



COURSE DESCRIPTION CARD - SYLLABUS

Course name

Control theory

Course

Field of study

Automatic control and robotics

Area of study (specialization)

Level of study

First-cycle studies

Form of study

full-time

Year/Semester

3/5

Profile of study

general academic

Course offered in

polish

Requirements

compulsory

Number of hours

Lecture

30

Laboratory classes

15

Other (e.g. online)

Tutorials

15

Projects/seminars

Number of credit points

6

Lecturers

Responsible for the course/lecturer:

dr hab. inż. Dariusz Pazderski

email: dariusz.pazderski@put.poznan.pl

Wydział Automatyki, Robotyki i Elektrotechniki

ul.Piotrowo 3a, 61-138 Poznań

Responsible for the course/lecturer:

dr inż. Robert Bączyk

email: robert.baczyk@put.poznan.pl

Wydział Automatyki, Robotyki i Elektrotechniki

ul.Piotrowo 3a, 61-138 Poznań

Prerequisites

Knowledge: The student starting this subject should have basic knowledge of subjects such as Fundamentals of Automation, Mathematical Analysis, General Mechanics.

Skills: Should have the ability to solve basic problems covered by the required knowledge and the ability to obtain information from the indicated sources. He should also understand the need to expand his competences.

Social competences In addition, in terms of social competences, the student must present attitudes such as honesty, responsibility, perseverance, cognitive curiosity, creativity, personal culture, respect for other people.



Course objective

1. To provide students with knowledge of control theory and, in particular, knowledge related to dynamic control systems in order to prepare them substantively for issues related to their stability and the synthesis and analysis of control algorithms.
2. To develop students' skills related to modelling of dynamic systems, transformation of linear systems to equivalent forms, interpretation and study of controllability and observability of linear systems, study of state input and input-output stability, basic stability analysis according to the Lyapunov methodology. In addition, students will be skilled in the design of various observers and in solving selected optimisation problems of control systems and dynamic programming.

Course-related learning outcomes

Knowledge

1. has extended and in-depth knowledge of mathematics including algebra, geometry, analysis, probability and elements of discrete mathematics and logic, including mathematical methods and numerical methods necessary for the description and analysis of the properties of linear and basic nonlinear dynamic and static systems, description and analysis complex quantities, - [K1_W1]
2. description of random processes and uncertain quantities, description and analysis of combinational and sequential logic systems, description of control algorithms and analysis of the stability of dynamic systems, description, analysis and methods of signal processing in the time and frequency domains, numerical simulation of dynamic systems in the domain of continuous and time discrete; - [K1_W1]
3. has ordered knowledge of the theory of linear dynamical systems, including selected modeling methods and the theory of stability; knows and understands the basic properties of linear dynamic elements in the time and frequency domain and the properties of selected non-linear elements; knows and understands the design techniques of linear control systems using the description in the state space - [K1_W14]
4. is familiar with the current state and the latest development trends in the field of automation and robotics; - [K1_W21]

Skills

1. obtain information from literature, technical documentation and other sources, also in English; - [K1_U1]
2. can check the stability of linear and selected nonlinear objects and dynamical systems; - [K1_U12]
3. can design simple control systems for processes with one input and one output; can consciously use standard functional blocks of automation systems and shape dynamic properties of measurement paths; - [K1_U29]

Social competences



Methods for verifying learning outcomes and assessment criteria

Learning outcomes presented above are verified as follows:

Formative assessment:

a) in the field of lectures: on the basis of answers to questions about the material discussed in previous lectures,

b) in terms of exercises and labs: based on the assessment of the current progress of the tasks being solved,

Summative assessment:

a) in the field of lectures, verification of the assumed learning outcomes is carried out by:

i. assessment of the knowledge and skills shown in the written exam in the subject, which consists of 10 tasks for which 20 points can be obtained (2 points per task).

ii. assessment of knowledge and skills on the basis of individual discussion of written results (additional control questions),

b) in the field of exercises and labs, verification of the assumed learning outcomes is carried out by:

i. assessment of the student's preparation for individual auditorium exercises and assessment of skills related to the implementation of laboratory exercises,

ii. continuous assessment during each class (oral answers) - rewarding the increase in the ability to use the learned rules and methods,

iii. assessment of knowledge and skills related to the implementation of learning outcomes through one written test.

