

A Separation Principle for Non-UCO Systems: The Jet Engine Stall and Surge Example

Manfredi Maggiore and Kevin M. Passino

Abstract

The problem of controlling surge and stall in jet engine compressors is of fundamental importance in preventing damage and lengthening the life of these components. In this theoretical study, we illustrate the application of a novel output feedback control technique to the Moore-Greitzer mathematical model for these two instabilities assuming that the plenum pressure rise is measurable. This problem is particularly challenging since the system is not *uniformly completely observable* and, hence, none of the output feedback control techniques found in the literature can be applied to recover the performance of a full state feedback controller.

Index Terms

Surge and stall, nonlinear control, output feedback, separation principle, nonlinear observer.

I. INTRODUCTION AND PROBLEM DESCRIPTION

We consider the problem of controlling two instabilities which occur in jet engine compressors, namely rotating stall and surge. In [8] Moore and Greitzer developed a three-state finite dimensional Galerkin approximation of a nonlinear PDE model describing the compression system. Since its development, several researchers have used the Moore-Greitzer three state model (MG3) to design stabilizing controllers for stall and surge, see for instance the works [3], [5], [9]. Most existing results focus on the development of state feedback controllers which may not be implementable because the state is not entirely measurable. In [3] a partial state feedback controller simplifies practical implementation by only requiring measurements of the mass flow and plenum pressure rise.

To the best of our knowledge, available solutions to the output feedback control problem using only plenum pressure rise (see [1] and Sections 12.6, 12.7 in [2]) do not rely on the estimation of the entire state of the system, and it seems that no attempt has been made to design a stabilizing output feedback controller (using only plenum pressure rise feedback) based on a full-state feedback control law. In this paper we introduce a new globally stabilizing full state feedback control law for MG3, and we employ the theory developed in [7] for the output feedback control of non-UCO systems (i.e., system that are not globally observable) to regulate stall and surge by using only pressure measurements. We stress that the details of a practical design and implementation are not within the scope of this note.

The MG3 model is described by (see [3] for an analogous exposition)

$$\begin{aligned}\dot{\Phi} &= -\Psi + \Psi_C(\Phi) - 3\Phi R \\ \dot{\Psi} &= \frac{1}{\beta^2}(\Phi - \Phi_T) \\ \dot{R} &= \sigma R(1 - \Phi^2 - R), \quad R(0) \geq 0\end{aligned}\tag{1}$$

where Φ represents the mass flow, Ψ is the plenum pressure rise, $R \geq 0$ is the normalized stall cell squared amplitude, Φ_T is the mass flow through the throttle (throughout this note we will set $\sigma = 7$, and $\beta = 1/\sqrt{2}$). The functions $\Psi_C(\Phi)$ and $\Phi_T(\Psi)$ are the compressor and throttle characteristics, respectively, and are defined as $\Psi_C(\Phi) = \Psi_{C_0} + 1 + 3/2\Phi - 1/2\Phi^3$, $\Psi = \frac{1}{\gamma^2}(1 + \Phi_T(\Psi))^2$, where Ψ_{C_0} is a constant and γ is the throttle opening, the control input. Our control objective is to stabilize system (1) around the critical equilibrium $R^e = 0$, $\Phi^e = 1$, $\Psi^e = \Psi_C(\Phi^e) = \Psi_{C_0} + 2$, which achieves the peak operation on the compressor characteristic. Shifting the origin to the desired equilibrium with the change of variables $\phi = \Phi - 1$, $\psi = \Psi - \Psi_{C_0} - 2$ we obtain

$$\begin{aligned}\dot{R} &= -\sigma R^2 - \sigma R(2\phi + \phi^2) \\ \dot{\phi} &= -\psi - 3/2\phi^2 - 1/2\phi^3 - 3R\phi - 3R \\ \dot{\psi} &= \frac{1}{\beta^2}(\phi - \gamma\sqrt{\psi + \Psi_{C_0} + 2} + 2)\end{aligned}\tag{2}$$

We assume the pressure rise (and hence ψ) to be the only measurable state variable.

II. STATE FEEDBACK CONTROL DESIGN

We start by designing a full-state feedback controller which makes the origin of (2) an asymptotically stable equilibrium point with domain of attraction $\{(R, \phi, \psi) \in \mathbb{R}^3 | R \geq 0\}$, as seen in the next theorem.

Theorem 1 *For system (2), with the choice of the control law*

$$\bar{\gamma} = \frac{2 + (1 - \beta^2 k_1 k_2)\phi + \beta^2 k_2 \psi + 3\beta^2 k_1 R\phi}{\sqrt{\psi + \Psi_{C_0} + 2}}\tag{3}$$

M. Maggiore is the Department of Electrical and Computer Engineering, University of Toronto, 10 King's College Rd., Toronto, ON, M5S 3G4, Canada (e-mail: maggiore@control.utoronto.ca). Part of this research was performed when the author was a student at the Ohio State University.

