AFRL-SR-AR-TR-09-0188

REPORT DOCUMENTATION PAGE

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1. REPORT DATE *(DD-MM-YYYY)*	2. REPORT TYPE	3. DATES COVERED *(From - To)*
05/06/2009	final	03/01/2008-111/30/2008

4. TITLE AND SUBTITLE
Robust Adaptive Control of Multivariable Nonlinear Systems

5a. CONTRACT NUMBER
FA9550-08-1-0135

5b. GRANT NUMBER
FA9550-08-1-0135

5c. PROGRAM ELEMENT NUMBER

6. AUTHOR(S)
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5d. PROJECT NUMBER

5e. TASK NUMBER

5f. WORK UNIT NUMBER

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8. PERFORMING ORGANIZATION REPORT NUMBER

9. SPONSORING/MONITORING AGENCY NAME(S) AND ADDRESS(ES)
AFOSR/NL
875 N Randolph St
Arlington, VA 22203

10. SPONSOR/MONITOR'S ACRONYM(S)

11. SPONSOR/MONITOR'S REPORT NUMBER(S)

12. DISTRIBUTION/AVAILABILITY STATEMENT

DISTRIBUTION A: APPROVED FOR PUBLIC RELEASE

13. SUPPLEMENTARY NOTES

14. ABSTRACT
Our research is focused on development of reconfigurable robust adaptive control architectures that can be designed with systematic methods to have guaranteed performance specifications and robustness/stability margins. Research in this direction over the past three years has led to a powerful set of tools shaping The Theory of Fast and Robust Adaptation. This new paradigm for design of adaptive control systems embeds the robustness specifications explicitly into the control problem formulation (control objective) and enables to predict the closed-loop system performance a priori based on the conservative bounds of uncertainty. The time-delay margin of these architectures can be systematically tuned using methods from classical and robust control.

15. SUBJECT TERMS

16. SECURITY CLASSIFICATION OF:			17. LIMITATION OF ABSTRACT	18. NUMBER OF PAGES	19a. NAME OF RESPONSIBLE PERSON
a. REPORT	b. ABSTRACT	c. THIS PAGE			19b. TELEPHONE NUMBER *(Include eree code)*

Standard Form 298 (Rev. 8/98)
Prescribed by ANSI Std. Z39.18
Adobe Professional 7.0

ROBUST ADAPTIVE CONTROL OF MULTIVARIABLE NONLINEAR SYSTEMS

FA9550-08-1-0135 (March - November, 2008)

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Abstract
Our research is focused on development of reconfigurable robust adaptive control architectures that can be designed with systematic methods to have guaranteed performance specifications and robustness/stability margins. Research in this direction over the past several years has led to a powerful set of tools shaping *The Theory of Fast and Robust Adaptation.* This new paradigm for design of adaptive control systems embeds the hardware specification explicitly into the control problem formulation (control objective) and enables to predict the closed-loop system performance *a priori* based on the conservative bounds of uncertainty. Moreover, it leads to analytically provable robustness/stability margins. The performance limitations are proved to be consistent with the hardware limitations: the available CPU sets the adaptation rate, while the control channel specifications define the limits of the achievable performance. Similar to linear systems, the time-histories of system's input/output signals scale with the change of reference inputs, uncertain parameters and initial conditions. Various architectures of this theory have been flight tested by our collaborators, which include design of autopilots for MAVs, augmentation of off-the-shelf autopilots for flight test validation of robustness metrics in the presence of control surface failures[1], and time-critical coordination of UAVs within spatial constraints in the presence of time-varying communication network topology[2]. Other applications, verified in mid-to-high fidelity simulation environments, include design of control laws for validation of time-delay margins for unmanned unstable tailless aircraft and aerial refueling autopilot design[3], development of vision-based guidance laws, control of hypersonic vehicles, missile longitudinal autopilot design, control of CLV vehicle and control of flexible aircraft[4]. The key concepts and tools of this framework can be extended to a broader class of nonlinear controllers with an objective to quantify uniform performance bounds and guaranteed robustness metrics.

Status of effort

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[1] Leveraged by NASA LaRC IRAC Flight program
[2] Leveraged by ARO, and transitioned to NPS for further use in USSOCOM supported TNT exercises
[3] Leveraged by AFRL WP/Boeing under CerTA FCS program
[4] Leveraged by NASA LaRC under *Sensorcraft* project of Air Force

During this time period we worked on extension of L_1 adaptive controller to output feedback and its application to Boeing's missile longitudinal autopilot design and NASA's CLV model.

Output feedback solution [10]: The key contribution of the past year was the output feedback solution for the class of systems

$$y(s) = A(s)(u(s) + d(s)),$$

where $A(s)$ is strictly proper unknown transfer function, while $d(s)$ is the Laplace transform of unknown nonlinearities $f(t, y(t))$, subject to $|f(t, y_1) - f(t, y)| \le L|y_1 - y_2|$. The control objective is to design an adaptive output feedback controller to ensure that y follows that output of a given transfer function $y_m(s) = M(s)r(s)$ for the reference input $r(s)$, where $M(s)$ is **not** necessarily strictly positive real (SPR). The main result is given by the following theorem.