Obtaining additional points for activity during classes, especially for:

i. discuss additional aspects of the issue,

ii. effectiveness of applying the acquired knowledge while solving a given problem, iii. comments related to the improvement of teaching materials,

iv. identifying students' perceptual difficulties enabling ongoing improvement of the teaching process.

Programme content

The lecture program covers the following topics:

1. Dynamical systems and description of systems in the state space.

a) definition of a dynamical system

b) classes of dynamical systems



- c) typical forms of dynamic systems in the continuous time domain
 - d) the case of dynamic systems in the discrete time domain
 - e) LTI and LTV linear systems
 - f) relation between state space description and operator transmittance
 - g) example models
2. State and input transformations. Equivalent systems.
- a) basic concepts
 - b) linear transformations and normal forms
 - c) transformation into controllable and observable normal forms (the LTI case)
 - d) transformation to modal form (diagonal and Jordan form, real Jordan form)
 - e) Kalman decomposition and minimal representation
3. Selected properties of linear systems
- a) solution of the equation of state and properties of the transfer matrix
 - b) the concepts of controllability and observability
 - c) derivation of Kalman conditions
4. Selected stability issues
- a) BIBO stability (of finite input finite output type), BIBS stability (of finite input finite state type)
 - b) Lyapunov stability
 - c) definition of positive, negative, semi-positive, semi-negative Lyapunov functions with examples for linear and non-linear systems
 - d) stability criteria for LTI systems
 - e) classes of trajectories for the solution of an autonomous LTI system
5. Observers for linear systems
- a) derivation of the Luenberger observer and condition of applicability
 - b) Kalman filter as a case of stochastic observer
 - c) interpretation of the Kalman filter equations
6. Dynamic correction and design of linear control systems



- a) state feedback and output feedback
- b) stabilizability condition
- c) definition of input-output decoupling
- d) design of a decoupling algorithm for a linear system
- e) control algorithm using dynamic expansion
- f) design of decoupling control algorithm
- g) application of an observer application and separation principle

7 Elements of optimal control

- a) Elements of discrete minimisation of functions of many variables with equality constraints
- b) Definition of the Hamiltonian and Lagrange multipliers
- c) Necessary and sufficient conditions for quadratic optimisation,
- d) Pontriagin's maximum principle
- e) description of dynamic programming method for discrete systems
- f) quadratic optimisation of discrete systems using dynamic programming,

Auditorium exercises and laboratory exercises are conducted in the form of seven 2-hour classes each. In the audit exercises, students solve calculus tasks covering the content taught in the lecture. The modelling of systems, transformation of dynamics to normal forms, study of stability, controllability and observability, design of coupling from state and linear observers are considered in detail. The laboratory includes numerical and simulation exercises that are complementary to the content considered in the exercises, mainly due to the possibility of considering more complex cases.

Teaching methods

1. Lecture: traditional presentation on the board illustrated with examples.
2. Auditorium exercises: solving problems, case studies.

Bibliography

Basic

1. T. Kaczorek, Teoria układów regulacji automatycznej, Wydawnictwa Naukowo - Techniczne, 1974
2. P. De Larminat, Yves Thomas, Automatyka - układy liniowe, tom 2, Sterowanie, Wydawnictwa Naukowo - Techniczne, 1983



3. P. De Larminat, Yves Thomas, Automatyka - układy liniowe, tom 3, Sterowanie, Wydawnictwa Naukowo - Techniczne, 1983
4. Jean-Jacques E. Slotine, Weiping Li, Applied Nonlinear Control, Prentice Hall, 1995
5. R. C. Dorf, R. H. Bishop, Modern Control Systems, tenth edition, Pearson Educational International, Prentice Hall, 2005

Additional

1. A. Isidori, Nonlinear Control Systems, Springer Verlag, 1995

Breakdown of average student's workload

	Hours	ECTS
Total workload	150	6,0
Classes requiring direct contact with the teacher	60	3,0
Student's own work (literature studies, preparation for laboratory classes/tutorials, preparation for tests/exam, project preparation) ¹	90	3,0

¹ delete or add other activities as appropriate