K. Passino is with the Department of Electrical Engineering, The Ohio State University, 2015 Neil Avenue, Columbus, OH 43210 USA (e-mail: k.passino@osu.edu).

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where k_1 and k_2 are positive scalars satisfying the inequalities,

$$\begin{aligned} k_1 &> \frac{17}{8} + \frac{(2C\sigma + 3)^2}{2} \\ \left(C\sigma - \frac{105}{64}\right) k_1^2 + \frac{3}{4} \left(-\frac{1}{2}C\sigma + \frac{21}{4}\right) k_1 - (C\sigma + 3)^2 &> 0 \\ k_2 &> k_1 + \frac{9}{4}k_1^2 + \frac{9k_1}{4k_1 - 9/2} + \frac{(k_1^2 - 1)^2}{4}, \quad C > \frac{3}{2\sigma} \end{aligned} \quad (4)$$

the origin is asymptotically stable with domain of attraction $\mathcal{A} = \{(R, \phi, \psi) \in \mathbb{R}^3 \mid R \geq 0\}$.

Proof: Without loss of generality let $u = \frac{1}{\beta^2}(\phi - \gamma\sqrt{\psi + \Psi_{C_0} + 2} + 2)$, so that the last equation in (2) becomes $\dot{\psi} = u$. Next, notice that system (2) can be viewed as the interconnection of two subsystems:

$$[S_1] \dot{R} = -\sigma R^2, \quad [S_2] \begin{cases} \dot{\phi} = -\psi - \frac{3}{2}\phi^2 - \frac{1}{2}\phi^3 \\ \dot{\psi} = u \end{cases}$$

Consider the following Lyapunov function candidate (partly inspired by Section 2.4.3 in [4]) for system (2), $V = CR + \frac{1}{2}\phi^2 + \frac{k_1}{8}\phi^4 + \frac{1}{2}(\psi - k_1\phi)^2$, where $C > 0$ is a scalar. After noticing that V is positive definite on the domain \mathcal{A} , and letting $\tilde{\psi} = \psi - k_1\phi$, we calculate the time derivative of V as follows,

$$\begin{aligned} \dot{V} &= -C\sigma R^2 - C\sigma R(2\phi + \phi^2) + \left(\phi + \frac{k_1}{2}\phi^3\right) \left(-\psi - \frac{3}{2}\phi^2 - \frac{1}{2}\phi^3 - 3R\phi - 3R\right) + \tilde{\psi} \left(u + k_1\psi + \frac{3}{2}k_1\phi^2 + \frac{1}{2}k_1\phi^3 + 3k_1R\phi + 3k_1R\right). \end{aligned} \quad (5)$$

Here, as in [4], we use the identity

$$-\frac{3}{2}\phi^2 - \frac{1}{2}\phi^3 = -\frac{1}{2} \left(\phi + \frac{3}{2}\right)^2 \phi + \frac{9}{8}\phi$$

to eliminate the potentially destabilizing term $-(\phi + k_1/2\phi^3)3/2\phi^2$. Next, substituting (3) into (5) (after taking in account the definitions of u and γ), letting $\bar{k}_1 = k_1 - 9/8$, and using the definition of $\tilde{\psi}$, we get

$$\begin{aligned} \dot{V} &= -C\sigma R^2 - C\sigma R(2\phi + \phi^2) + \left(\phi + \frac{k_1}{2}\phi^3\right) \left(-\tilde{\psi} - \bar{k}_1\phi - \frac{1}{2} \left(\phi + \frac{3}{2}\right)^2 \phi - 3R\phi - 3R\right) + \tilde{\psi} \left(-(k_2 - k_1)\tilde{\psi} + k_1^2\phi + \frac{3}{2}k_1\phi^2 + \frac{1}{2}k_1\phi^3 + 3k_1R\right) \\ &\leq -C\sigma R^2 - (2C\sigma + 3)R\phi - (C\sigma + 3)R\phi^2 - \bar{k}_1\phi^2 - \left(\frac{k_1\bar{k}_1}{2} + \frac{3k_1}{2}R\right)\phi^4 - \frac{3k_1}{2}R\phi^3 + \tilde{\psi} \left(-(k_2 - k_1)\tilde{\psi} + (k_1^2 - 1)\phi + \frac{3}{2}k_1\phi^2 + 3k_1R\right). \end{aligned}$$

