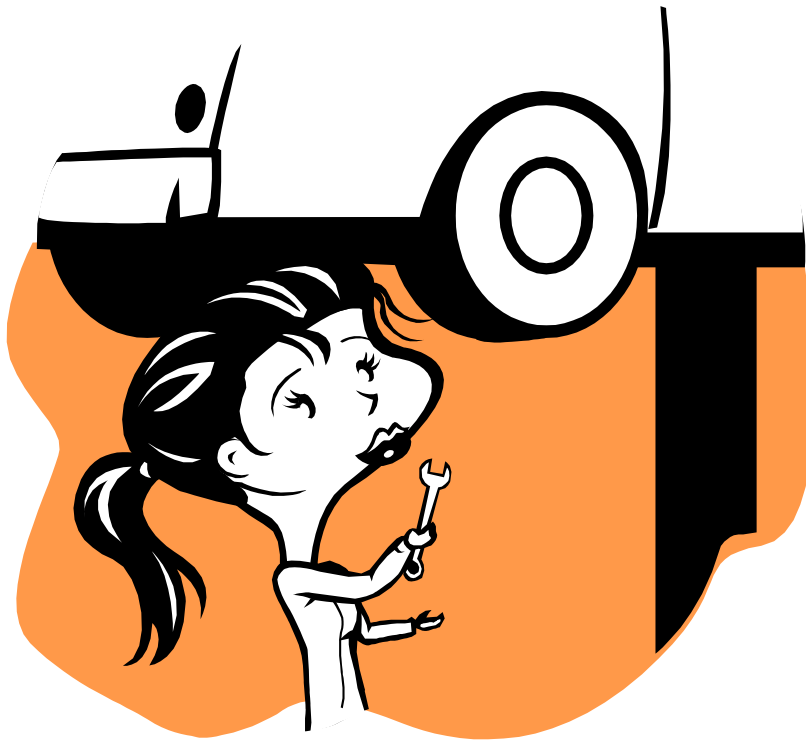


Passive Network Synthesis: Camelot in our Grasp

Prepared by

Dr. Richard Saeks, CTO



King of the Engineering Art: the What?

☐ The Art of the Artificial!! What about Natural Philosophy?

☐ Synthesis!! What about Analysis?

☐ Prognostic!! What about Diagnostic?

Oh! Like in **Passive Network Synthesis**



Design:
Dummy



Passive Network Synthesis

Aha! To Algorithmatize the
Design Process! The Epitome
of the Engineering Art!!
Off with Your head.



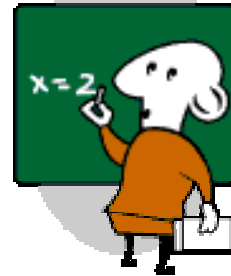
What We Did!

❑ 1910s and 20s

- Developed Explicit Algorithms for Designing Passive LC Filters.
- Established a Billion Dollar (in 1930s Dollars) Industry Designing Passive LC Telephone Filters.
- Made Modern Telephony Possible!

❑ 1930s

- Passive Network Synthesis
- Academic but it Taught us how to Handle Resistive Loads.



What Else We Did – Not Much

❑ 1940s

- Developed Explicit Algorithms for Designing Passive n-Ports
- Done Independently in 4 Countries During WWII
- **Absolutely Beautiful** – **Totally Worthless**

❑ 1950s – **The Golden Age of Circuit Theory**

- Didn't do Anything Much, unless you count the **Resistive n-port Problem** – **The Worlds Greatest Career Destroyer**

❑ 1960s - Goodbye



What Happened?

❑ **Cheap Transistors:** When the price of a CK722 went from \$99 to 99¢ in 6 Months

- The **Passivity Constraint Disappeared**, and since *Design with Constraints is What Engineering is All About*, the **Fun Disappeared Too!**
- Of Course, We hadn't Discovered **Sensitivity and Noise Floors** Yet!
- Since Our Company is at **WAR with Raytheon**, I Shouldn't Admit that, as a High School Hobbyist, I Bought my First CK722 at **Allied Radio** when it Passed the **\$25** Threshold.



What Else Happened?

