Paper

H_∞ Control System Design of the Magnetic Suspension System Considering Initial State Uncertainties

Toru Namerikawa* Member
Masayuki Fujita** Non-member

This paper deals with H_∞ control attenuating initial-state uncertainties, and its application to a magnetic suspension system. H_∞ control problem, which treats as a mixed attenuation of disturbance and initial-state uncertainty for linear time-invariant systems in the infinite-horizon case, is examined. The mixed attenuation supplies H_∞ controls with good transients and assures H_∞ controls of robustness against initial-state uncertainty. We apply this method to a magnetic suspension system, and evaluate attenuation property of the proposed disturbance and initial-state uncertainty via simulations and experiments.

Keywords: H_∞ Control, DIA Control, Initial-State Uncertainties, Magnetic Suspension Systems

1. Introduction

H_∞ control for linear time-invariant systems attenuates the effect of disturbances on controlled outputs and is originally defined under the assumption that the initial states of the system are zero. Initial states are often uncertain where as it might be zero or non-zero. If the initial states are non-zero, the system adopting an H_∞ control will present some transients as the effect of the non-zero initial states, to which the H_∞ control is not intrinsically responsible. Such transients might be unacceptable to themselves, or might cause the performance level of disturbance attenuation of the H_∞ control to deteriorate intolerably. These circumstances motivated us in this paper to be concerned with H_∞ controls which accomplish a mixed attenuation of disturbance and initial-state uncertainty in controlled outputs.

It is expected that the mixed attenuation supplies H_∞ controls with some good transients and assures H_∞ controls of robustness against initial-state uncertainty. Recently, hybrid/switching control are actively studied, this method might be one of the most reasonable approach to implement them.

In the finite-horizon case, a generalized type of H_∞ control problem which formulated and solved by Uchida and Fujita (1) and Khargonekar et al. (2). This problem was extended to the infinite-horizon case, and a result was derived by Kojima et al. (3) and Khargonekar et al. (2), The same result was derived by the different approaches. The problem discussed by Kojima et al. (3) and Khargonekar et al. (2) is limited to the central control case. Uchida et al. (4) extended this result and obtained an H_∞ control with a free-parameter which considers a mixed attenuation of disturbance and initial-state uncertainty for linear time-invariant systems in the infinite-horizon case (4).

In this paper, we evaluate the effectiveness of the proposed approach (3) (4) with a magnetic suspension system via simulations and experiments. A magnetic suspension system can suspend a magnetic body by magnetic force without any contact (5). Feedback control, especially robust feedback control is indispensable for a magnetic suspension system, which is essentially an unstable system. Recently, this seems to be one of the hot topics in control application field (6)~(9).

First, we show that the proposed controller has a relatively better transient property than the conventional standard H_∞ controller. Next, a role of the weighting matrix N for the initial state x_0 is shown via numerical simulation. N is a measure of relative importance of the initial-state uncertainty attenuation to the disturbance attenuation. Finally, usefulness and effectiveness of the free parameter Ψ from the mixed attenuation of disturbance and initial-state uncertainty is examined via experiments.

2. Mixed Attenuation of Disturbance and Initial-state Uncertainties

Consider the linear time-invariant system which is defined on the time interval $[0, \infty)$ and described by

$$\begin{aligned} \dot{x} &= Ax + Bu + Dv, \quad x(0) = x_0 \\ y &= Cx + w \\ z &= Fx \end{aligned} \qquad (1)$$

where $x \in R^n$ is the state and x_0 is the initial state; $u \in R^r$ is the control input; $y \in R^m$ is the observed output; $g := (z' \;\; u')' \in R^{q+r}$ is the controlled output and $h := (v' \;\; w')' \in R^{p+m}$ is the disturbance.

Without loss of generality, we regard x_0 as the initial-state uncertainty, and $x_0 = 0$ as a known initial-state

* Department of Mechanical Engineering, Nagaoka University of Technology
1603-1 Kamitomioka, Nagaoka, Niigata 940-2188
** Department of Electrical and Electronic Engineering, Kanazawa University
2-40-20 Kodatsuno, Kanazawa, Ishikawa 920-8667

case. Each element of the disturbance $h(t)$ is a square integrable function defined on $[0,\infty)$; A, B, C, D and F are constant matrices of appropriate dimensions and satisfies that (C,A,B) and (F,A,D) are controllable and observable.

For system (1), every admissible control $u(t)$ is given by a linear time-invariant system to the form

$$u = Js + Ky, \quad s(0) = 0$$
$$\dot{s} = Gs + Hy \quad \cdots\cdots (2)$$

which makes the closed-loop system given by (1) and (2) internally stable, where $s(t)$ is a state of a controller of a finite dimension, and J, K, G, H as constant matrices of appropriate dimensions.