By using Young's inequality¹ one can show that (refer to [6] for a detailed derivation)

$$\begin{aligned} \dot{V} &\leq - \begin{bmatrix} R \\ \phi^2 \end{bmatrix}^\top \begin{bmatrix} C\sigma - \frac{3}{2} & \frac{1}{2}(C\sigma + 3 - \frac{3}{8}k_1) \\ \frac{1}{2}(C\sigma + 3 - \frac{3}{8}k_1) & \frac{1}{4}k_1\bar{k}_1 \end{bmatrix} \begin{bmatrix} R \\ \phi^2 \end{bmatrix} \\ &\quad - \left(\bar{k}_1 - \frac{(2C\sigma + 3)^2}{2} - 1\right)\phi^2 \\ &\quad - \left(k_2 - k_1 - \frac{9}{4}k_1^2 - \frac{9k_1}{4\bar{k}_1} - \frac{(k_1^2 - 1)^2}{4}\right)\tilde{\psi}^2. \end{aligned}$$

Using the inequalities in (4) we conclude that \dot{V} is negative definite on the domain \mathcal{A} . This and the fact that the boundary of \mathcal{A} , $\partial\mathcal{A} = \{(R, \phi, \psi) \mid R = 0\}$, is an invariant manifold prove that the origin of the closed-loop system is an asymptotically stable equilibrium point and the set $\{(R, \phi, \psi) \mid V \leq K\} \cap \mathcal{A}$ is its region of attraction for any positive real number K . This in turn shows that \mathcal{A} is the domain of attraction of the origin of the closed-loop system. \blacksquare

In practice, k_1 and k_2 can be chosen significantly smaller than their theoretical lower bounds in (4). Choosing $\beta = 7$ and $\sigma = 1/\sqrt{2}$, we found that the smallest values of k_1 and k_2 satisfying (4) are given by $k_1 = 20.43$, $k_2 = 4.43 \cdot 10^4$ ($C = 0.2179$). However, simulations of the closed-loop system (not included here for space limitations, see [6]) for several different initial conditions indicate that k_1 and k_2 can be chosen as low as 10.

¹For any real numbers a and b , and any positive real k , one has that $ab \leq \frac{a^2}{4k} + kb^2$.

Generally a full-state feedback controller may yield a better closed-loop performance than one using partial-state feedback because it uses more information about the state of the system. When comparing our full-state feedback controller to the partial-state feedback controller developed in [3], however, this claim cannot be made without a rigorous analysis which is beyond the scope of this paper.

III. OUTPUT FEEDBACK DESIGN

In this section we apply the methodology developed in [7] to recover the performance of the state feedback controller (3) using output feedback. In what follows, we summarize the main result in [7]. Consider the following dynamical system,

$$\begin{aligned}\dot{x} &= f(x, u) \\ y &= h(x, u)\end{aligned}\tag{6}$$

where $x \in \mathbb{R}^n$, $u, y \in \mathbb{R}$, f and h are known smooth functions, and $f(0, 0) = 0$. We want to design a stabilizing controller for (6) without the availability of the system states x . In order to do so, we need an observability assumption. Define the observability mapping \mathcal{H} by calculating $n - 1$ derivatives of y along the vector field f

$$y_e \triangleq [y, \dots, y^{(n-1)}]^\top = \mathcal{H}(x, u, \dots, u^{(n_u-1)}),\tag{7}$$

where n_u , $0 \leq n_u \leq n$, denotes the number of time derivatives of u that appear in \mathcal{H} ($n_u = 0$ indicates that there is no dependence on u). Next, augment the system dynamics with n_u integrators at the input side, which corresponds to using a compensator of order n_u

$$\dot{x} = f(x, z_1), \dot{z}_1 = z_2, \dots, \dot{z}_{n_u} = v,\tag{8}$$

so that (7) can be written as $y_e = \mathcal{H}(x, z)$. Let $X = [x^\top, z^\top]^\top \in \mathbb{R}^{n+n_u}$ denote the state variable of the *extended system*. We are now ready to state our first assumption.

Assumption A1 (Observability): System (6) is observable over an open set $\mathcal{O} \subset \mathbb{R}^n \times \mathbb{R}^{n_u}$ containing the origin, i.e., the mapping $\mathcal{F} : \mathcal{O} \rightarrow \mathcal{Y}$ (where $\mathcal{Y} = \mathcal{F}(\mathcal{O})$) defined by

$$Y = [y_e^\top, z^\top]^\top = \mathcal{F}(X) = [\mathcal{H}(x, z)^\top, z^\top]^\top\tag{9}$$

has a smooth inverse $\mathcal{F}^{-1} : \mathcal{Y} \rightarrow \mathcal{O}$, $\mathcal{F}^{-1}(Y) = \mathcal{F}^{-1}(y_e, z) = [\mathcal{H}^{-1}(y_e, z)^\top, z^\top]^\top$.

