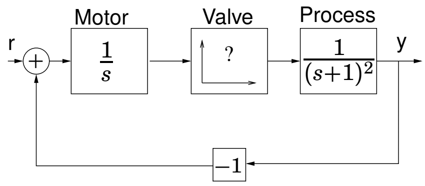
Clearly outside linear region!

Contact problem, friction, centripetal force, saturation

How fast can it be done? (Optimal control)

2 minute exercise: *Find a simple system* $\dot{x} = f(x, u)$ *that is stable for a small input step but unstable for large input steps.*

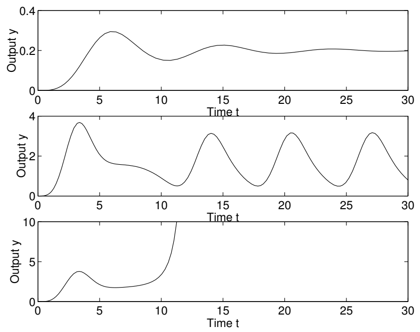
Stability Can Depend on Amplitude



Valve characteristic $f(x)$ =???

Step changes of amplitude, $r = 0.2$, $r = 1.68$, and $r = 1.72$

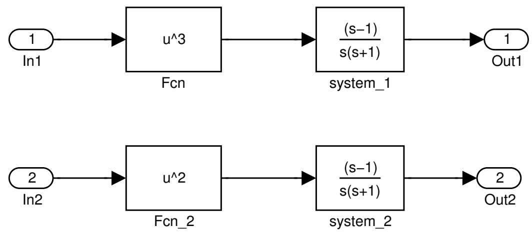
Step Responses



Stability depends on amplitude!

Simple compensation

How would you go about the previous problem if there is an "input nonlinearity"? Are there still any problems?



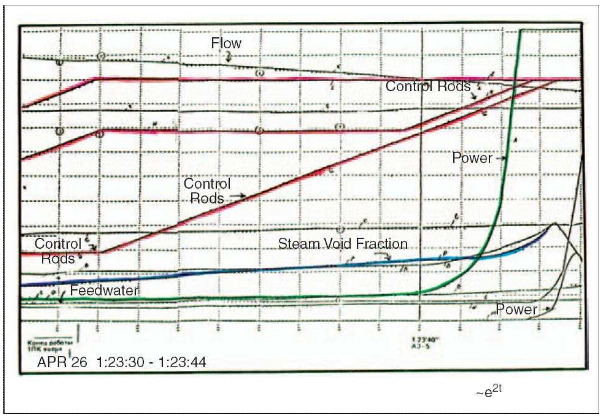
What system is (was!) this?

Unstable process

Bounded domain of stability

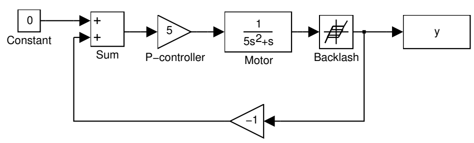
Rate limitations

see time plots



Stable Periodic Solutions

Example: Motor with back-lash

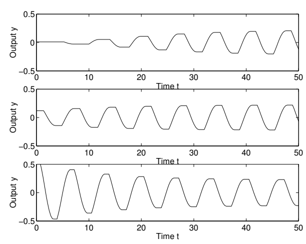


Motor: $G(s) = \frac{1}{s(1+5s)}$

Controller: $K = 5$

Stable Periodic Solutions

Output for different initial conditions:

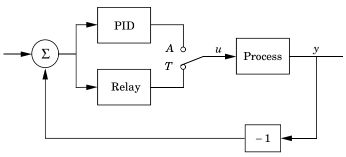


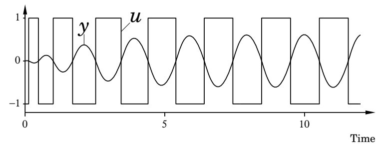
Frequency and amplitude independent of initial conditions!

Several systems use the existence of such a phenomenon

Relay Feedback Example

Period and amplitude of limit cycle are used for autotuning





[patent: T Hägglund and K J Åström]

The peaking phenomenon

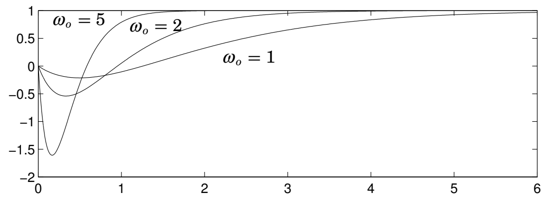
Example: Controlled linear system with right-half plane zero

Feedback can change location of poles but not location of zero (unstable pole-zero cancellation not allowed).

$$G_{cl}(s) = \frac{(-s+1)\omega_o^2}{s^2 + 2\omega_o s + \omega_o^2} \tag{1}$$

A step response will reveal a transient which grows in amplitude for faster closed loop poles $s = -\omega_o$, see Figure on next slide.

