LUND UNIVERSITY

A Robust Sampled Regulator for Stable Systems with Monotone Step Responses

Åström, Karl Johan

Published in:
Automatica

1980

[Link to publication](#)

Citation for published version (APA):

Åström, K. J. (1980). A Robust Sampled Regulator for Stable Systems with Monotone Step Responses. *Automatica*, 16, 313-315.

Total number of authors:

1

General rights

Unless other specific re-use rights are stated the following general rights apply:

Copyright and moral rights for the publications made accessible in the public portal are retained by the authors and/or other copyright owners and it is a condition of accessing publications that users recognise and abide by the legal requirements associated with these rights.

- Users may download and print one copy of any publication from the public portal for the purpose of private study or research.
- You may not further distribute the material or use it for any profit-making activity or commercial gain
- You may freely distribute the URL identifying the publication in the public portal

Read more about Creative commons licenses: <https://creativecommons.org/licenses/>

Take down policy

If you believe that this document breaches copyright please contact us providing details, and we will remove access to the work immediately and investigate your claim.

LUND UNIVERSITY

PO Box 117
221 00 Lund
+46 46-222 00 00

Brief Paper

A Robust Sampled Regulator for Stable Systems with Monotone Step Responses*

K. J. ÅSTRÖM†

Key Words—Digital control; sampled data systems; system order reduction; stability; robustness.

Abstract—It is shown that a discrete time integrating regulator can be designed based on a strongly simplified model. The regulator has only two tuning parameters which are easy to choose from the step response of the open loop system. The problem is a prototype for a general robustness problem.

1. Introduction

It is useful to have simple robust methods for solving simple problems. This paper gives a very simple way of designing a robust digital regulator for stable linear single-input single-output systems with positive impulse responses. The basic idea is that a regulator is designed for a strongly simplified model of the process. The regulator obtained has two tuning parameters, a gain and the sampling period. It is shown that the regulator works for a given class of problems provided that a simple condition is satisfied. Linear time-invariant systems with monotone step responses occur commonly in the process industries. Typical examples are systems which describe flows, levels, concentrations, and temperatures. See e.g. Åström (1976). The regulator obtained has integral action. The settling time of the closed loop system is larger than the settling time of the open loop system.

2. The algorithm

Consider a stable system with a monotone step response H . See Fig. 1. The system is approximated with the following crude model

$$y(t) = bu(t - T), \quad b > 0. \quad (1)$$

FIG. 1. Step responses of the system and the approximating model.

This model is characterized by two parameters, the gain b and the time delay T . There are many ways to design a simple regulator for the system (1). One possibility is to use a sampled dead-beat regulator with integral action. Such a regulator is obtained as follows. Choose T as the sampling period and let y_k denote the value of the signal y at time kT .

Equation (1) then gives

$$y_k - y_{k-1} = b[u_{k-1} - u_{k-2}]$$

*Received 2 July 1979; revised 26 November 1979. The original version of this paper was not presented at any IFAC meeting. This paper was recommended for publication in revised form by associate editor J. Ackermann.

†Department of Automatic Control, Lund Institute of Technology, Lund, Sweden

Require that y should equal the command signal y^0 after a delay of one sampling period. The following control law is then obtained

$$u_k = [y_k^0 - y_k]/b + u_{k-1}. \quad (2)$$

This control law has two tuning parameters b and T . If the control (2) is applied to the system (1) it follows that

$$y_k = y_{k-1}^0$$

3. Analysis

It will now be investigated what happens when the sampled regulator (2), which is designed using the simplified model (1), is applied to a real system. The following result holds.

Theorem 1. Consider a stable time invariant linear system with monotone nonnegative step response. The closed loop obtained with the regulator (2) is always stable if

$$2H(T) > H(\infty) \quad (3)$$

and

$$2b > H(\infty). \quad (4)$$

Proof. Let h be the impulse response of the system. Then

$$y(t) = \int_0^{\infty} h(s)u(t-s)ds.$$

Since the control signal u is constant over the sampling periods, it follows that

$$y_k = \left(\int_0^T h(s)ds \right) u_{k-1} + \left(\int_T^{2T} h(s)ds \right) u_{k-2} + \dots \quad (5)$$

The closed loop system is thus characterized by equations (2) and (5). Elimination of y between these equations gives

$$\sum_{n=1}^{\infty} a_n u_{k-n} = y_k^0/b$$

where

$$a_n = \begin{cases} 1 & n=0 \\ [H(T) - b]/b & n=1 \\ [H(nT) - H(nT - T)]/b & n > 1. \end{cases}$$