Following the terminology in [10], when $\mathcal{O} = \mathbb{R}^{n+n_u}$ we say that the system is *uniformly completely observable (UCO)*.

Assumption A2 (Stabilizability): There exists a smooth function $\bar{u}(x)$ such that the origin of (6) is an asymptotically stable (or globally asymptotically stable) equilibrium point of $\dot{x} = f(x, \bar{u}(x))$.

Using A2, the knowledge of a Lyapunov function for (6) with $u = \bar{u}(x)$, and the integrator backstepping lemma (see, e.g., [4]), one may design a smooth control law $v = \phi(x, z) = \phi(X)$ which makes the origin of (8) an asymptotically stable equilibrium point. In particular, from the application of the integrator backstepping lemma one also gets a Lyapunov function $\bar{V}(X)$. Given any scalar $c > 0$, let Ω_c denote the generic level set of \bar{V} , i.e., $\Omega_c \triangleq \{X \in \mathbb{R}^{n+n_u} \mid \bar{V} \leq c\}$. Our last assumption concerns the topology of the ‘‘observability set’’ \mathcal{O} .

Assumption A3 (Topology of \mathcal{O}): Assume that there exists a constant $c_2 > 0$ and a set \mathcal{C} such that $\mathcal{F}(\Omega_{c_2}) \subset \mathcal{C} \subset \mathcal{Y}$ ($= \mathcal{F}(\mathcal{O})$), where \mathcal{C} has the following properties

- (i) The boundary of \mathcal{C} , $\partial\mathcal{C}$, is class C^1 , i.e., there exists a C^1 function $g : \mathcal{C} \rightarrow \mathbb{R}$ such that $\partial\mathcal{C} = \{Y \in \mathcal{C} \mid g(Y) = 0\}$, and $(\partial g / \partial Y)^\top \neq 0$ on $\partial\mathcal{C}$.
- (ii) Each slice $\mathcal{C}^{\bar{z}} = \{y_e \in \mathbb{R}^n \mid [y_e^\top, \bar{z}^\top]^\top \in \mathcal{C}\}$ is convex for all $\bar{z} \in \mathbb{R}^{n_u}$.
- (iii) 0 is a regular value of $g(\cdot, \bar{z})$ for each fixed $\bar{z} \in \mathbb{R}^{n_u}$, i.e., $[\partial g / \partial y_e(y_e, \bar{z})]^\top$ does not vanish anywhere on the boundary of each slice $\mathcal{C}^{\bar{z}}$.
- (iv) $\bigcup_{\bar{z} \in \mathbb{R}^{n_u}} \mathcal{C}^{\bar{z}}$ is compact.

Given a real-valued function $x \mapsto a(x)$, $\mathbb{R}^n \rightarrow \mathbb{R}$, and a vector field a in \mathbb{R}^n , recall that the Lie derivative $L_a b$ is defined as $L_a b = (\partial b / \partial x)a(x)$. We are now ready to introduce the output feedback controller for the extended system (8),

$$\dot{\hat{x}}^P = \begin{cases} \left[\frac{\partial \mathcal{H}}{\partial \hat{x}^P} \right]^{-1} \left\{ L_{\hat{F}} \mathcal{H} - \Gamma \frac{N_{y_e}(\hat{Y}^P) L_{\hat{G}} g}{N_{y_e}(\hat{Y}^P)^\top \Gamma N_{y_e}(\hat{Y}^P)} - \frac{\partial \mathcal{H}}{\partial z} \dot{z} \right\} & \text{if } L_{\hat{G}} g \geq 0 \text{ and } \hat{Y}^P \in \partial\mathcal{C} \\ \hat{f}(\hat{x}^P, z, y) & \text{otherwise} \end{cases}\tag{10}$$

$$v = \phi(\hat{x}^P, z),\tag{11}$$

where

$$\begin{aligned}\hat{f}(\hat{x}^P, z, y) &= f(\hat{x}^P, z_1) + \left[\frac{\partial \mathcal{H}(\hat{x}^P, z)}{\partial \hat{x}^P} \right]^{-1} \mathcal{E}^{-1} L(y - h(\hat{x}^P, z_1)) \\ \hat{F} &= [\hat{f}(\hat{x}^P, z, y)^\top, z^\top]^\top, \quad \hat{G} = L_{\hat{F}} \mathcal{F}\end{aligned}$$

and the various parameters are defined in the following table

$\hat{y}_e^P = \mathcal{H}(\hat{x}^P, z)$	$\hat{Y}^P = \mathcal{F}(\hat{x}^P, z) = [\hat{y}_e^{P\top}, z^\top]^\top$
$N_{y_e}(\hat{Y}^P) = [\partial g / \partial \hat{y}_e^P]^\top$	$\mathcal{E} = \text{diag}[\rho, \dots, \rho^n], \rho > 0$
$L \in \mathbb{R}^n$ Hurwitz	$\Gamma = \rho^{2n} (S\mathcal{E})^{-1} (S\mathcal{E})^{-\top}$