The peaking phenomenon – *cont.*



Step responses for the system in Eq. (1), $\omega_o = 1, 2$, and 5. Faster poles gives shorter settling times, but the transients grow significantly in amplitude, so called *peaking*.

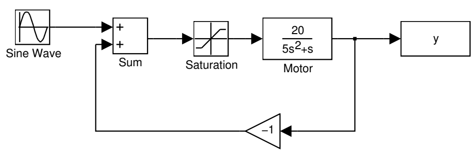
The peaking phenomenon – *cont.*

Note!

- Linear case: Performance may be severely deteriorated by peaking, but stability still guaranteed.
- Nonlinear case: Instability and even finite escape time solutions may occur.

What bandwidth constraints does a non-minimum zero impose for linear systems? See *e.g.*, [**?**, **?**, **?**]

Jump Resonances



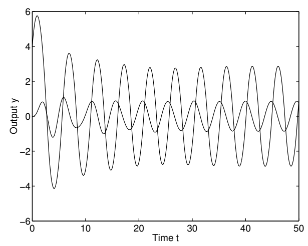
Response for sinusoidal depends on initial condition

Problem when doing frequency response measurement

Jump Resonances

$u = 0.5\sin(1.3t)$, saturation level =1.0

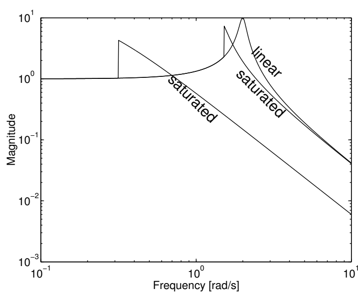
Two different initial conditions



give two different amplifications for same sinusoid!

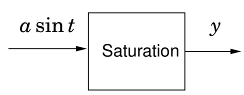
Jump Resonances

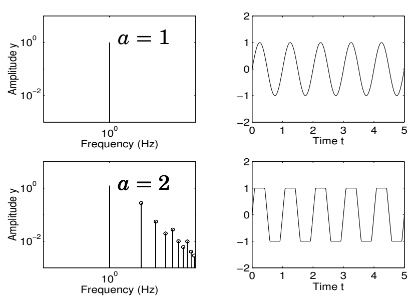
Measured frequency response (many-valued)



New Frequencies

Example: Sinusoidal input, saturation level 1





New Frequencies

Example: Electrical power distribution

THD = Total Harmonic Distortion = $\frac{\sum_{k=2}^{\infty} \text{energy in tone } k}{\text{energy in tone 1}}$

Nonlinear loads: Rectifiers, switched electronics, transformers

Important, increasing problem

Guarantee electrical quality

Standards, such as $THD < 5\%$

New Frequencies

Example: Mobile telephone

Effective amplifiers work in nonlinear region

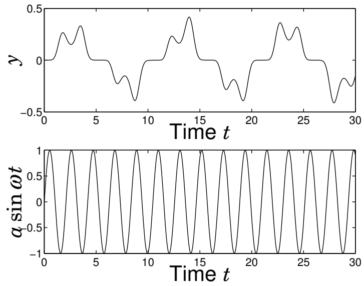
Introduces spectrum leakage

Channels close to each other

Trade-off between effectivity and linearity

Subresonances

Example: Duffing's equation $\ddot{y} + \dot{y} + y - y^3 = a\sin(\omega t)$



When is Nonlinear Theory Needed?

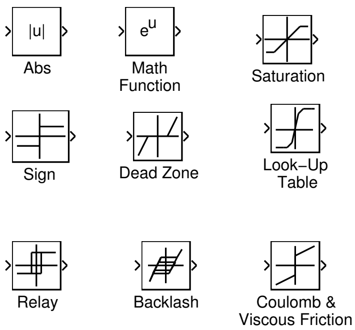
- Hard to know when - Try simple things first!
- Regulator problem versus servo problem
- Change of working conditions (production on demand, short batches, many startups)
- Mode switches
- Nonlinear components

How to detect? Make step responses, Bode plots

- Step up/step down
- Vary amplitude
- Sweep frequency up/frequency down

Some Nonlinearities

Static – dynamic



2 minute exercise

Construct a model for a "rate limiter" using some of the previous nonlinear blocks.