- ❑ **Expensive Computers:**
When the Mainframe
Replaced a Roomful of
Graduate Students with
Mechanical Calculators
Engineering Art was
Replaced by **Brute Force**.



- ❑ **Passive Network
Synthesis: RIP**



What's This Have to do with Camelot?



And What Do You
Think You Guys are
Going to Do Out There?

Diaspora

H_∞ Control



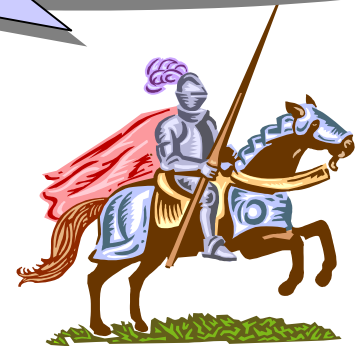
Adaptive
Control



Active
Synthesis?



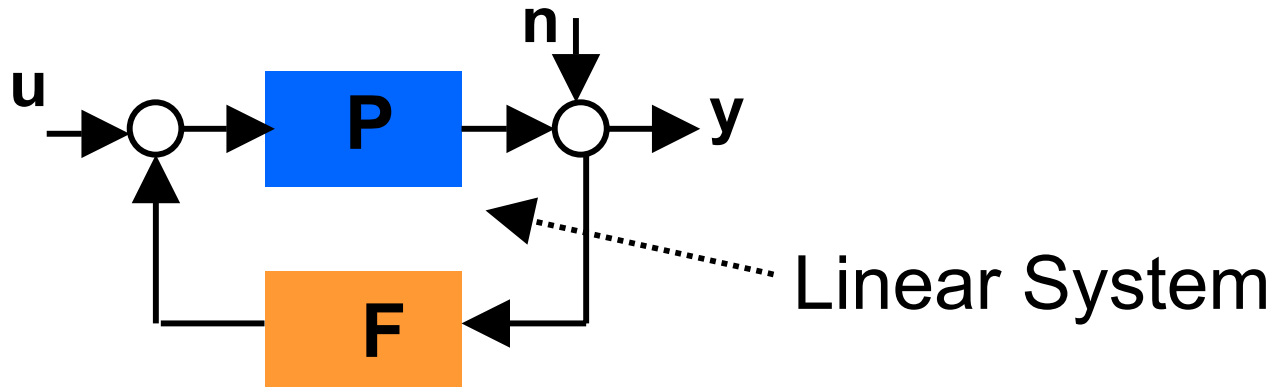
Youla Parameterization



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Ah So!

Youla Parameterization



- Let $\mathbf{P} = \mathbf{ND}^{-1}$, where \mathbf{N} and \mathbf{D} are Stable and Coprime, i.e., there exist Stable \mathbf{U} and \mathbf{V} such that; $\mathbf{UN} + \mathbf{VD} = \mathbf{1}$.
- Then the set of all possible Stabilizing Feedback Gains may be Parameterized by
$$\mathbf{F} = [\mathbf{DW} + \mathbf{U}][\mathbf{NW} + \mathbf{V}]^{-1}$$
where \mathbf{W} is Stable



What Did Dan Do?

Mommy: He's Mean

☐ **NO**, He didn't Algorithmatize the Solution of All Linear Control Problems

☐ **BUT**, He Did Parameterize the Constraint Set

☐ The Solution of "Most" Linear Control Problems Follows From the Youla Parameterization.

☐ H_2 and H_∞ Optimal Control,

☐ Tracking and Disturbance Rejection

☐ Pole and Zero Placement

☐ Robust Control and Simultaneous Design



It'll Never Work!!

Why not Learn the Design?