$$\hat{f} = \begin{bmatrix} -\sigma(\hat{R}^P)^2 - \sigma\hat{R}^P(2\hat{\phi}^P + (\hat{\phi}^P)^2) - \frac{l_1/\rho + \beta^2 l_2/\rho^2(3\hat{\phi}^P + 3\hat{R}^P + 3/2(\hat{\phi}^P)^2) + \beta^2 l_3/\rho^3}{3(1+\hat{\phi}^P)}(\psi - \hat{\psi}^P) \\ -\hat{\psi}^P - 3/2(\hat{\phi}^P)^2 - 1/2(\hat{\phi}^P)^3 - 3\hat{R}^P\hat{\phi}^P - 3\hat{R}^P + \beta^2 l_2/\rho^2(\psi - \hat{\psi}^P) \\ -\frac{z_1 - \hat{\phi}^P}{\beta^2} + l_1/\rho(\psi - \hat{\psi}^P) \end{bmatrix} \quad (16)$$

with $S = S^\top = P^{\frac{1}{2}}$, where P is the solution of the Lyapunov equation $P(A_c - LC_c) + (A_c - LC_c)^\top P = -I$ and (A_c, C_c) is the canonical observable pair with eigenvalues at zero.

The controller (11) has a certainty equivalence structure. The observer with state \hat{x}^P incorporates a dynamic projection which constrains the estimate \hat{x}^P to lie inside the set $\mathcal{H}^{-1}(\mathcal{C}) \subset \mathcal{O}$ and thus guarantees its well-definiteness. This feature is particularly useful when \mathcal{O} is not all of \mathbb{R}^{n+n_u} (that is, when the system is not UCO) and other output feedback control approaches based on a separation principle such as [10] cannot be employed. In the next section we will show that MG3 is not UCO and will use the methodology presented here to solve the output feedback stabilization problem.

The following result states that (10) and (11) guarantee closed-loop stability.

Theorem 2 ([7]) *For the closed-loop system (8), (10), (11), satisfying assumptions A1, A2, and A3, for any $0 < c_1 < c_2$ there exists a scalar ρ^* , $0 < \rho^* \leq 1$, such that, for all $\rho \in (0, \rho^*)$, the set $\{(X, \hat{x}^P) \in \mathbb{R}^{2n+n_u} \mid X \in \Omega_{c_1}, (\hat{x}^P, z) \in \mathcal{F}^{-1}(\mathcal{C})\}$ is contained in the region of attraction of the origin $(X, \hat{x}^P) = (0, 0)$.*

We are now ready to apply the result of Theorem 2 to MG3. To this end, we start by verifying that assumptions A1-A3 hold for (2).

Observability: We form the mapping \mathcal{H} from the measurable output $y = \psi$

$$\begin{aligned} y_e &= [y, \dot{y}, \ddot{y}]^\top = \mathcal{H}([R, \phi, \psi]^\top, \gamma, \dot{\gamma}) \\ &= \begin{bmatrix} \psi \\ 1/\beta^2(\phi - \theta(\psi, \gamma)) \\ 1/\beta^2(-\psi - 3/2\phi^2 - 1/2\phi^3 - 3R\phi - 3R - \dot{\theta}) \end{bmatrix} \end{aligned} \quad (12)$$

where, for convenience, we denoted $\theta(\psi, \gamma) = \gamma\sqrt{\psi + \Psi_{C_0} + 2} - 2$ and $\dot{\theta} = (\partial\theta/\partial\psi)\dot{\psi} + (\partial\theta/\partial\gamma)\dot{\gamma}$. Recall that γ is the control input and note that both γ and $\dot{\gamma}$ appear in \mathcal{H} , thus $n_u = 2$. Next, we need to augment the system with $n_u = 2$ integrators at its input side. To simplify the integrator backstepping design, we employ a chain of two integrators with a *modified output*:

$$\dot{z}_1 = z_2, \quad \dot{z}_2 = v, \quad \gamma = \frac{z_1 + 2}{\sqrt{\psi + \Psi_{C_0} + 2}}, \quad (13)$$

so that θ and $\dot{\theta}$ in (12) are replaced by z_1 and z_2 , respectively, and the augmented system becomes the following cascade interconnection of two subsystems $[P_1]$ and $[P_2]$

$$\begin{aligned} [P_1] &\begin{cases} \dot{R} = -\sigma R^2 - \sigma R(2\phi + \phi^2) \\ \dot{\phi} = -\psi - 3/2\phi^2 - 1/2\phi^3 - 3R\phi - 3R \\ \dot{\psi} = \frac{1}{\beta^2}(\phi - z_1) \end{cases} \\ [P_2] &\begin{cases} \dot{z}_1 = z_2 \\ \dot{z}_2 = v. \end{cases} \end{aligned} \quad (14)$$

