Contents

1 Introduction to Control Reconfiguration 1
1.1 Fault-Tolerant Control 1
1.2 Fault Detection 2
1.3 Control Reconfiguration 3
1.4 Reconfiguration Goal 5
1.5 Aim of this Manuscript 5
1.6 Structure of the Manuscript 6

2 Literature Overview 9
2.1 Fault-Tolerant Control 9
2.2 Specific Reconfiguration Approaches 10
2.3 General Reconfiguration Approaches 11
2.4 Alternatives to Reconfiguration 12
2.5 Advanced Control Theory 14

Part I. Reconfiguration Problem

3 Running Example: the 2-Tank System 17
3.1 Nonlinear Model 17
3.2 Linear Model 18
3.3 Controller 19
3.4 Faults 20
3.5 Analysis 21

4 General Reconfiguration Problem 25
4.1 Overview 25
4.2 Modelling the System and the Fault 25
4.3 Control Loop 28
4.4 Reconfiguration Block 31
4.5 Reconfiguration Goals 33
4.6 2-Tank Example 38

5 Linear Reconfiguration Problem 41
5.1 Nominal Control Loop 41
5.2 Fault and Reconfiguration 42
5.3 Reconfiguration Goals 45
5.4 Specific Faults 47
5.5 2-Tank Example 50

Part II. Linear Solution Approaches

6 Direct Reconfiguration Using a Static Block 55
6.1 Direct Reconfiguration After Actuator Faults 55
6.2 Solvability Consideration 56
6.3 Derivation of a Static Reconfiguration Block 57
6.4 Reconfiguration Algorithm 59
6.5 Analysis 60
6.6 Application to the 2-Tank Example 62
6.7 Pseudo-Inverse Method 63
6.8 Reconfiguration After Sensor Faults 66
6.9 Conclusion 67

7 Reconfiguration Using a Virtual Sensor 69
7.1 Stabilising Reconfiguration After Sensor Faults 69
7.2 Solvability Consideration 70
7.3 Derivation of the Virtual Sensor 71
7.4 Reconfiguration Algorithm 74
7.5 Analysis of the Virtual Sensor 75
7.6 Application to the 2-Tank Example 78
7.7 Conclusion 79

8 Reconfiguration Using a Virtual Actuator 81
8.1 Stabilising Reconfiguration After Actuator Faults 81
8.2 Solvability Consideration 82
8.3 Derivation of the Virtual Actuator 83
8.4 Reconfiguration Algorithm 88
8.5 Analysis of the Reconfigured Closed-Loop System 89
8.6 Application to the 2-Tank Example 92
8.7 Duality of Virtual Sensor and Actuator 96
8.8 Reconfiguration After Internal Faults 98
8.9 Conclusion 101

9 Reconfiguration with Set-Point Tracking 103
9.1 Weak Reconfiguration After Actuator Faults 103
9.2 Solvability Consideration 104
9.3 Approach 1: Zero Placement 105
9.4 Approach 2: Integrating Controller 110
9.5 Analysis and Comparison 112
9.6 Application to the 2-Tank Example 114
9.7 Dual Approach For Sensor Faults 116
9.8 Conclusion 117

10 Reconfiguration by Disturbance Decoupling 119
10.1 Strong Reconfiguration After Actuator Faults 119
10.2 Solvability Condition 120
10.3 Interpretation as a Disturbance Decoupling Problem 122
10.4 Geometric Approach 125
10.5 Reconfiguration Algorithm 130
10.6 Analysis of Reconfigured System 132
10.7 Application to the 2-Tank Example 135
10.8 Dual Approach for Sensor Faults 138
10.9 Conclusion 139

Part III. Structural Tests for Control Reconfiguration

11 Structural Models 143
11.1 Introduction to Structural Models 143
11.2 Structural Matrices 144
11.3 Structural Digraphs 148
11.4 Paths in a Structural Graph 150
11.5 Digraphs and Matrix Models 152
11.6 Weighted Digraphs 154
11.7 Bi-partite Graphs 156
11.8 Structure of Non-Linear Systems 158
11.9 Diagnosis Based on Structural Graphs 159

12 Basic Structural Properties 161
12.1 Defining Structural Properties 161
12.2 s-Controllability and s-Observability 162
12.3 Stabilisability 165
12.4 Reduced Control Problem 167
12.5 Solvability of the Weak Reconfiguration Problem 169
12.6 Application to the 2-Tank Example 170

13 Solvability of Disturbance Decoupling 173
13.1 Disturbance Decoupling 173
13.2 Variants of the Disturbance Decoupling Problem 174
13.3 Disturbance Decoupling of the First Kind 177
13.4 Structural Rank of a System 178
13.5 Almost Disturbance Decoupling 181
13.6 Known-Disturbance Decoupling 183
13.7 Finding a Minimal Difference System 184

14 Structural Solutions to Disturbance Decoupling 189
14.1 Idea of the Iterative Algorithm 189
14.2 Algorithm for Single-Variable Decoupling 190
14.3 Structural Test 193
14.4 Matrix-Based Algorithm for Single-Variable Decoupling 194
14.5 Optimising the Matrix-Based Algorithm 198
14.6 Multi-variable Cancellation 199
14.7 Strong Structural Test 201

15 A Structural Reconfiguration Algorithm for Actuator Faults 205
15.1 Test for Reconfigurability 205
15.2 Reconfiguration After Actuator Faults 207
15.3 Reconfiguration in a Fault-Tolerant Control Scheme 210
15.4 Conclusion 211

Part IV. Application Examples

16 Reconfiguration of the 3-Tank System 215
16.1 Nominal 3-Tank System 215
16.2 Valve 2 Blocked Open 220
16.3 Valve 2 Blocked Closed 223
16.4 Pump 1 Blocked 224
16.5 Conclusion 227

17 Reconfiguration of a Helicopter Model 229
17.1 Helicopter Model 229
17.2 Fault in a Main Rotor 233
17.3 Fault in Both Main Rotors 236
17.4 Fault in the Lateral Rotors 239
17.5 Conclusion 242

18 Conclusion 243
18.1 Summary 243
18.2 Outlook 244

Part V. Appendices

Glossary 249
A.1 Terms of Fault-Tolerant Control 249
A.2 List of Important Symbols 251

RECONF – A Toolbox for Reconfiguration 253
B.1 Overview 253
B.2 MATLAB Functions 253
B.3 Simulink Integration 255

References 261