The control problem is to find an admissible control attenuating disturbances and initial state uncertainties in the way that, for given $N>0$, $g=(z',u')'$ satisfies

$$\|g\|_2^2 < \|h\|_2^2 + x_0' N^{-1} x_0 \quad \cdots\cdots (3)$$

for all $h=(v',w')' \in L^2[0,\infty)$ and all $x_0 \in R^n$, s.t., $(v,w,x_0) \neq 0$.

We call such an admissible control the disturbance and initial state uncertainty attenuation (DIA) control.

The weighting matrix N^{-1} on x_0 is a measure of relative importance of the initial-state uncertainty attenuation to the disturbance attenuation [3][4].

2.1 **DIA Control** In order to solve the DIA control problem, we require the so-called Riccati equation conditions:

A1 : There exists a solution $M=M'>0$ to the Riccati equation

$$MA + A'M + F'F - M(BB' - DD')M = 0 \quad \cdots\cdots (4)$$

such that $A - BB'M + DD'M$ is stable.

A2 : There exists a solution $P=P'>0$ to the Riccati equation

$$PA' + AP + DD' - P(C'C - F'F)P = 0 \quad \cdots (5)$$

such that $A - PC'C + PF'F$ is stable.

A3 :

$$\rho(PM) < 1 \quad \cdots\cdots (6)$$

where $\rho(X)$ denotes the spectral radius of matrix X, and $\rho(X) = \max|\lambda_i(X)|$.

In addition to these conditions, let us introduce the following condition:

A4 :

$$Q + N^{-1} - P^{-1} > 0 \quad \cdots\cdots (7)$$

where $Q=Q'$ is the maximal solution of the Riccati equation

$$Q\left(A + DD'P^{-1}\right) + \left(A + DD'P^{-1}\right)' Q$$
$$-Q\left(DD' + LPC'CPL'\right)Q = 0 \quad \cdots\cdots (8)$$

with $L := (I - PM)^{-1}$.

Theorem 1 [4] Suppose that the conditions (A1), (A2), and (A3) are satisfied. The central control (10) is a DIA control if and only if the condition (A4) is satisfied, where the central control is given by

$$u = -B'S\underline{x}$$
$$\dot{\underline{x}} = A\underline{x} + Bu + PC'(y - C\underline{x}) + PF'F\underline{x} \quad \cdots (9)$$
$$\underline{x}(0) = 0, \quad S := M(I - PM)^{-1}$$

2.2 **Parameterization of all DIA Controllers** Under the assumption that (A1)-(A3) are satisfied, the class of all H_∞ controls $u(t)$ are parametrized with a parameter Ψ as

$$u(t) = \underline{u}(t) + \left[\Psi\left(y - \underline{y}\right)\right](t) \quad \cdots\cdots (10)$$
$$\underline{u}(t) = -B'S\underline{x}$$
$$\underline{y}(t) = C(I + PS)\underline{x}$$
$$\dot{\underline{x}}(t) = (A - BB'S - PC'C + PF'F)\underline{x}$$
$$+B\Psi\left(y - \underline{y}\right) + PC'y, \quad \underline{x}(0) = 0 \quad \cdots\cdots (11)$$

Here, Ψ has a rational, strictly proper stable transfer function representation $\Psi(s)$, $s.t.$ $\|\Psi w\|_2^2 < \|w\|_2^2$, $\forall w \neq 0 \in L^2[0,\infty)$.

Theorem 2 [4] Suppose that the conditions (A1)-(A3) are satisfied. An H_∞ control (10) with a parameter $\Psi(s)$ is a DIA control if and only if

$$Q_{22} + N^{-1} - P^{-1} > 0 \quad \cdots\cdots (12)$$

where $Q_{22} = Q_{22}'$ is the $(2,2)$ block of the maximal solution $Q = \begin{bmatrix} Q_{11} & Q_{12} \\ Q_{12}' & Q_{22} \end{bmatrix}$, whose existence is assured by the Riccati equation

$$Q\begin{bmatrix} A_m & 0 \\ -PSBK_m & A + DD'P^{-1} \end{bmatrix} + \begin{bmatrix} A_m & 0 \\ -PSBK_m & A + DD'P^{-1} \end{bmatrix}' Q$$
$$-Q\begin{bmatrix} B_m B_m' & -B_m CPL' \\ -LPC'B_m' & DD' + LPC'CPL' \end{bmatrix} Q$$
$$-\begin{bmatrix} K_m' K_m & 0 \\ 0 & 0 \end{bmatrix} = 0 \quad \cdots\cdots (13)$$

Where (A_m, B_m, K_m) is a minimal realization of $\Psi(s)$. A_m is stable and $L = (I - PM)^{-1}$. Q_{22} is an independent of a particular choice of realization of $\Psi(s)$, and $Q_{22} \geq 0$.