Note that the dynamic extension (13) is well-defined in an output feedback setting because the output of (13) is a function of the measurable variables z_1 and ψ . Next, the mapping \mathcal{F} is given by $Y = \mathcal{F}([R, \phi, \psi]^\top, [z_1, z_2]^\top) = [\mathcal{H}([R, \phi, \psi]^\top, z_1, z_2)^\top, z_1, z_2]^\top$. Notice that the observability assumption A1 is satisfied on the set $\mathcal{O} = \{[R, \phi, \psi]^\top \in \mathbb{R}^3, z \in \mathbb{R}^2 \mid \phi > -1\}$ and hence the system is *not UCO*. It is easy to check that, when $\phi = -1$ and hence $\Phi = 0$, \mathcal{F} does not depend on R and hence it is not invertible. Hence, when there is no mass flow through the compressor ($\Phi = 0$) the normalized stall cell squared amplitude R cannot be observed. Clearly, $\Phi = 0$ is a condition we would like to avoid during normal engine operation.

Stabilizability: To be consistent with the notation used earlier, let $x = [R, \phi, \psi]^\top$. Rewrite $[P_1]$ in (14) as $\dot{x} = f_1(x) + g_1(x)z_1$ (also, let $f(x, z_1) = f_1(x) + g_1(x)z_1$). From Theorem 1 we have that the stabilizability assumption A2 is satisfied by the controller $\bar{\gamma}(x)$. Next, recalling that $z_1 = \theta$, in order to design a stabilizing control law for the extended system (14) one can view $[P_1]$ as a subsystem with input θ and stabilizing controller $\bar{\theta} = \bar{\gamma}(x)\sqrt{\psi + \Psi_{C_0} + 2} - 2$ and apply integrator backstepping. Doing so, one obtains the stabilizing control law

$$v = \dot{\alpha} - \tilde{z}_1 - k_4 \tilde{z}_2 \triangleq \phi(x, z), \quad (15)$$

where $\tilde{z}_1 = z_1 - \bar{\theta}(x)$, $\alpha(x, z_1) = -k_3 \tilde{z}_1 - \frac{\partial V}{\partial x} g(x) + \frac{\partial \bar{\theta}}{\partial x} [f(x) + g(x)z_1]$, $\tilde{z}_2 = z_2 - \alpha(x, z_1)$, and k_3, k_4 are arbitrary positive constants. This completes the design of a stabilizing state feedback for the extended system (14). The Lyapunov function of the closed-loop extended system is $\bar{V} = V + \frac{1}{2}\tilde{z}_1^2 + \frac{1}{2}\tilde{z}_2^2$, where V is defined in the proof of Theorem 1. Following the same reasoning as in the proof of Theorem 1, we conclude that the origin of the extended system is asymptotically stable with domain of attraction $\mathcal{D} = \mathcal{A} \times \mathbb{R}^2$.

Topology of the Observability Set: Noting that $\mathcal{Y} = \mathcal{F}(\mathcal{O}) = \{y_e \in \mathbb{R}^5, z \in \mathbb{R}^2 \mid y_{e,2} > \frac{1}{\beta^2}(-1 - z_1)\}$, it is readily seen that the set

$$\begin{aligned} \mathcal{C} &= \left\{ Y \in \mathbb{R}^5 \mid y_{e,1} \in [a_1, b_1], y_{e,2} \in \left[\frac{a_2 - z_1}{\beta^2}, \frac{b_2 - z_1}{\beta^2} \right], \right. \\ &\quad \left. y_{e,3} \in \left[\frac{-z_2 + a_3}{\beta^2}, \frac{-z_2 + b_3}{\beta^2} \right], z_1 \in [a_4, b_4], z_2 \in [a_5, b_5] \right\}, \end{aligned}$$

parameterized by the set of scalars $\{a_i, b_i \in \mathbb{R} \mid a_i < b_i, i = 1, \dots, 5\}$, is contained in \mathcal{Y} for all $a_2 > -1$. Furthermore, each slice $\mathcal{C}^{\bar{z}}$ obtained from \mathcal{C} by holding z constant at \bar{z} is convex (it is a parallelepiped in \mathbb{R}^3), thus satisfying requirement (ii) in A3. The union of all slices $\mathcal{C}^{\bar{z}}$ is the set

