Contents

Preface xi

Book Structure and Content xvii

Chapter 1. The Control Loop: Characterization and Behavior in Open Loop and Closed Loop 1

1.1. Introduction. 1
1.2. Definition and terminology 2
1.3. The plant 2
1.3.1. Definition 2
1.3.2. From a modeling difficulty to a pragmatic approach to disturbances 3
1.4. Functional representation of the control loop 5
1.4.1. Block diagram and corresponding transfers 5
1.4.2. Regarding the gap detector 6
1.5. Open-loop transmittance 9
1.5.1. Definition 9
1.5.2. General expression 9
1.5.3. Regarding the input impedance of the open loop 10
1.5.4. Open-loop Nichols locus: elementary form and characteristic quantities 12
1.5.5. Left-hand criterion in the Nichols plane 14
1.6. Closed-loop transmittances 19
1.6.1. Transmittance in tracking 20
1.6.2. Transmittance in regulation 21
1.6.3. A tracking-regulation dilemma? 22

1.7. Input sensitivity 23
1.7.1. Input sensitivity in tracking 24
1.7.2. Input sensitivity in regulation 24
1.7.3. Input sensitivity in tracking and regulation 25
1.8. Behavior and frequency performances in tracking and regulation 34
1.8.1. Frequency and time behavior 35
1.8.2. Frequency performances 37
1.8.3. Regarding the effect of the increase in frequency ω_u 38
1.9. Dynamics in tracking and regulation 40
1.10. Charts in tracking and regulation 42
1.10.1. Chart in tracking: Nichols chart 42
1.10.2. Chart in regulation: dual of the Nichols chart 45
1.10.3. Passage from the Nichols chart to its dual 48
1.10.4. A little background 49

Chapter 2. The Control Loop: Stability and Stability Degree, Precision, Dynamic Performances and Controller Synthesis 51

2.1. Introduction 51
2.2. Stability 52
2.2.1. Definition 52
2.2.2. Fundamental stability condition 52
2.2.3. Stability algebraic criteria 53
2.2.4. Stability graphic criteria 54
2.3. Stability margins 58
2.3.1. Gain margin 59
2.3.2. Phase margin 59
2.4. Stability degree 69
2.4.1. Time domain 69
2.4.2. Frequency domain 70
2.4.3. Comparison with pole-placement control: an observation confirmed by section 2.4.2 71
2.5. Precision 73
2.5.1. Definition 73
2.5.2. Precision in tracking and regulation 74
2.5.3. Precision in steady state 74
2.6. Stability degree–precision dilemma 77
2.6.1. Definition 77
2.6.2. Highlighting the dilemma in the Nichols plane 77
2.6.3. Compromise between stability degree and precision, and optimum adjustment 78
2.6.4. Improving the compromise between stability degree and precision 78

2.6.5. Bringing the dilemma into question 79
2.7. Dynamics 80
2.8. Time dynamic performances. 80
2.9. Frequency dynamic performances 81
2.10. Determination of dynamics. 81
2.10.1. Overshoot. 81
2.10.2. Damping 82
2.10.3. Rapidity. 82
2.11. Study consideration for the controller synthesis 83
2.12. Controller phase at frequency ω_u 84
2.13. Type of controller 85
2.13.1. Phase-lead correction. 85
2.13.2. Phase-lag correction 87
2.13.3. An additional correction to obtain a PID regulator 89
2.14. Example of a practical task: detailed study of the single phase-lead controller 90

Chapter 3. An Overview of Linearizing Approaches 95

3.1. Introduction. 95
3.2. Linearization by immersion 96
3.2.1. Principle 96
3.2.2. Application 97
3.3. Linearization by high gain 102
3.3.1. Principle 102
3.3.2. Application 103
3.3.3. Conclusion and comments 104
3.4. Linearization by disturbance rejection 105
3.4.1. Principle 105
3.4.2. Application 105
3.4.3. Conclusion and comments 107
3.5. Linearization of the plant around a nominal trajectory: tangent linearized 107
3.5.1. Principle 107
3.5.2. Application 110
3.6. Additional discussion provided by Brigitte d'Andréa-Novel. 116

Chapter 4. High-Gain, Feedforward, Internal-Model, Quadratic-Criterion and Predictive Controls: From Principle to Control Loop 119

