

# Control Systems Synthesis: A Factorization Approach, Part I (Synthesis Lectures on Control and Mechatronics)

By Mathukumalli Vidyasagar

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## Control Systems Synthesis: A Factorization Approach, Part I (Synthesis Lectures on Control and Mechatronics) By Mathukumalli Vidyasagar

This book introduces the so-called "stable factorization approach" to the synthesis of feedback controllers for linear control systems. The key to this approach is to view the multi-input, multi-output (MIMO) plant for which one wishes to design a controller as a matrix over the fraction field  $F$  associated with a commutative ring with identity, denoted by  $R$ , which also has no divisors of zero. In this setting, the set of single-input, single-output (SISO) stable control systems is precisely the ring  $R$ , while the set of stable MIMO control systems is the set of matrices whose elements all belong to  $R$ . The set of unstable, meaning not necessarily stable, control systems is then taken to be the field of fractions  $F$  associated with  $R$  in the SISO case, and the set of matrices with elements in  $F$  in the MIMO case. The central notion introduced in the book is that, in most situations of practical interest, every matrix  $P$  whose elements belong to  $F$  can be "factored" as a "ratio" of two matrices  $N, D$  whose elements belong to  $R$ , in such a way that  $N, D$  are coprime. In the familiar case where the ring  $R$  corresponds to the set of bounded-input, bounded-output (BIBO)-stable rational transfer functions, coprimeness is equivalent to two functions not having any common zeros in the closed right half-plane including infinity. However, the notion of coprimeness extends readily to discrete-time systems, distributed-parameter systems in both the continuous- as well as discrete-time domains, and to multi-dimensional systems. Thus the stable factorization approach enables one to capture all these situations within a common framework. The key result in the stable factorization approach is the parametrization of all controllers that stabilize a given plant. It is shown that the set of all stabilizing controllers can be parametrized by a single parameter  $R$ , whose elements all belong to  $R$ . Moreover, every transfer matrix in the closed-loop system is an affine function of the design parameter  $R$ . Thus problems of reliable stabilization, disturbance rejection, robust stabilization etc. can all be formulated in terms of choosing an appropriate  $R$ .

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
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