3. System Description and Modeling

Magnetic suspension systems can suspend objects without any contact. Increasing use of this technology is now utilized for various industrial purposes, and has already been applied to magnetically levitated vehicles, magnetic bearings, etc.

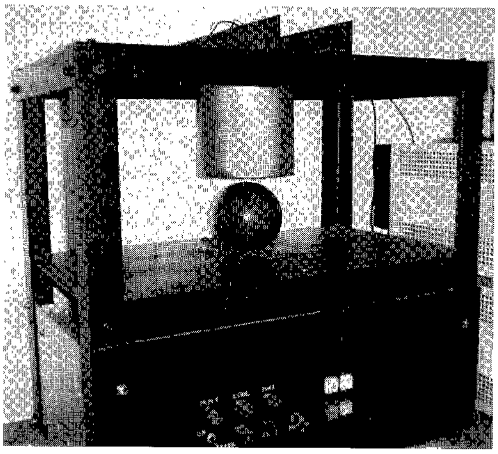

Fig. 1. Experimental setup.

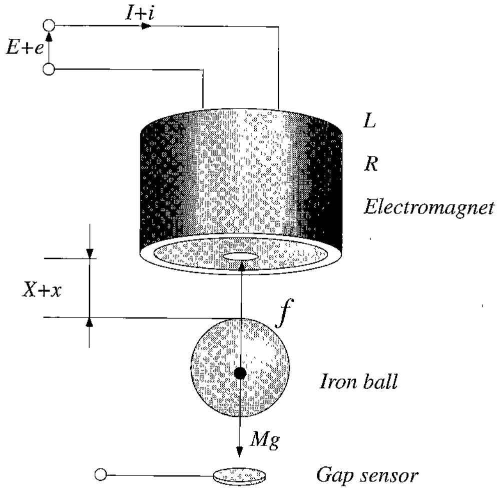

Fig. 2. Magnetic suspension system (M.S.S.).

3.1 **Construction** The experimental setup is shown in Fig.1, and its model is shown schematically in Fig.2 [5]. An electromagnet is located at the top of the experimental system. The control problem is to levitate the iron ball stably utilizing the electromagnetic force, where the mass M of the iron ball is 1.75 kg, and steady state gap X is 5 mm. Note that this simple electromagnetic suspension system requires feedback control in order to be workable. As a gap sensor, a standard induction probe of eddy current type is placed below the ball.

3.2 **Mathematical Model** In order to derive a model of the system by the laws of physic, we introduce following assumptions [5].

[a1] Magnetic flux density and magnetic field do not have any hysteresis, and they are not saturated.
[a2] There are no leakage flux in the magnetic circuit.
[a3] Magnetic permeability of the electromagnet is infinity.
[a4] Eddy current in the magnetic pole can be neglected.
[a5] Coil inductance is constant around the operating point, and an electromotive force due to a motion of the iron ball can be neglected.

These assumptions are almost essential to model this system. Under these assumptions, we derived the equation of motion of the iron ball (14), the electromagnetic force equation(15) and the electric circuit equation(16) as followed [5].

$$M\frac{d^2x(t)}{dt^2} = Mg - f(t) + v_m \quad \cdots\cdots\cdots\cdots\cdots \quad (14)$$

$$f(t) = k\left(\frac{I+i(t)}{X+x(t)+x_0}\right)^2 \quad \cdots\cdots\cdots\cdots\cdots \quad (15)$$

$$L\frac{di(t)}{dt} + R(I+i(t)) = E + e(t) + v_L \quad \cdots\cdots \quad (16)$$

where M as the mass of the iron ball, X as a steady gap between the electromagnet(EM) and the iron ball, $x(t)$ as a deviation from X, I as a steady current, $i(t)$ as a deviation from I, E as a steady voltage, $e(t)$ as a deviation from E, $f(t)$ as an EM force. k, x_0 are coefficients of f, L as an inductance of EM, and R as a resistance of EM. v_m and v_L are exogenous disturbance inputs.

Next we linearize the electromagnetic force (15) around the operating point by the Taylor series expansion as

$$f(t) = k\left(\frac{I}{X+x_0}\right)^2 - K_x x(t) + K_i i(t) \quad \cdots\cdots \quad (17)$$

where $K_x = 2kI^2/(X+x_0)^3$ and $K_i = 2kI/(X+x_0)^2$.

The sensor provides the information for the gap $x(t)$. Hence the measurement equation can be written as

$$y = x + w \quad \cdots\cdots\cdots\cdots\cdots\cdots\cdots\cdots\cdots\cdots \quad (18)$$

where w represents the sensor noise as well as the model uncertainties.

