

Contents

Preface — V

1 System Model — 1

1.1 Introduction — 1

1.2 Models of Systems — 1

1.2.1 Differential Equation — 1

1.2.2 Transfer Function — 4

1.2.3 The State Space Model — 6

1.3 Transition From One Mathematical Model to Another — 16

1.3.1 From Differential Equation to Transfer Function for SISO Systems — 16

1.3.2 From Transfer Function to Differential Equation for SISO Systems — 17

1.3.3 From $G(s)$ to $g(t)$ and Vice Versa — 17

1.3.4 From State Equations to Transfer Function Matrix — 17

1.3.5 From Transfer Function Matrix to State Equations for SISO Systems — 19

1.4 Summary — 22

Appendix Three Power Generation Models — 22

Exercise — 28

2 Linear Transformation of State Vector — 31

2.1 Linear Algebra — 31

2.2 Transform to Diagonal Form and Jordan Form — 36

Exercise — 45

3 Solution of State Space Model — 47

3.1 Introduction — 47

3.2 Solution of LTI State Equations — 47

3.3 State Transfer Matrix — 50

3.3.1 Properties — 50

3.3.2 Calculating the State Transition Matrix — 54

3.4 Discretization — 61

3.5 Solution of Discrete Time Equation — 64

3.6 Summary — 70

Exercise — 70

4 Stability Analysis — 72

4.1 Introduction — 72

4.2 Definition — 72

4.3 Stability Criteria — 82

4.3.1 Lyapunov's Second Method — 82

4.3.2 State Dynamics Stability Criteria for Continuous Linear Systems — 90

4.3.3 State Dynamics Stability Criteria for Discrete Systems — 98

4.4 Summary — 100

Exercise — 100

5 Controllability and Observability — 103

5.1 Introduction — 103

5.2 Definition — 104

5.2.1 Controllability — 104

5.2.2 Observability — 105

5.3 Criteria — 106

5.3.1 Controllable Criteria — 106

5.3.2 Controllable Examples — 112

5.3.3 Observable Criteria — 115

5.3.4 Observable Examples — 117

5.4 Duality System — 120

5.4.1 Definition — 120

5.4.2 Properties of Duality Systems — 121

5.5 Canonical Form — 122

5.5.1 Controllability Canonical Form of Single Input Systems — 122

5.5.2 Observability Canonical Form of Single Output Systems — 128

5.5.3 Examples — 130

5.5.4 Observability and Controllability Canonical Form of Multiple Input Multiple Output Systems — 132

5.6 System Decomposition — 134

5.6.1 Controllability Decomposition — 134

5.6.2 Observability Decomposition — 137

5.6.3 Controllability and Observability Decomposition — 140

5.6.4 Minimum Realization — 145

5.7 Summary — 152

Exercise — 152

6	State Feedback and Observer — 156
6.1	Introduction — 156
6.2	Linear Feedback — 156
6.2.1	State Feedback — 156
6.2.2	Output Feedback — 157
6.2.3	Feedback From Output to $\dot{x}$ — 158
6.3	Pole Assignment — 159
6.3.1	Sufficient and Necessary Condition for Arbitrary Pole Assignment — 159
6.3.2	Methods to Assign the Poles of a System — 162
6.3.3	Examples — 166
6.4	State Estimator — 171
6.4.1	Introduction — 171
6.4.2	State Estimator — 172
6.5	State Feedback Based on State Estimator — 185
6.6	Summary — 188
Appendix	State Feedback and Observer for Main Steam Temperature Control in Power Plant Steam Boiler Generation System — 188
Exercise	— 192
 Bibliography — 195	
 Index — 197	