$$\bigcup_{\bar{z} \in \mathbb{R}^2} \mathcal{C}^{\bar{z}} = \left\{ y_e \in \mathbb{R}^3 \mid y_{e,1} \in [a_1, b_1], y_{e,2} \in \left[\frac{a_2 - b_4}{\beta^2}, \frac{b_2 - a_4}{\beta^2} \right], \right. \\ \left. y_{e,3} \in \left[\frac{-b_5 + a_3}{\beta^2}, \frac{-a_5 + b_3}{\beta^2} \right] \right\},$$

which is clearly compact, thus satisfying requirement (iv). Notice that the boundary of the set \mathcal{C} defined above does not fully satisfy requirement (i) because it is continuous but not differentiable at some corners. This, in general, may generate some numerical problems in the projection which can be dealt with by smoothing out the corners of \mathcal{C} . Using the definition of \mathcal{C} above one can calculate the vectors N_{y_e} and N_z (because of space limitations we omit their expression, see [6]) and verify that N_{y_e} never vanishes. So in particular N_{y_e} does not vanish on any slice $\mathcal{C}^{\bar{z}}$, and thus requirement (iii) is fulfilled. In conclusion, in order for A3 to be satisfied, it remains to use the Lyapunov function \bar{V} to find the largest value of c_2 such that $\Omega_{c_2} \subset \mathcal{O}$ (implying that $\mathcal{F}(\Omega_{c_2}) \subset \mathcal{F}(\mathcal{O})$) and subsequently pick values for the scalars $a_i, b_i, i = 1, \dots, 5$ such that $a_2 > -1$ and $\mathcal{F}(\Omega_{c_2}) \subset \mathcal{C}$. A more practical way to address the design of $\{a_i, b_i\}$ entails running a number of simulations for the closed-loop system under state feedback corresponding to several initial conditions $(x(0), z(0))$ and calculating upper and lower bounds for $\psi(t), \phi(t), -\psi(t) - 3/2\phi^2(t) - 1/2\phi^3(t) - 3R(t)\phi(t) - 3R(t), z_1(t), z_2(t)$. By doing that, we found that whenever $[x(0)^\top, z(0)^\top]^\top \in \Omega_0 \triangleq \{[x(0)^\top, z(0)^\top]^\top \in \mathbb{R}^5 : R \in [0, 0.1], \phi \in [-0.1, 0.1], \psi \in [-0.5, 0.5], z_1 \in [-0.1, 0.1], z_2 \in [-0.1, 0.1]\}$, we have that $a_1 = -1.15, b_1 = 0.5, a_2 = -0.3, b_2 = -0.1, a_3 = -0.75, b_3 = 0.4, a_4 = -2, b_4 = 7, a_5 = -70, b_5 = 250$. We must point out that our choice of Ω_0 is rather conservative and is made primarily for the sake of illustration.

Observer Design: Having verified that assumptions A1-A3 hold and having selected the set \mathcal{C} , we are ready to design observer (10) for MG3. Denoting by \hat{x}^P the vector $[\hat{R}^P, \hat{\phi}^P, \hat{\psi}^P]^\top$, the vector field $\hat{f}(\hat{x}^P, z, y)$ is given in (16). In conclusion, the output feedback controller design is given by $\hat{v} = \phi(\hat{x}^P, z)$, where the function ϕ is defined in (15).

IV. SIMULATION RESULTS

Here we present the simulation results when the output feedback controller developed in the previous section is applied to system (2). We choose $k_1 = 20.43, k_2 = 4.43 \cdot 10^4$ to fulfill inequalities (4) in Theorem 1, and $L = [6, 12, 8]^\top$ so that the associated polynomial $s^3 + l_1 s^2 + l_2 s + l_3 = 0$ is Hurwitz. In Figure 1 system and controller states, together with the control input, are plotted for $\rho = 1/5$. The figure clearly shows the operation of the projection which prevents the observer from peaking and guarantees that $\hat{\phi} > -0.3$, and thus is bounded away from the singularity in -1 . Figure 1 also depicts the evolution of the observer estimation error for $\rho = 1/10$ and $\rho = 1/50$, confirming the theoretical predictions of Theorem 1 and Lemma 1 in [7] concerning the arbitrary fast rate of convergence of the observer with projection (10). Finally, in Figure 2 the orbits of (R, ϕ, ψ) are plotted for decreasing values of ρ .

V. CONCLUDING REMARKS

While existing separation principle approaches such as [10] cannot be applied to recover the performance of full-state feedback controllers for MG3, they can be employed to recover the performance of *any* partial state feedback controller which does not use R (such as the one in [3]), since the (ϕ, ψ) subsystem is UCO (whereas, as shown in earlier, R is *not* observable when $\phi = -1$). Additionally, without resorting to a separation principle, one can employ the technique developed in [2], Sections 12.6, 12.7 and obtain semiglobal stabilization of the origin of the closed-loop system, or the one presented in [1], based on a globally convergent observer and a small-gain design.

