
Contents

Preface	ix
List of Notations	xiii
Chapter 1. Representation of Systems: A Historical Overview . . .	1
1.1. Transfer functions and matrices	1
1.1.1. Transfer functions	1
1.1.2. Transfer matrices	3
1.1.3. The discrete-time case	6
1.2. State-space representation	7
1.2.1. Continuous-time state-space systems	7
1.2.2. Discrete-time state-space systems	7
1.2.3. Controllability and observability	8
1.2.4. Poles of a state-space system	11
1.2.5. Stability of linear time-invariant systems	13
1.3. “Geometric” approach	14
1.3.1. Formalism of the geometric approach	14
1.3.2. Reachable and non-observable subspaces	15
1.3.3. State-feedback controls, observers	16
1.3.4. Canonical Kalman decomposition, stabilizability and detectability	17
1.4. Polynomial matrix description	21
1.4.1. PBH test (Hautus criterion)	21
1.4.2. Rosenbrock representation	23
1.5. The behavioral approach	26
1.5.1. Controllability without control variables	26
1.5.2. Observability in the behavioral approach	30
1.6. Module of a system	32
1.6.1. Using modules in control theory	32

1.6.2. The Fliessian approach	33
1.6.3. Characterization in terms of modules of controllability and observability	34
1.7. The formalism of algebraic analysis	35
1.7.1. Nature of algebraic analysis	35
1.7.2. Oberst's contribution and its consequences	35
Chapter 2. Linear Systems: Concepts and General Results	43
2.1. Control systems	43
2.1.1. The formalism of control systems	43
2.1.2. Transfer matrix: general case	45
2.1.3. State-space representation of a control system	46
2.2. Strict equivalence of Rosenbrock systems	49
2.2.1. Admissible Rosenbrock representations	49
2.2.2. Strict equivalence	51
2.3. Controllability, observability and their duality: the algebraic point of view	55
2.3.1. Algebraic controllability	55
2.3.2. Algebraic controllability of state-space systems (continuous time)	57
2.3.3. Algebraic controllability of state-space systems (discrete-time)	63
2.3.4. Algebraic duality	66
2.3.5. Algebraic observability and the algebraic duality principle	74
2.4. Reachability, observability and their duality: Kalmanian point of view	77
2.4.1. Complete controllability of a state-space system (continuous time)	78
2.4.2. Complete reachability and controllability of a state-space system (discrete-time)	83
2.4.3. Observability of state-space systems (continuous-time)	86
2.4.4. Complete observability and constructibility of state-space systems (discrete-time)	91
Chapter 3. Poles and Zeros of Linear Systems, Interconnectedness and Stabilization	97
3.1. Poles and zeros of continuous or discrete invariant linear systems	97
3.1.1. System poles, transmission poles and zeros	97
3.1.2. Input–output-decoupling zeros and hidden modes	109
3.1.3. Relations between poles, transmission poles and hidden modes	112
3.1.4. Invariant zeros	113
3.1.5. Dynamic interpretation of different poles and zeros	118
3.2. Poles and zeros of interconnected systems	119
3.2.1. Diagram of a control system	119

3.2.2. System interconnection	120
3.2.3. Series interconnection	121
3.2.4. Parallel interconnection	126
3.2.5. Feedback interconnection	129
3.2.6. Youla-Kučera parametrization of stabilizing controllers	135
Chapter 4. Systems with Differential Equations and Difference Equations	145
4.1. Systems governed by functional differential equations	145
4.1.1. Functional differential equation of retarded type	146
4.1.2. Functional differential equations of neutral type	147
4.1.3. Case of infinite delays	149
4.1.4. Linear functional differential equations	151
4.1.5. Stability of functional differential equations	156
4.2. Time-invariant linear systems with lumped delays	159
4.2.1. Definition and simplified framing	159
4.2.2. Commensurability or incommensurability of delays	162
4.2.3. Case of commensurable delays	162
4.2.4. Homological questions	165
4.3. Time-invariant linear systems with distributed delays	172
4.3.1. Ring \mathcal{H} : case of non-commensurable delays	172
4.3.2. Rings \mathcal{H} and \mathcal{H}_0 : case of commensurable delays	180
4.3.3. Controllability and observability of \mathcal{H} -systems	181
4.3.4. Stability of \mathcal{H} -systems	182
4.3.5. Poles and zeros of \mathcal{H} -systems	185
Appendix. The Mathematics of the Theory of Systems	187
References	267
Index	279