Nonlinear Differential Equations

Problems

- No analytic solutions
- Existence?
- Uniqueness?
- etc

Existence Problems

Example: The differential equation

$$\frac{dx}{dt} = x^2, \qquad x(0) = x_0$$

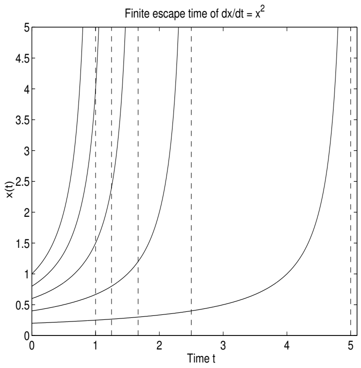
has solution

$$x(t) = \frac{x_0}{1 - x_0 t}, \qquad 0 \le t < \frac{1}{x_0}$$

Finite escape time

$$t_f = \frac{1}{x_0}$$

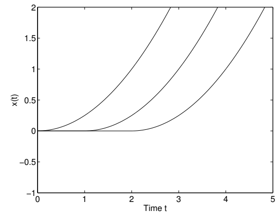
Finite Escape Time



Uniqueness Problems

Example: The equation $\dot{x} = \sqrt{x}$, $x(0) = 0$ has many solutions:

$$x(t) = \begin{cases} (t-C)^2/4 & t > C \\ 0 & t \le C \end{cases}$$



Compare with water tank:

$$dh/dt = -a\sqrt{h}, \qquad h : \text{height (water level)}$$

Change to backward-time: "If I see it empty, when was it full?")

Existence and Uniqueness

Theorem
Let Ω_R denote the ball

$$\Omega_R = \{z; \|z - a\| \le R\}$$

If f is Lipschitz-continuous:

$$\|f(z) - f(y)\| \le K\|z - y\|, \qquad \text{for all } z, y \in \Omega$$

then $\dot{x}(t) = f(x(t)), x(0) = a$ has a unique solution in

$$0 \le t < R/C_R,$$

where $C_R = \max_{\Omega_R} \|f(x)\|$

State-Space Models

- State vector x
- Input vector u
- Output vector y

general:	$f(x, u, y, \dot{x}, \dot{u}, \dot{y}, \ldots) = 0$
explicit:	$\dot{x} = f(x, u), \quad y = h(x)$
affine in u:	$\dot{x} = f(x) + g(x)u, \quad y = h(x)$
linear time-invariant:	$\dot{x} = Ax + Bu, \quad y = Cx$

Transformation to Autonomous System

Nonautonomous:

$$\dot{x} = f(x, t)$$

Always possible to transform to autonomous system

Introduce x_{n+1} = time

$$\begin{aligned} \dot{x} &= f(x, x_{n+1}) \\ \dot{x}_{n+1} &= 1 \end{aligned}$$

Transformation to First-Order System

Assume $\frac{d^k y}{dt^k}$ highest derivative of y

Introduce $x = \begin{bmatrix} y & \frac{dy}{dt} & \ldots & \frac{d^{k-1}y}{dt^{k-1}} \end{bmatrix}^T$

Example: Pendulum

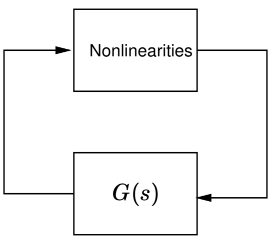
$$MR^2\ddot{\theta} + k\dot{\theta} + MgR\sin\theta = 0$$

$x = \begin{bmatrix} \theta & \dot{\theta} \end{bmatrix}^T$ gives

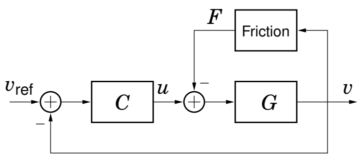
$$\begin{aligned} \dot{x}_1 &= x_2 \\ \dot{x}_2 &= -\frac{k}{MR^2}x_2 - \frac{g}{R}\sin x_1 \end{aligned}$$

A Standard Form for Analysis

Transform to the following form



Example, Closed Loop with Friction



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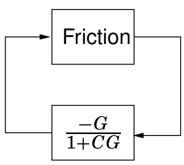

Equilibria (=singular points)

Put all derivatives to zero!

General: $f(x_0, u_0, y_0, 0, 0, 0, \ldots) = 0$

Explicit: $f(x_0, u_0) = 0$

Linear: $Ax_0 + Bu_0 = 0$ (has analytical solution(s)!)

Multiple Equilibria

Example: Pendulum

$$MR^2\ddot{\theta} + k\dot{\theta} + MgR\sin\theta = 0$$

Equilibria given by $\ddot{\theta} = \dot{\theta} = 0 \Longrightarrow \sin\theta = 0 \Longrightarrow \theta = n\pi$

Alternatively,

$$\begin{aligned} \dot{x}_1 &= x_2 \\ \dot{x}_2 &= -\frac{k}{MR^2}x_2 - \frac{g}{R}\sin x_1 \end{aligned}$$

gives $x_2 = 0$, $\sin(x_1) = 0$, etc

Next Lecture

- Linearization
- Stability definitions
- Simulation in Matlab