Thus, summing up the above results, the state equations for the system are

$$\begin{aligned} \dot{x}_g &= A_g x_g + B_g u_g + D_g v_0 \\ y_g &= C_g x_g + w \quad \cdots\cdots\cdots\cdots\cdots\cdots \quad (19) \end{aligned}$$

where $x_g := [x \ \ \dot{x} \ \ i]'$, $u_g := e$, $v_0 := [v_m \ \ v_L]'$,

$$A_g = \begin{bmatrix} 0 & 1 & 0 \\ 4481 & 0 & -18.4 \\ 0 & 0 & -45.7 \end{bmatrix}$$

$$B_g = \begin{bmatrix} 0 & 0 & 1.97 \end{bmatrix}', \quad C_g = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix}$$

$$D_g = \begin{bmatrix} 0 & 0 \\ 0.57 & 0 \\ 0 & 1.97 \end{bmatrix}$$

Here (A_g, B_g) and (A_g, D_g) are controllable, and (A_g, C_g) is observable. The transfer function of the plant from e to x is given as

$$\begin{aligned} G(s) &:= C_g(sI - A_g)^{-1}B_g \\ &= \frac{-30.3}{(s+47.6)(s+64.5)(s-64.5)} \quad \cdots\cdots \quad (20) \end{aligned}$$

4. Control System Design

4.1 **Problem Setup** For the magnetic suspension system described and modeled in the previous section, our principal control objective is its stabilization.

Further, as we have clarified in the modeling of the disturbances, it should be stabilized robustly against 1) unmodeled dynamics, 2) the neglected nonlinearities, 3) the parametric uncertainties. To this end, we will set up the control problem within the framework of the H_∞ DIA control.

First let us consider the system disturbance v_0. Since v_0 mainly acts on the plant in a low frequency range in practice, it is helpful to introduce a frequency weighting factor. Hence let v_0 be of the form

$$\begin{aligned} v_0 &= W_1(s)\,v(s) \\ W_1(s) &= \Phi W(s) = \Phi C_{w1}(sI - A_{w1})^{-1} B_{w1} \\ \Phi &= [\,1 \quad 1\,]' \end{aligned} \quad \cdots\cdots (21)$$

where $W_1(s)$ is a frequency weighting whose gain is relatively large in a low frequency range. These values, as yet unspecified, can be regarded as free design parameters. It is noted that, in (21), we have not made explicit distinction in the notation between a time domain function and its Laplace transform.

Next we consider the variables which we want to regulate. In this study, since our main concern is in the stabilization of the iron ball, the gap and the corresponding velocity are chosen; i.e.,

$$z_g = F_g x_g, \quad F_g = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \end{bmatrix} \quad \cdots\cdots (22)$$

Then, as the error vector, let us define as follows

$$z = \Theta z_g, \quad \Theta = \mathrm{diag}\,[\,\theta_1 \quad \theta_2\,] \quad \cdots\cdots (23)$$

where Θ is a weighting matrix on the regulated variables z_g. This value, as yet unspecified, are also free design parameters.

Finally, let $x := [\,x_g \quad x_{w1}\,]'$, where x_{w1} denotes the state of the frequency weighting $W_1(s)$, then we can construct the generalized plant as in the following;

$$\begin{aligned} \dot{x} &= Ax + Bu + Dv \\ y &= Cx + w \\ z &= Fx \end{aligned} \quad \cdots\cdots (24)$$

where

$$A = \begin{bmatrix} A_g & D_g C_{w1} \\ 0 & A_{w1} \end{bmatrix}, \quad B = \begin{bmatrix} B_g \\ 0 \end{bmatrix}$$
$$C = [\,C_g \quad 0\,], \quad D = \begin{bmatrix} D_g D_{w1} \\ B_{w1} \end{bmatrix}$$
$$F = [\,\Theta F_g \quad 0\,]$$

The block diagram of the generalized plant with an unspecified controller K is shown in Fig.3. Since the disturbances v and w represent the various model uncertainties, the effects of these disturbances on the error vector z should be reduced.

Now our control problem setup is: finding an admissible controller $K(s)$ that attenuates disturbances and initial state uncertainties to achieve DIA condition in (3).

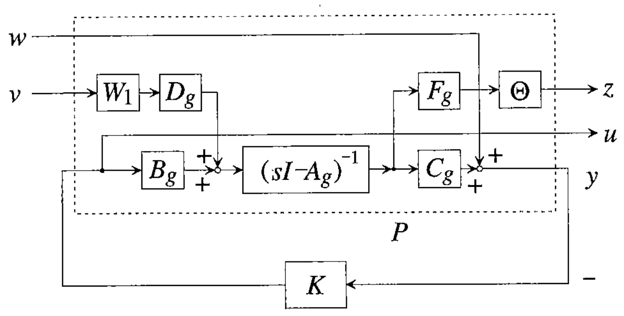

Fig. 3. Generalized Plant

4.2 **Design I: Central Controller** We designed controllers for the generalized plant in the previous subsection based on the following 4-Step procedure.