It follows from a theorem of Wiener (1933) that the closed loop system is asymptotically stable if the function

$$A(z) = \sum_{n=0}^{\infty} a_n z^{-n}$$

has the property

$$\inf |A(z)| > 1 \quad \text{for } |z| \geq 1.$$

See also Desoer and Vidyasagar (1975). Since

$$\left| \sum_{n=1}^{\infty} a_n z^{-n} \right| \leq \sum_{n=1}^{\infty} |a_n| \quad \text{for } |z| \geq 1$$

the system is thus stable if

$$\sum_{n=1}^{\infty} |a_n| < 1.$$

Consider

$$\begin{aligned} \sum_{n=1}^{\infty} |a_n| &= \left| \frac{H(T)-b}{b} \right| + \left| \frac{H(2T)-H(T)}{b} \right| + \left| \frac{H(3T)-H(2T)}{b} \right| + \dots \\ &= \left| \frac{H(T)-b}{b} \right| + \left| \frac{H(\infty)-H(T)}{b} \right|. \end{aligned}$$

Two different cases are considered separately. First assume that $H(T) \geq b$. It then follows from (4) that

$$\sum_{n=1}^{\infty} |a_n| = \frac{H(\infty)-b}{b} < 1.$$

Next, assume that $H(T) < b$. Then it follows from (3) that

$$\sum_{n=1}^{\infty} |a_n| = 1 + \frac{H(\infty)-2H(T)}{b} < 1$$

and the theorem is proven.

The bounds (3) and (4) can not be improved as is seen by the following counterexamples. Consider a system described by

$$y(t) = b_0 u(t - T_0).$$

To satisfy (3) choose $T_0 \leq T$. At the sampling instants the closed loop system is then described by

$$u_k = (1 - b_0/b) u_{k-1}.$$

Since $b_0 = H(\infty)$ this equation becomes unstable if (4) is violated. Similarly, choose $b < b_0 < 2b$, which clearly satisfies (4). Assume that $T \leq T_0 < 2T$, which implies that (3) does not hold. At the sampling instants the closed loop system is described by

$$u_k - u_{k-1} + (b_0/b) u_{k-2} = 0$$

which is unstable.

Based on the theorem the following simple design rule can be obtained for the regulator (2). Choose a sampling period such that $H(T) > H(\infty)/2$. Choose the integrator gain $1/b$ smaller than $2/H(\infty)$. It can be seen that the response time of the closed loop system will in general be slower than the response time of the open loop system. This is often acceptable in simple process control application.

The control law (2) can be interpreted as a special case of model algorithmic control (MAC). See Richalet *et al.* (1978) and Mehra and Rouani (1979). Theorem 1 can therefore also be interpreted as a robustness result for MAC. Another approach to robustness for MAC is given in Mehra and colleagues (1979). In MAC the process is modeled by an impulse response. It is therefore of interest to interpret the conditions of Theorem 1 in terms of impulse responses. The assumption that the step response is monotone implies that the impulse response is nonnegative. The model (1) implies that the process is modeled by an impulse at $t = T$. The inequality (3) implies that T is larger than the median of the impulse response and the inequality (4) implies that the area of the model impulse response is larger than half the area under the impulse response of the system.

4. An example

The design procedure is illustrated by an example. Consider a system with the transfer function

$$G(s) = \frac{1}{(s+1)^6}.$$

A step response of the process is shown in Fig. 2. It is seen from this step response that the condition (3) is satisfied for the sampling period $T = 7.5$. The parameter b was chosen to be $b = 1.5$.

The response of the closed loop system to a step command signal and a step load disturbance at time 100 is shown in Fig. 3.

FIG. 2. Step response of the system.

FIG. 3. Response of a system to a step change in the command signal and a unit step load disturbance at time 100.

5. Conclusions

It has been demonstrated in a simple case that good control can be obtained by designing a regulator for a simplified process model. It would be of interest to extend this result to other design procedures and other model classes. Results in this direction are given in Åström (1980).

Acknowledgements—This work has been partially supported by DOE under contract ET-78-C-01-3394.

References

- Åström, K. J. (1976). Flow systems. In Y. C. Ho and S. K. Mitter (editors), *Directions in Large Scale Systems*. Pergamon Press, New York.

- Åström, K. J. (1980). Robustness of a design method based on assignment of poles and zeros. To appear in *IEEE Trans. AC*.
- Desoer, C. A. and M. Vidyasagar (1975). *Feedback Systems Input-Output Properties*. Academic Press, New York.
- Mehra, K. R. and R. Rouhani (1979). Theoretical considerations on model algorithmic control. Submitted to *IEEE Trans. AC*.
- Mehra, R. K., R. Rouhani, A. Rault and J. G. Reid (1979). Model algorithmic control. Preprints 1979 Joint Automatic Control Conference, Denver, Colorado.
- Richalet, J., A. Rault, J. L. Testud and J. Papon (1978). Model predictive heuristic control: Applications to industrial applications. *Automatica* **14**, 413-428.
- Wiener, N. (1933). *The Fourier Integral and Certain of Its Applications*. Cambridge University Press, London.