Yes it Will



- ❑ Just Design a **Generic Control Architecture** or Two and let it **Learn the Design in Real Time**
- ❑ The Trick is to use **Measurements of the Actual System** in Operation **Instead of a Model** of the System
- ❑ This Algorithmatizes the Design Process and Yields an **Adaptive Controller** which Compensates for
 - **System Failures** and **Environmental Changes**



Two Adaptive Control Algorithms

❑ **Neural Adaptive (Tracking) Controller**

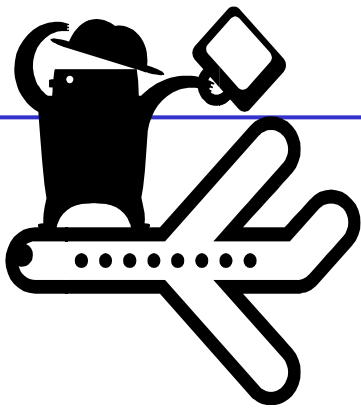
❑ **Adaptive Dynamic Programming (Optimal) Controller**

❑ **Both Algorithms are:**

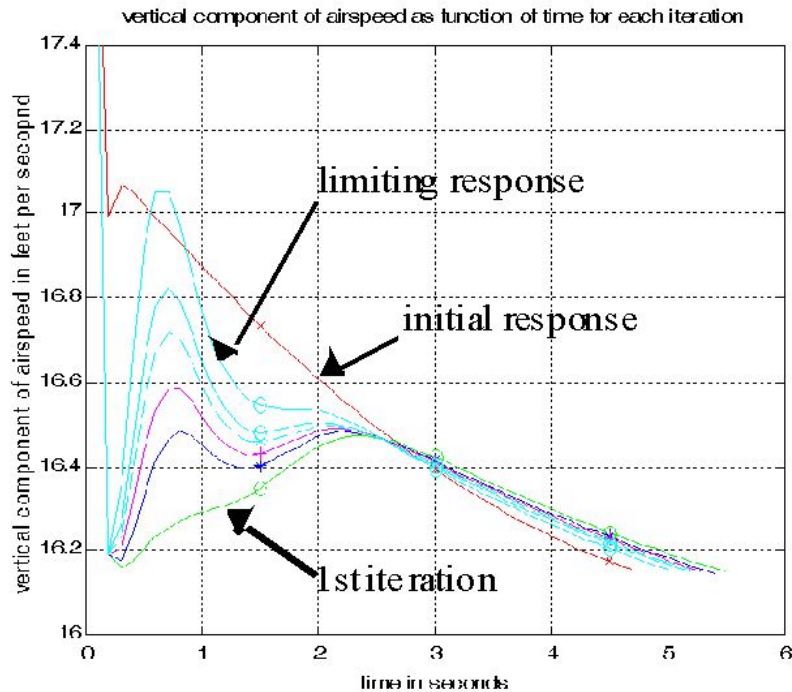
- Nonlinear
- MIMO
- Require “Minimal” *a priori* Knowledge About Plant[#]
- Characterized by a Full Stability Theory