[Step 1] Selection of the frequency weighting function $W(s)$: $W_1(s)$ is a frequency weighting which its gain is relatively large in a low frequency range.

[Step 2] Selection of the weighting Matrix Θ: Θ is a weighting matrix on the regulated variables z_g.

[Step 3] Construction of generalized plant: With the specified design parameters in Steps 1 and 2, the generalized plant is constructed. The DIA controller is designed for this plant.

[Step 4] Calculation of the maximum matrix N: Calculating the maximum N satisfies the condition (A4). For the sake of simplicity, the structure of the matrix N is limited in $N = nI$, where n is a positive scalar number.

4.2.1 **DIA Controller 1** After some iteration in MATLAB environment, these parameters are chosen as follows;

$$\begin{aligned} W_1(s) &= \frac{7.5}{s + 1.0e^{-4}}, \\ \Theta &= \mathrm{diag}\,[\,1.01 \quad 1.0e^{-5}\,] \end{aligned} \quad \cdots\cdots (25)$$

Direct calculations yield the central controller;

$$K_{DIA_1} = C_{f1}(sI - A_{f1})^{-1} B_{f1} \quad \cdots\cdots (26)$$

where

$$\begin{aligned} A_{f1} &= A - BB'S - PC'C + PF'F \\ &= \begin{bmatrix} -1.38e^{2} & 1.00 & 0 & 0 \\ -4.48e^{3} & -2.98e^{-3} & -1.84e^{1} & 4.28 \\ 1.05e^{11} & 1.98e^{7} & -2.72e^{4} & 6.33e^{3} \\ -4.06e^{-2} & -2.71e^{-8} & 0 & -1e^{-4} \end{bmatrix} \\ B_{f1} &= PC' \\ &= [\,-2.11e^{9} \quad -1.41e^{11} \quad -2.07e^{5} \quad -6.39e^{5}\,]' \\ C_{f1} &= -B'S \\ &= [\,1.68e^{5} \quad 3.18e^{1} \quad -4.36e^{-2} \quad 1.01e^{-2}\,]. \end{aligned}$$

The frequency response of the controller K_{DIA_1} is shown in Fig. 4 by a solid line. And the maximum value of the weighting matrix N is $N = 3.855 \times 10^{-9} \times I$, and the spectral radius $\rho(PM)$ is 0.892. We designed the standard H_∞ controller for the comparison, where the H_∞ controller [5] was designed via the MATLAB command `hinfsyn.m`. We denote the state-space realization of the obtained H_∞ controller as K_∞. The frequency response of the controller K_∞ is shown in Fig. 4 by a dotted line.

Comparing the controllers K_∞ and K_{DIA_1}, simulated step responses of these two controllers from the initial state $x_0 = [x, \dot{x}, i]' = [0,\ 0,\ 0.1]'$ are shown in Fig.5 where the solid line shows a response with K_{DIA_1} and the dashed line shows one with K_∞. From this result, we can see that K_{DIA_1} achieves better performance against initial state uncertainty than K_∞ does.

4.2.2 **Investigation of Weight** N The weighting matrix N on x_0 is a measure of relative importance of the initial-state uncertainty attenuation to the disturbance attenuation. A larger choice of N in the sense of matrix inequality order means finding an admissible control which attenuates the initial-state uncertainty more [3][4]. For the evaluation of feedback performance against the weighting matrix N, we have designed another DIA controller K_{DIA_2}. After some iteration in MATLAB environment, design parameters are chosen as follows to obtain another DIA controller;

$$W_1(s) = \frac{5.0}{s + 1.0e^{-4}},$$

$$\Theta = \mathrm{diag}\left[\ 1.01 \quad 1.0e^{-5}\ \right] \cdots\cdots\cdots\cdots (27)$$

Direct calculations yield the central controller K_{DIA_2};

$$K_{DIA_2} = C_{f2}(sI - A_{f2})^{-1}B_{f2} \cdots\cdots\cdots\cdots (28)$$

where

$$A_{f2} = \begin{bmatrix} -1.34e^{2} & 9.99e^{-1} & 0 & 0 \\ -4.48e^{3} & -1.48e^{-1} & -1.84e^{1} & 2.85 \\ 1.38e^{9} & 2.20e^{6} & -2.86e^{4} & 4.43e^{3} \\ -5.39e^{-2} & -1.79e^{-8} & 0 & -1.00e^{-4} \end{bmatrix}$$

$$B_{f2} = \left[\ -1.05e^{9} \quad -7.01e^{10} \quad -9.10e^{4} \quad -4.22e^{5}\ \right]'$$

$$C_{f2} = \left[\ 2.22e^{5} \quad 3.54e^{1} \quad -4.58e^{-2} \quad 7.09e^{-2}\ \right]$$

The frequency response of the controller K_{DIA_2} is shown in Fig. 4 by a dash-dot line, and the maximum value of Ns of the controllers K_{DIA_1} and K_{DIA_2} are given in Table 1, where the spectral radius $\rho(PM)$ is also $\rho(PM) = 0.892$.