The modularity of our approach and, specifically, the availability of an estimate for the *full state* of the system provides some design flexibility in that it allows using available state feedback control design techniques. On the other hand, the results presented here have some limitations that need to be addressed. First, our methodology (as well as the approach in [10]) requires adding two integrators at the input side of MG3, thus unnecessarily complicating the state feedback design. Additionally, assuming, as we do, perfect knowledge of the compressor characteristic² and absence of disturbances is not a realistic assumption. We are currently working on extending our results in this direction.

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²Note that the works [3], [2], [1] make the same assumption.

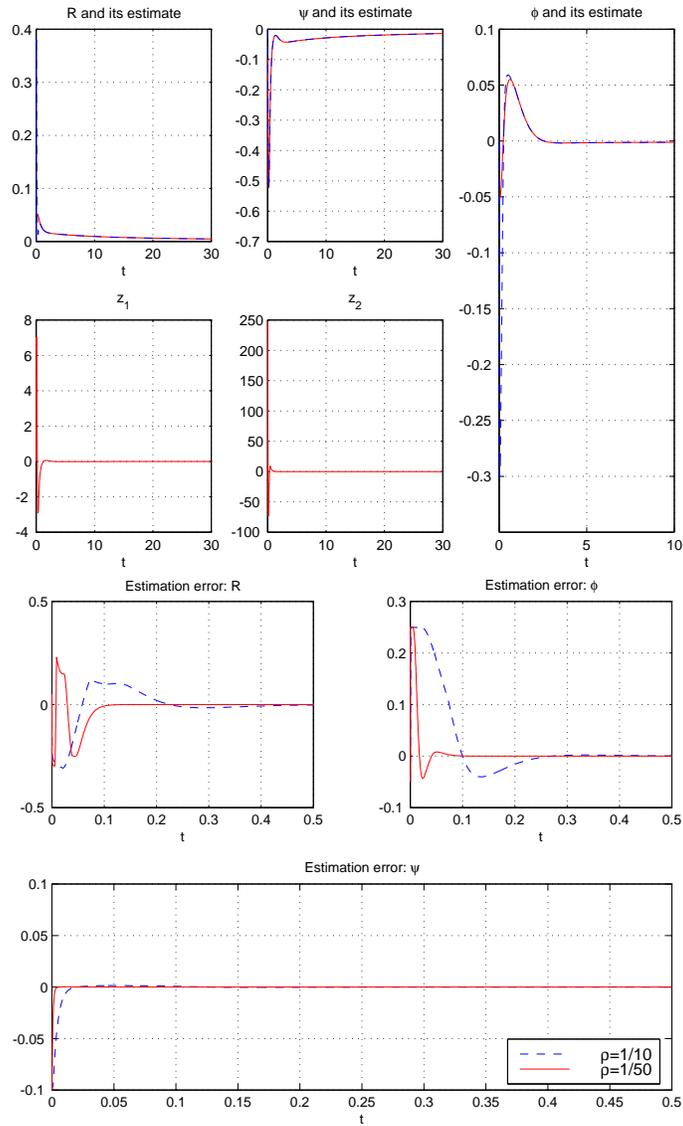


Fig. 1. Closed-loop system trajectories ($\rho = 1/5$) and estimation errors ($\rho = 1/10, 1/50$).

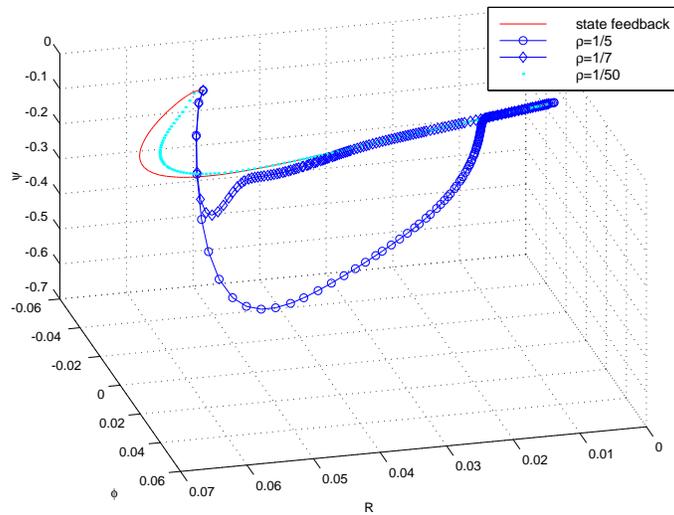


Fig. 2. State feedback trajectories and output feedback trajectories for several choices of ρ .