

Contents

Introduction	ix
Vicenç PUIG and Silvio SIMANI	
Chapter 1. Mathematical Modeling and Fault Description	1
Silvio SIMANI	
1.1. Introduction	1
1.2. Model-based FDI techniques	2
1.3. Modeling of faulty systems	3
1.3.1. Fault modeling and description	5
1.3.2. Mathematical description	6
1.4. Residual generation	11
1.5. Residual generation techniques	14
1.5.1. Residual generation via parameter estimation	15
1.5.2. Observer-based approaches	18
1.5.3. Fault detection via parity equations	24
1.6. Change detection and symptom evaluation	28
1.7. Residual generation robustness problem	30
1.7.1. FDI H_∞ approach	32
1.7.2. Active and passive disturbance decoupling	35
1.8. Fault diagnosis technique integration	36
1.8.1. Fuzzy logic for residual generation	37
1.8.2. Neural networks for fault diagnosis	38
1.8.3. Neuro-fuzzy approaches to FDI	40
1.8.4. Fault detectability and isolability	42

1.8.5. NF model structure identification	43
1.8.6. NF residual generation for FDI	44
1.9. Conclusion	46
1.10. References	47
Chapter 2. Structural Analysis	57
Mattias KRYSANDER and Erik FRISK	
2.1. Introduction	57
2.2. Background	58
2.2.1. Structural models	58
2.2.2. Dulmage–Mendelsohn decomposition and matchings	60
2.2.3. Dulmage–Mendelsohn decomposition and simulation	63
2.3. Fault isolability analysis	64
2.3.1. Fault detectability analysis	64
2.3.2. Fault isolability analysis	65
2.3.3. Canonical isolability decomposition of the overdetermined part	67
2.4. Testable submodels	69
2.4.1. Basic definitions	69
2.4.2. MSO algorithm	71
2.4.3. Residual generation based on matching	72
2.5. Sensor placement	74
2.5.1. The basic sensor placement problem	74
2.5.2. A structural approach	75
2.6. Summary and discussion	80
2.7. References	81
Chapter 3. Set-based Fault Detection and Isolation	83
Ye WANG and Vicenç PUIG	
3.1. Introduction	83
3.2. Notations, definitions and properties	84
3.3. Problem statement	86
3.3.1. Uncertain discrete-time linear systems	86
3.3.2. Set-based methods	86
3.3.3. FDI problem statement	88
3.4. Proposed techniques	89
3.4.1. Set-membership approach	89
3.4.2. Zonotopic observer	90
3.4.3. Relationship between set-based methods	91
3.5. Design methods	92
3.5.1. Robustness conditions	92
3.5.2. Fault sensitivity condition	96

3.6. Fault detection and isolation procedures	99
3.6.1. Fault detection	99
3.6.2. Fault isolation	100
3.7. Application example: quadruple-tank system	101
3.7.1. Results with robustness condition	105
3.7.2. Results with robustness and fault sensitivity conditions	105
3.8. Conclusion	105
3.9. References	109
Chapter 4. Diagnosis of Stochastic Systems	111
Gregory PROVAN	
4.1. Introduction	111
4.2. Stochastic diagnosis task	113
4.2.1. Notation	113
4.2.2. Problem formulation	113
4.2.3. Representing uncertainty	115
4.3. Inference methods for diagnosis task	116
4.3.1. Difference with other tasks	116
4.4. Model-based approach	117
4.4.1. Traditional FDD methods	117
4.4.2. Bayesian inversion/filtering	120
4.5. Data-driven approaches	122
4.5.1. ML methods	123
4.5.2. Statistical methods	124
4.6. Hybrid approaches: surrogate methods	125
4.6.1. Fitting surrogate models via sampling	125
4.7. Comparative analysis of approaches	126
4.8. Summary and conclusions	127
4.9. References	128
Chapter 5. Data-Driven Methods for Fault Diagnosis	131
Silvio SIMANI	
5.1. Introduction	131
5.2. Models for linear system fault diagnosis	133
5.3. Parameter estimation methods for fault diagnosis	135
5.3.1. Data-driven method in ideal conditions	135
5.3.2. Data-driven methods in real scenarios	138
5.3.3. Algebraic Frisch scheme	139
5.3.4. Dynamic Frisch scheme	141
5.3.5. MIMO case Frisch scheme	145
5.4. Nonlinear dynamic system identification	146
5.4.1. Piecewise affine model	147
5.4.2. Hybrid model structure	148
5.4.3. Nonlinear system approximation	149

5.4.4. Model continuity and domain partitioning	151
5.4.5. Local affine model estimation	154
5.4.6. Multiple-model estimation	158
5.5. Fuzzy data-driven approach to fault diagnosis	164
5.5.1. Fuzzy model identification	165
5.5.2. Takagi–Sugeno prototypes	167
5.5.3. Data-driven fuzzy modeling	170
5.5.4. Clustering methods	170
5.5.5. Fuzzy c-means clustering algorithms	172
5.5.6. Gustafson–Kessel clustering algorithm	174
5.5.7. Optimal number of clusters	176
5.6. Fuzzy model identification	176
5.6.1. Nonlinear model identification	178
5.6.2. Product space clustering identification	181
5.6.3. Fuzzy clustering model identification	183
5.6.4. Antecedent membership function estimation	183
5.6.5. Estimating consequent parameters	185
5.7. Conclusion	189
5.8. References	189
Chapter 6. The Artificial Intelligence Approach to Model-based Diagnosis	197
Belarmino PULIDO, Carlos J. ALONSO-GONZÁLEZ and Anibal BREGON	
6.1. Introduction	197
6.2. Case studies	199
6.3. Knowledge-based diagnosis systems	201
6.3.1. Diagnosis task and system model	203
6.3.2. Diagnosis of physical devices	206
6.3.3. Limits of KBS for diagnosis of physical devices	207
6.4. Model-based diagnosis	208
6.4.1. Formalization of consistency-based diagnosis and its first implementation, GDE	209
6.5. CBD for dynamic systems	217
6.5.1. Different approaches for CBD of dynamic systems	219
6.5.2. PCs for the three-tank system case study	222
6.6. Conclusion	224
6.7. References	226
List of Authors	231
Index	233
Summary of Volume 2	237