The value of N for K_{DIA_1} is bigger than the value for K_{DIA_2}, which means that the controller K_{DIA_1} can attenuate the initial state uncertainty more than K_{DIA_2}. For the evaluation of this property, we examine the simulated time responses of the gap x with initial state uncertainty, where the initial state is $x_0 = [x, \dot{x}, i]' = [0,\ 0,\ 0.1]'$ in Fig.6. Note that a scale of the vertical axis in Fig.6 is different from Fig.5.

The solid line shows the response with K_{DIA_1}, and the dashed line shows the response with K_{DIA_2}. From this result, we can see that the controller K_{DIA_1}(solid line) which has a relatively large N, achieves greater attenuation of the initial state uncertainty, which means that the weighting matrix N can be an indicator of initial state uncertainty attenuation.

Table 1. DIA controllers and Ns

DIA controller	N
K_{DIA_1}	3.855×10^{-9}
K_{DIA_2}	1.713×10^{-9}

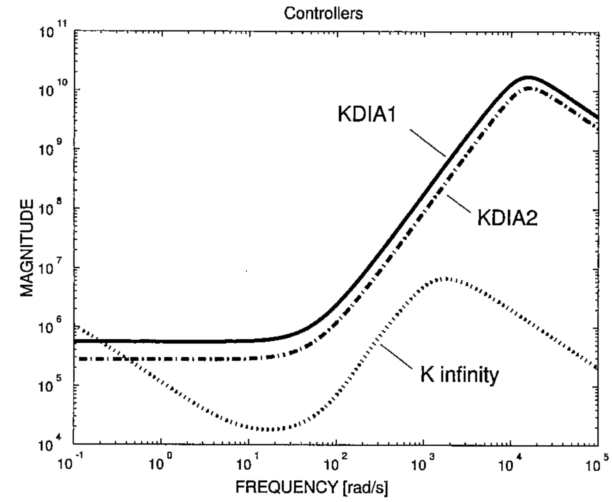

Fig. 4. Frequency response of the controller K_{DIA_1}, K_{DIA_2} and K_∞.

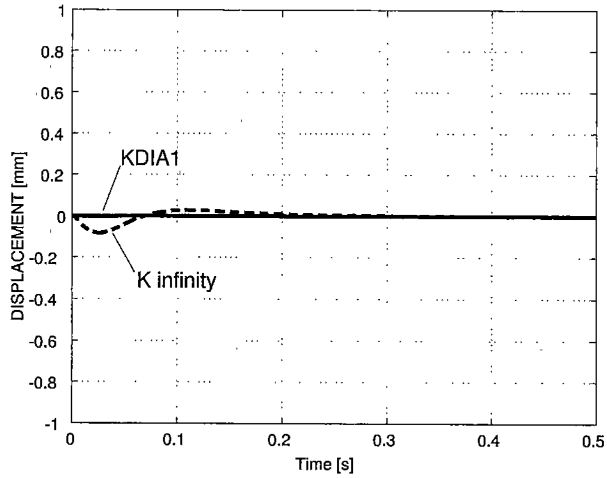

Fig. 5. Comparison between K_{DIA_1} and K_∞.

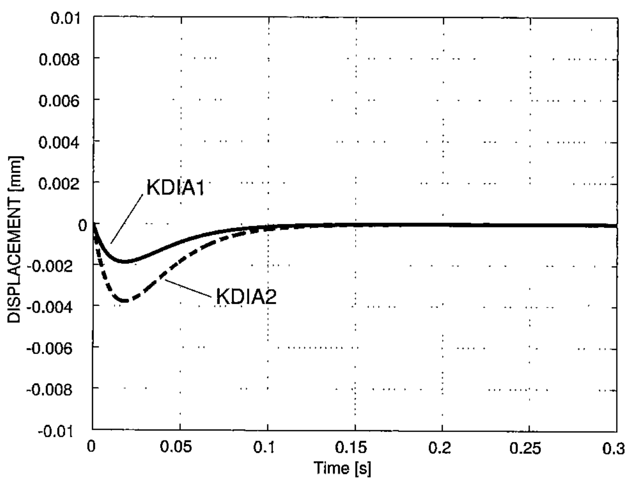

Fig. 6. Initial responses with K_{DIA_1}(solid line) and K_{DIA_2}(dashed line) for an initial state: $x_0 = [0.0,\ 0.0,\ 0.1]'$.