Theorem: Consider the following reference system dynamics:

$$y_{ref}(s) = M(s)(u_{ref}(s) + \sigma_{ref}(s)), \;\; u_{ref}(s) = C(s)(r(s) - \sigma_{ref}(s))$$
$$\sigma_{ref}(s) = ((A(s) - M(s))u_{ref}(s) + A(s)d_{ref}(s)) / M(s)$$

where $d_{ref}(s)$ is the Laplace transform of $f(t, y_{ref}(t))$, while $C(s)$ is strictly proper low-pass filter with DC gain 1, verifying stability of $H(s) = \dfrac{A(s)M(s)}{C(s)A(s) + (1 - C(s))M(s)}$ and ensuring that the 1-norm of the cascaded system $H(s)(1 - C(s))$ verifies the following upper bound $\|H(s)(1 - C(s))\|_{L_1} L \le 1$. Then the reference system is BIBO stable. Moreover, the following adaptive output feedback controller

$$u(s) = C(s)r(s) - C(s)\frac{c_m^T(sI - A_m)^{-1}}{c_m^T(sI - A_m)^{-1}b_m}\hat{\sigma}(s)$$

where $(A_m \in R^{n\times n}, b_m \in R^n, c_m \in R^n)$ is the minimal realization of $M(s)$, while the piece-wise constant adaptive law for $\hat{\sigma}(t)$ is given by[5].

[5] The parameter T is the sampling rate of the CPU.

$$\hat{\sigma}(t) = \hat{\sigma}(iT), \quad t \in [iT,(i+1)T)$$
$$\hat{\sigma}(iT) = -\Phi^{-1}(T)\mu(iT), \quad i = 1,2,3,...$$
$$\Phi(T) = \int_0^T e^{\Lambda A_m \Lambda^{-1}(T-\tau)} \Lambda d\tau, \quad \Lambda = \begin{bmatrix} c_m^T \\ D\sqrt{P} \end{bmatrix}, \quad A_m^T P + P A_m = -Q$$
$$\mu(iT) = e^{\Lambda A_m \Lambda^{-1} T} 1_1 \tilde{y}(iT), \quad \tilde{y}(t) = \hat{y}(t) - y(t)$$

with D being the null-space of $c_m^T\left(\sqrt{P}\right)^{-1}$, $1_1 = [10...0]^T \in R^n$ and $\hat{y}(t)$ being the output of the following estimator dynamics (with unmatched estimation)

$$\dot{\hat{x}}(t) = A_m \hat{x}(t) + b_m u(t) + \hat{\sigma}(t)$$
$$\hat{y}(t) = c_m^T \hat{x}(t)$$

ensures that there exist constants γ_1, γ_2, proportional to T, such that

$$\left\|y - y_{ref}\right\|_{L_\infty} \le \gamma_1, \quad \left\|u - u_{ref}\right\|_{L_\infty} \le \gamma_2$$

Acknowledgment/Disclaimer

This work was sponsored (in part) by the Air Force Office of Scientific Research, USAF, under grants FA9550-05-1-0157, FA9550-08-1-0135. The views and conclusions contained herein are those of the authors and should not be interpreted as necessarily representing the official policies or endorsements, either expressed or implied, of the AFOSR or the U.S. Government.

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4. J. Wang, V. Patel, C. Cao, N. Hovakimyan, E. Lavretsky, Novel L_1 Adaptive Control Methodology for Aerial Refueling with Guaranteed Transient Performance, AIAA Journal of Guidance, Control and Dynamics, vol. 18, No. 1, pp. 182-193, 2008.
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22. C. Cao, N. Hovakimyan, L_1 Adaptive Controller for Nonlinear Systems in the Presence of Unmodelled Dynamics: Part II, American Control Conference, Seattle, WA, 2008.
23. C. Cao, N. Hovakimyan, L_1 Adaptive Controller for Systems in the Presence of Unmodeled Actuator Dynamics, *In Proc. of* 46th IEEE Conference on Decision and Control, New Orleans, LA, 2007.

Honors & Awards Received

- College of Engineering Faculty Fellow of Virginia Tech, 2006-2009
- Promoted to professor in 2007
- Moved to UIUC as Professor and Schaller Faculty Scholar of MechSE, 2008
- Invited Plenary Speaker at SIAM Conf. Contr. and Its Applications, 2007, San Francisco, CA
- Associate Fellow of AIAA, 2006
- Associate Editor of IEEE Transactions on Neural Networks, 2004 – 2008
- Associate Editor of IEEE Transactions on Control Systems Technology, 2005 – present
- Outstanding reviewer of AIAA Journal of Guidance, Control and Dynamics

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Transitions

- The theory has been transitioned to NASA LaRC for wind-tunnel testing of *Sensorcraft* and also for flight control law design for a CLV model. POC: I. Gregory, NASA LaRC, Hampton, VA 23681, Ph: 757-864-4075.
- The theory has been used to augment an existing autopilot (Piccolo) for accurate path following in the problem of time-critical cooperation of UAVs with spatial constraints in the presence of time-varying communication network topology. POC: Isaac Kaminer, MAE, NPS, Monterey, CA 93943, Phone: 831-656-3459 (further transition to USSOCOM in TNT exercises).
- The theory has been implemented for AAR (Autonomous Aerial Refueling) problem in collaboration with The Boeing Co., under CerTA FCS program from WP AFRL. The UAV model was provided by The Boeing Co., while the ICE vortex data were obtained from WP AFRL. POC: E. Lavretsky (Boeing), Technical Fellow, 5301 Bolsa Ave. MC H013-b318, Huntington Beach, CA 92647, Ph: 714-235-7736, D. Homan (WP AFRL).
- The theory has been implemented for hypersonic vehicle model of WP AFRL. POC: D. Doman, WP AFRL, e-mail: David.Doman@WPAFB.AF.MIL
- The theory has been implemented for missile longitudinal autopilot design, the model being provided by Raytheon. POC: R. Hindman, e-mail: Rick.Hindman@raytheon.com, B. Ridgely, e-mail: dbridgely@raytheon.com

New Discoveries

2008 Provisional Patent filed "Adaptive Control Devices and Methods for Systems of Unknown Relative Degree" (with C. Cao)