Ah 1 and Ah 2

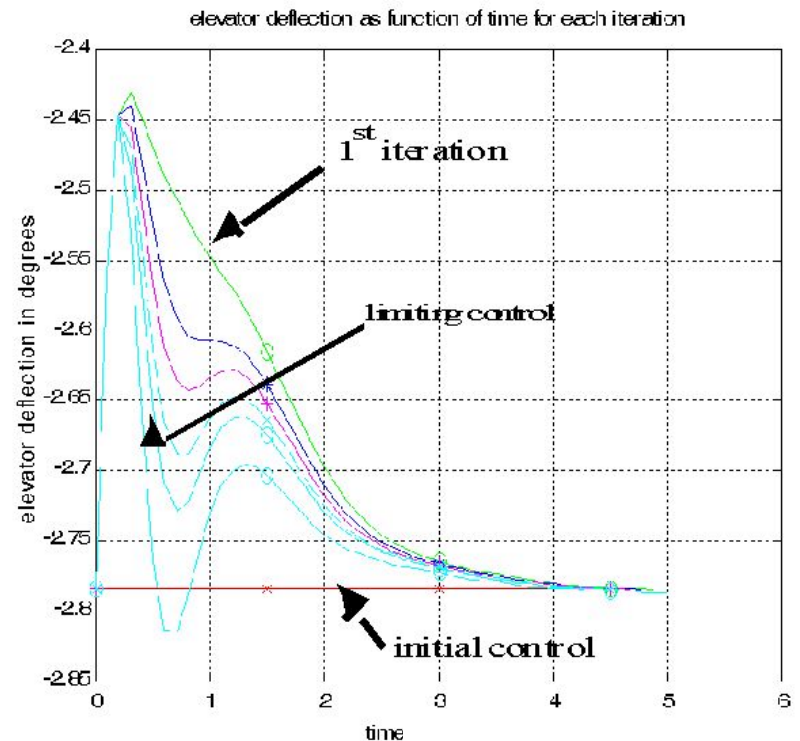




LoFLYTE® Adaptive Dynamic Programming



Vertical Component

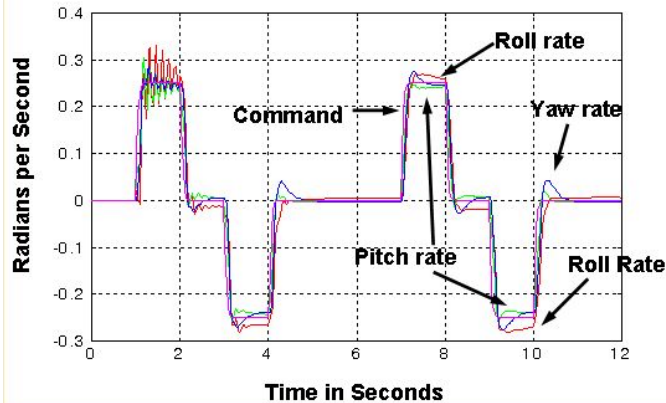


Elevator Deflection



LoFLYTE® Neural Adaptive Control

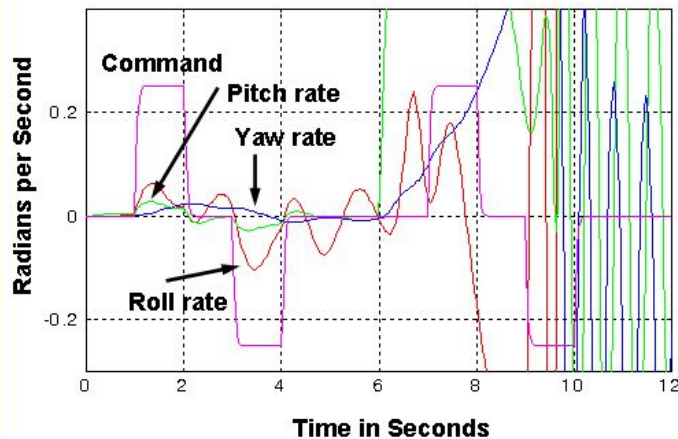
**Compensated, 100 kts, 1500 ft
Three Axes Commanded**



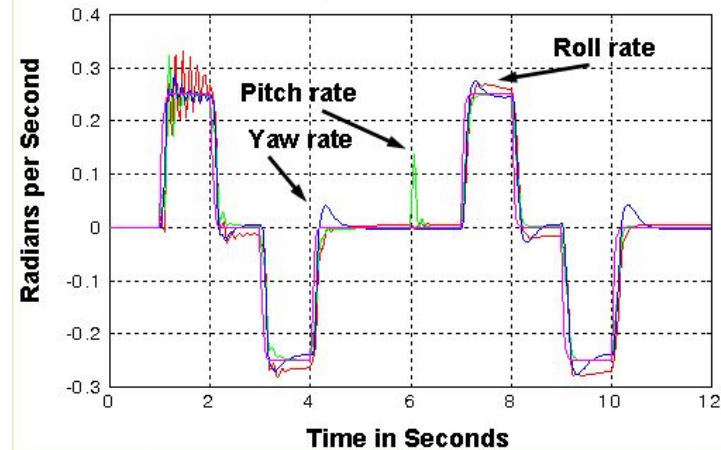
Wee!!