4.3 **Design 2: Controller with a Free Parameter** In this section, we designed a DIA controller with a free parameter Ψ via experiment. The following step is added to the design procedure in Section **4.2.**

[Step 5] Selection of the free parameter Ψ

After some iteration with experiments with a magnetic suspension system, the parameters are chosen as follows;

$$W_1(s) = \frac{25.0}{s+0.01},$$
$$\Theta = \mathrm{diag}\left[\ 1.40 \quad 1.0e^{-3}\ \right]$$
$$\Psi(s) = \frac{-9.9\times 10^{-2}}{s+0.1} \quad \cdots\cdots\cdots\cdots\cdots\cdots (29)$$

Here the free parameter Ψ which satisfies (10), and has been chosen to let the controller have an integral property. Direct calculations yield the central controller $K_{DIA_3} = C_{f3}(sI - A_{f3})^{-1}B_{f3}$.

Easy algebraic calculation with (10) and (11) derives the state space form of the DIA controller with a free parameter Ψ as

$$K_{DIA_3\Psi} = C_{f3\Psi}(sI - A_{f3\Psi})^{-1}B_{f3\Psi}$$
$$A_{f3\Psi} = \begin{bmatrix} A - BB'S - PC'C + PF'F & BK_m \\ -B_mC(I+PS) & A_m \end{bmatrix}$$
$$B_{f3\Psi} = \begin{bmatrix} PC' & B_m \end{bmatrix},\ C_{f3\Psi} = \begin{bmatrix} -B'S \\ K_m \end{bmatrix}$$
$$\cdots\cdots\cdots\cdots\cdots\cdots\cdots\cdots\cdots (30)$$

The frequency response of the controller K_{DIA_3} and $K_{DIA_3\Psi}$ are shown in Fig.7, where a dashed line shows the frequency response of K_{DIA_3} and a solid line shows one of $K_{DIA_3\Psi}$. The controller gain of $K_{DIA_3\Psi}$ has been increased just as aimed, and is larger than K_{DIA_3} at the low frequency.

4.3.1 **Experimental Evaluation** We have conducted experiments to evaluate properties of controllers K_{DIA_3} and $K_{DIA_3\Psi}$. Using the experimental machine in Fig.2, the iron ball at a standstill has been suspended stably with both the controller K_{DIA_3} and $K_{DIA_3\Psi}$. To ascertain transient responses, we input the step reference signal to a suspended iron ball. It is expected that $K_{DIA_3\Psi}$ will show an improved response for the reference signal.

A step reference signal is added to the system around 1[s], where the magnitude of the step signal is 0.5[mm], and steady state gap between the iron ball and the electromagnet is 5.0[mm]. Experimental results are shown in Figs.8 and 9, respectively.

These figures show that both controllers give oscillatory responses and are not satisfactory. However both controllers maintain stable suspension, and our aim here is to investigate the difference of both K_{DIA_3} and $K_{DIA_3\Psi}$'s responses so as to evaluate the free parameter Ψ(s). Actually, the oscillations might be caused by high-gain controllers which excite the unmodeled substructure of the experimental setup.

In Fig.8, the steady state error has been left, but Fig.9 shows that the controller $K_{DIA_3\Psi}$ makes this error to be zero, because of its integral property. This fact represents the usefulness of the free parameter Ψ.

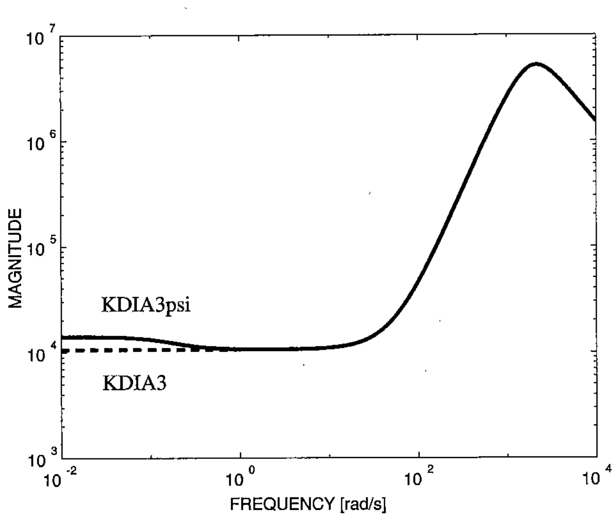

Fig. 7. Frequency responses of the controller K_{DIA_3}(Dashed line) and $K_{DIA_3\Psi}$(Solid line).