4.1. Introduction. 119
4.2. High-gain control 122
4.2.1. Principle 122

4.2.2. From high-gain control to control loop 123
4.2.3. Input sensitivity 125
4.3. Feedforward control 127
4.3.1. Principle 127
4.3.2. From feedforward to reference filtering of the elementary control loop 129
4.3.3. Tracking and regulation 130
4.4. Internal-model control 131
4.4.1. Principle 131
4.4.2. From internal-model control to control loop 133
4.4.3. Robustifying strategies 135
4.4.4. From internal model to high-gain control 139
4.5. Quadratic-criterion control 141
4.5.1. On control law synthesis 141
4.5.2. A property of linear systems that is decisive in this area 141
4.5.3. Study plant 142
4.5.4. Control objective and strategy 144
4.5.5. Regulator synthesis through minimization of a quadratic criterion 145
4.5.6. From quadratic-criterion control to control loop 149
4.6. Predictive control 153
4.6.1. Principle 153
4.6.2. From CGPC to LQ then LQG control 155
4.6.3. LQ and quadratic-criterion control 157
4.6.4. Study plant 159
4.6.5. Control law synthesis 159
4.6.6. From predictive control to control loop 163
4.6.7. On the phase-lead regulator stemming from the change to the control loop 166
4.6.8. A specific scenario suitable as the basis of an exercise or a problem 172

Chapter 5. On the Three Generations of CRONE Control 175

5.1. Introduction 175
5.2. From the porous dyke to first- and second-generation CRONE control 177
5.2.1. First interpretation of the relaxation model: first-generation CRONE control 178
5.2.2. Second interpretation of the relaxation model: second-generation CRONE control 181

5.3. Second-generation CRONE control and uncertainty domains 185
5.3.1. Uncertainty domains 185
5.3.2. Particular open-loop uncertainty domains 187
5.3.3. Adequacy of the second-generation CRONE control template to the particular uncertainty domains 188
5.4. Generalization of the vertical template through the third-generation CRONE control 189
5.4.1. First level of generalization 189
5.4.2. Second level of generalization 193
5.4.3. Open-loop transfer integrating the curvilinear template 196
5.4.4. Optimization of the open-loop behavior 198
5.4.5. Structure and parametric estimation of the controller 200
5.4.6. Application 200
5.5. An appendix on the frequency response describing the generalized template 203

Solved Problems 205

Presentation of Problem 1: Elementary Synthesis of a PID Regulator Based on the Single Phase-Lead Controller 207

Presentation of Problem 2: Improvement of the Elementary Synthesis of a PID Regulator by Reducing Transitional Frequency Dispersion 219

Presentation of Problem 3: Synthesis of a PID Regulator Based on Three Phase-Lead Controller Structures: Comparison and Choice of the Best Structure 229

Presentation of Problem 4: Linearizing Control of a Motor Shaft: Linearization by Immersion 241

Presentation of Problem 5: Linearizing Control of a Motor Shaft: Linearization by Disturbance Rejection 255

Presentation of Problem 6: High-Gain Control: Characterization in Tracking and Regulation 265

Presentation of Problem 7: Feedforward Control: Characterization in Tracking and Regulation by a Direct Approach and by an Indirect Approach via a Reference Prefilter 275

Presentation of Problem 8: Synthesis of an Internal-Model Control Using a PID Controller of the Equivalent Elementary Control Loop 283

Presentation of Problem 9: Quadratic-Criterion Control 295

Presentation of Problem 10: Synthesis of a Constant Phase-Lead CRONE Controller: The Essential Stage in the Synthesis of the Fractional PID Whose (Integer) Integration at Low Frequency Simply Results from a Cascade Proportional–Integral 305

Presentation of Problem 11: Synthesis of a Constant Phase-Lead CRONE Controller with Successively Symmetrical and Asymmetrical Frequency Placement 319

Presentation of Problem 12: Synthesis of a Constant Phase-Lag CRONE Controller and Synthesis Parameters of the Third-Generation CRONE Control 331

Presentation of Problem 13: Synthesis of a Variable-Phase CRONE Controller for the Synthesis of a Narrow-Band (Vertical and Generalized) Template 347

Appendices 365

Appendix 1: From Regulation Function to Active Noise Control . . 367

Appendix 2: Closed-Loop Behavior and Dynamic Performance of Second-Generation CRONE Control 375

Appendix 3: Iso-overshoot Contours and Isodamping Contours . . 389

References 409

Index 413