**Uncompensated, 100 kts, 1500 ft
Three Axes Commanded
Destabilization (CG from 51 % to 56% at 6s)**

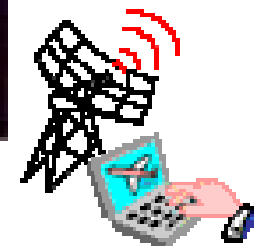


**Compensated, 100 kts, 1500 ft
Three Axes Commanded
Destabilization (CG from 51 % to 56% at 6s)**



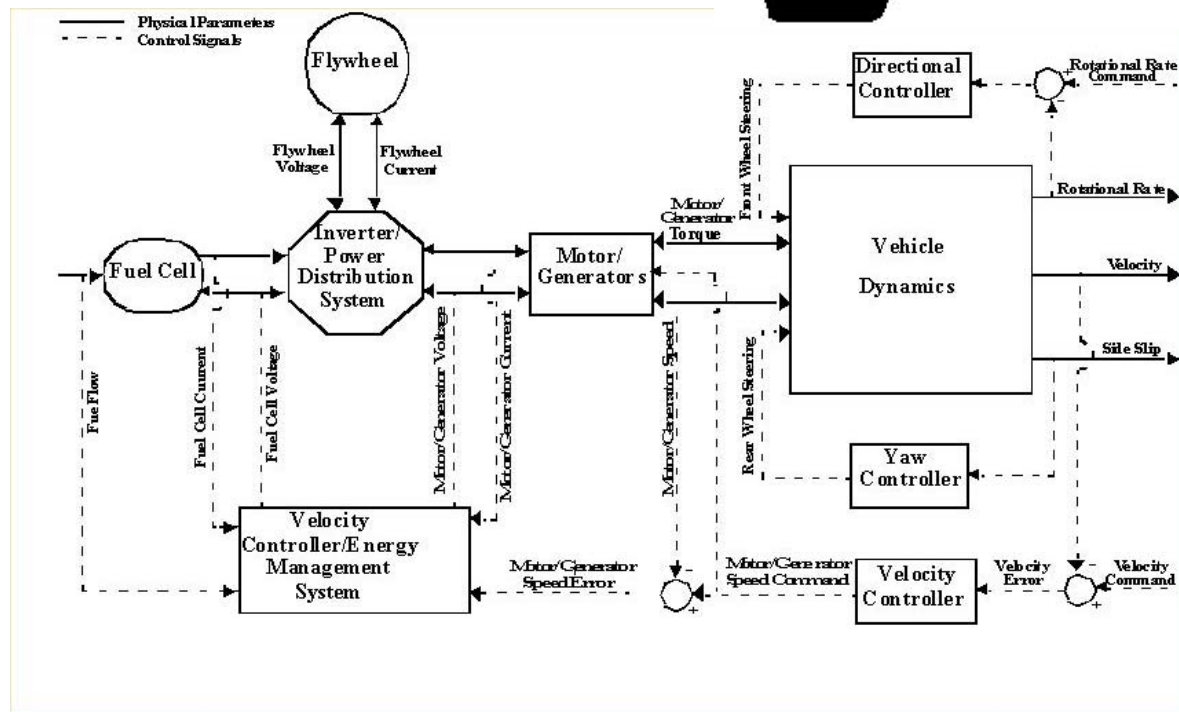
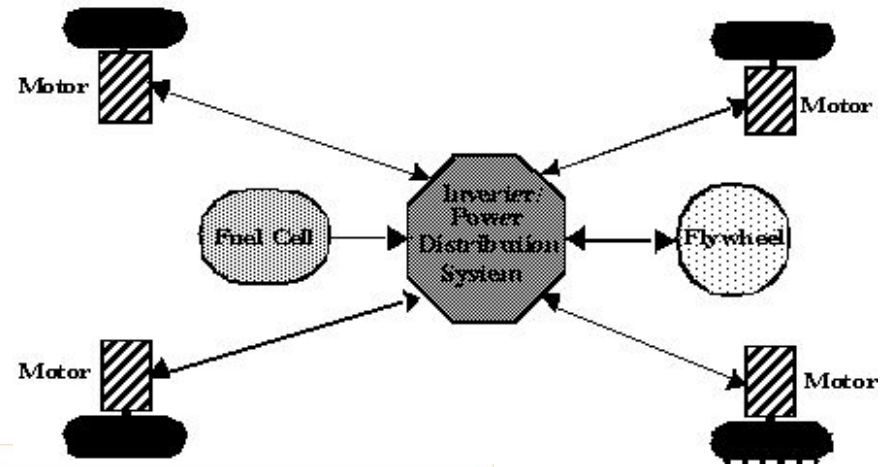
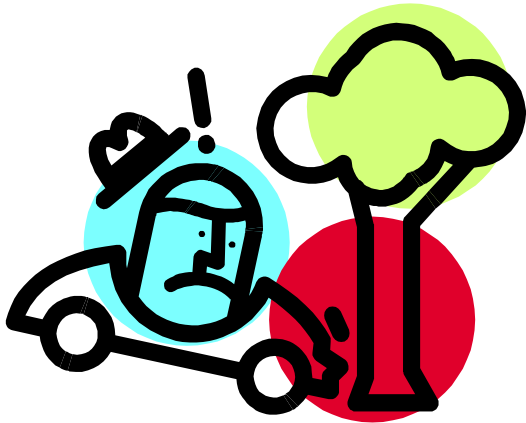
The Real Thing!!