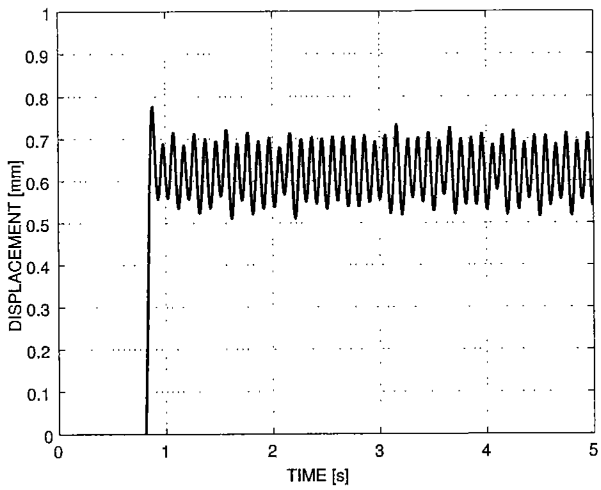

Fig. 8. Experimental results with $K_{DIA_3}(s)$ for step reference Signal(0.5[mm]).

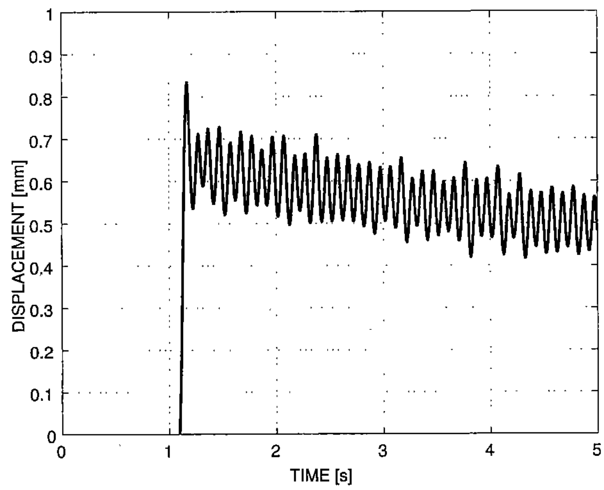

Fig. 9. Experimental results with $K_{DIA_3\Psi}(s)$ for step reference signal(0.5[mm]).

5. Conclusion

In this paper, a robustness property of H_∞ controls against initial-state uncertainty was discussed. We evaluated the effectiveness of the proposed approach via a magnetic suspension system. First, we showed the DIA controller had a relatively better transient property than the conventional standard H_∞ controller. Second, a role of the weighting matrix N for the initial state x_0 was definitely shown via numerical simulation. N is a measure of relative importance of the initial-state uncertainty attenuation to the disturbance attenuation. A larger choice of N in the sense of matrix inequality order means finding an admissible control which attenuates the initial-state uncertainty more. Finally, usefulness and effectiveness of the free parameter Ψ from the mixed attenuation of disturbance and initial-state uncertainty has been examined via experimental results.

However, the problem discussed here was limited to time-invariant systems satisfying the orthogonality assumptions (10). This is an immensely serious problem, because time-invariant systems satisfying the orthogonality assumptions restrict the degrees of freedom of the control system design, and have difficulty in regulating control inputs.

We formulated an infinite horizon disturbance and initial state uncertainty attenuation control problem without the orthogonality assumptions (11), and the solution to exist was derived as a natural but complicated extension of the previous results (3) (4).

The next goal is to apply this extended result (11) to the magnetic suspension system and evaluate its effectiveness by experiments.

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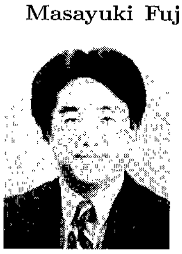
Toru Namerikawa (Member) Prof. Namerikawa received the B.E., M.E. and Dr. of engineering degrees in electrical and computer engineering from Kanazawa University, Japan, in 1991, 1993 and 1997, respectively. From 1994 until 2002, he was with Kanazawa University as a Research Associate. Since 2002, he has been with Nagaoka University of Technology, and he is currently an Associate Professor at the Department of Mechanical Engineering. In 1998, he held a visiting position at the Swiss Federal Institute of Technology, Zurich, Switzerland, and also held a visiting researcher at University of California, Santa Barbara in 2001-2002. His research interests are robust control and its applications to electro-mechanical systems including magnetic suspension systems and magnetic bearings.



Masayuki Fujita (Non-member) Prof. Fujita received the B.E., M.E. and Dr. of engineering degrees in electrical engineering from Waseda University, in 1982, 1984 and 1987, respectively. From 1995 until 1992, he was with Kanazawa University. From 1992 until 1998, he was with the Japan Advanced Institute of Science and Technology. In April 1998, he joined Kanazawa University, where he is presently a Professor in the Department of Electrical and Electronic Engineering. From 1994 to 1995, he held a visiting position in the Technical University of Munich, Germany. His research interests include robust control and its applications to robotics and mechatronics.