LoFLYTE[®] at Edwards AFB



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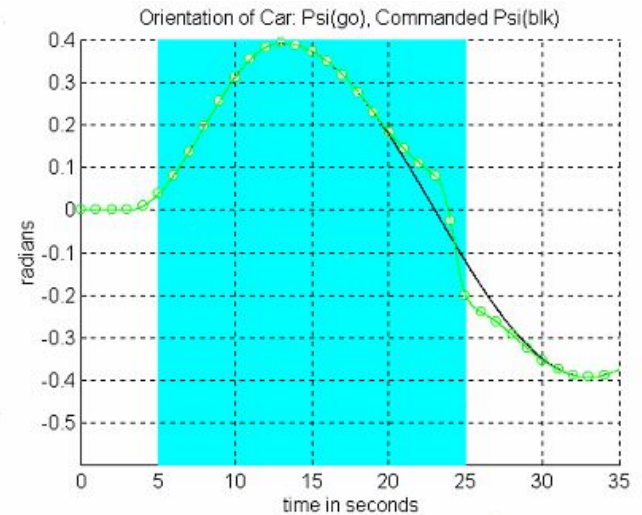
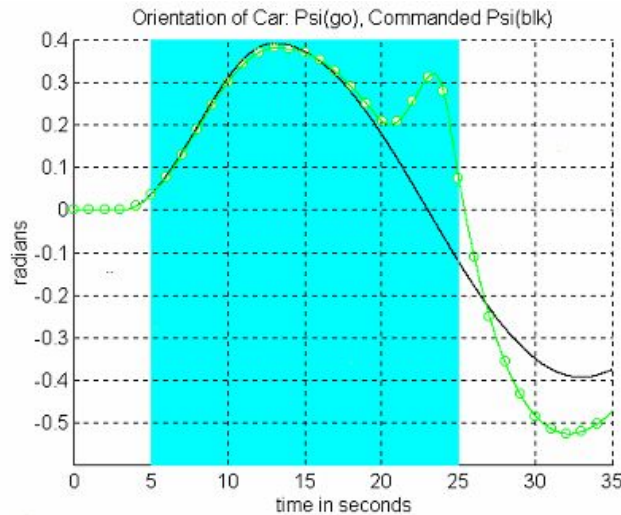
Electric Vehicle Control



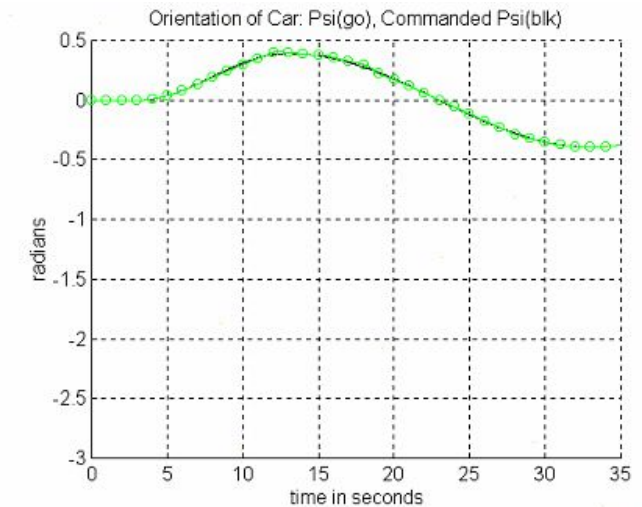
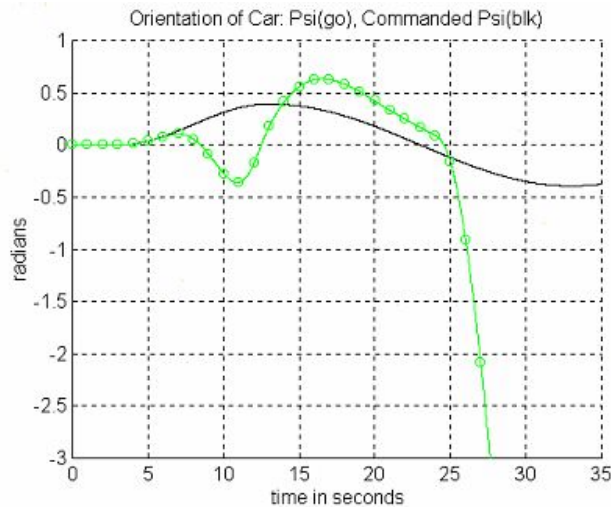
HEV Performance

If 1 is Good,
4 is Better!

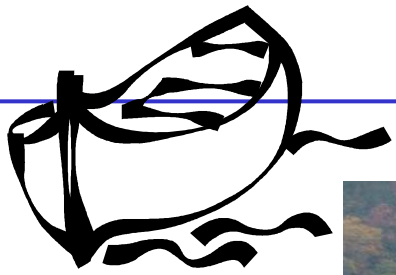
Lightly Loaded HEV
On Icy Patch



Heavily Loaded HEV
On Dry Road

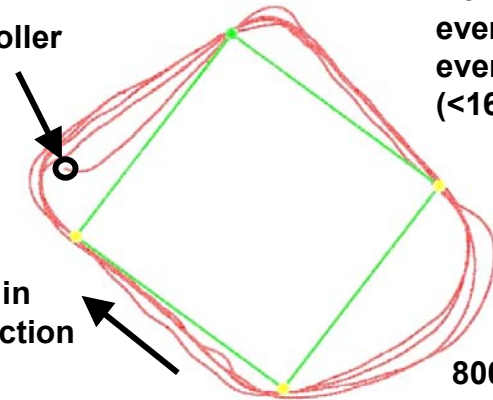


Unmanned Surface Vessel



Turned on controller

Boat traveling in clockwise direction



Controller hits every way-point every time (<16 foot tolerance)

800 feet legs

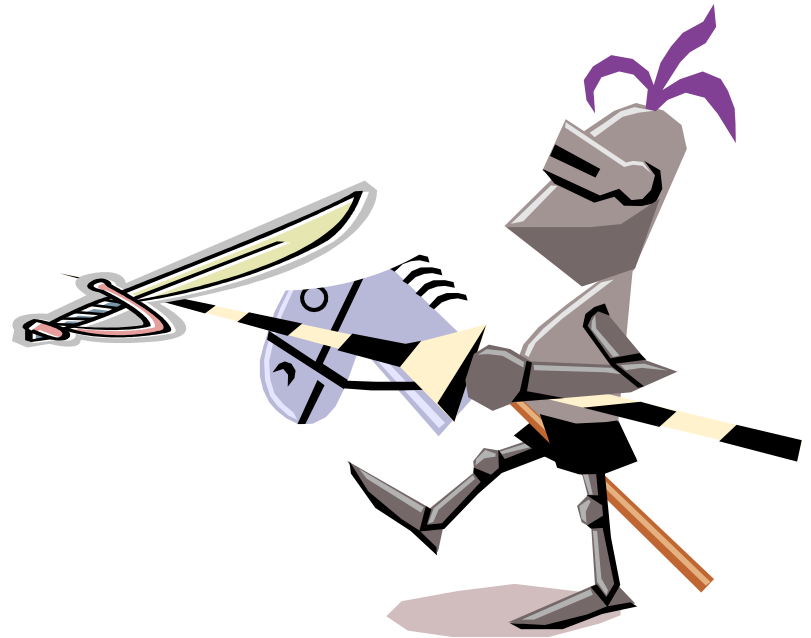


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Why Not Launch a UAV from a USV?



Off with His Head!!



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