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Technical Comments

Comment on "Matrix Method for Eigenstructure Assignment: The Multi-Input Case with Application"

Jae Weon Choi*
Pusan National University,
Pusan 609-735, Republic of Korea
Jang Gyu Lee†
Seoul National University,
Seoul 151-742, Republic of Korea
and
Hideto Suzuki‡ and Takashi Suzuki§
NASDA/Tsukuba Space Center, Ibaraki 305, Japan

Introduction

IN Ref. 1, a method for assigning eigenstructure to a linear time-invariant multi-input system is proposed. In the paper, the authors asserted that their method can assign the desired eigenvalues and eigenvectors at the desired locations. Based on the previous results on eigenstructure assignment, the authors proposed a novel computation method for a feedback gain matrix using some matrix operations in the subsection Computation of State Feedback Controller Gain. Another contribution of the paper is an application of their method to tethered satellite system (TSS). In the application, control of a space platform-based TSS is considered to assess the validity of their proposed algorithm.

In this Technical Comment, some crucial mistakes are pointed out. One is in the calculation of the feedback gain matrix F in Eq. (14) of the paper. Another one is the selection of the desired eigenvectors to decouple the platform from tether and offset dynamics in their application. In their formulation for computing the feedback gain matrix F [see Eq. (14) of Ref. 1], the pseudoinverse is used because the control input matrix B has rank deficiency in general. In other words, the gain F is obtained in the least square sense. This may cause inconsistency between the desired eigenvalues and the achieved eigenvalues. The primary objective of eigenstructure assignment is to assign the eigenvalues at the desired locations. The eigenvector assignment problem is an accompanying problem using the remaining freedom beyond closed-loop eigenvalue assignment. Thus, the exact achievement of the desired eigenvalues is very important requirement in eigenstructure assignment. In the sequel, the stability of the closed-loop system may not be guaranteed because the gain F is obtained in the least square sense. This is verified by a counterexample to follow. In addition, the selection of the desired eigenvectors in their application is not appropriate. The desired eigenvalues considered in the application are given in a complex-valued form. But the corresponding desired eigenvectors are given in a real-valued form. This fact does not agree with the previous result of Andry et al.[2] Thus, the desired eigenvectors should be changed to a complex-valued form corresponding to the complex-valued desired eigenvalues. A counterexample for illustrating the inconsistency mentioned is given in the following section.

Counterexample

Consider the following third-order controllable system:

$$A = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -2 & 1 & 2 \end{bmatrix}, \qquad B = \begin{bmatrix} 0 & 0 \\ 0 & 1 \\ 1 & 0 \end{bmatrix}$$

Let the desired eigenvalues be −2, −3, −4; then the matrix A_d defined in Eq. (11b) of Ref. 1 can be represented by $A_d = \text{diag}\{-2, -3, -4\}$. The structure of the desired eigenvectors can be selected as

$$V = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

Then according to the procedure of the paper, the achievable eigenvectors are given as follows:

$$T = \begin{bmatrix} 0.2 & -0.3 & 0 \\ -0.4 & 0.9 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

and the feedback gain matrix F is computed using the obtained T matrix and given matrices as follows:

$$F = \begin{bmatrix} 2 & -1 & -6 \\ 1.3333 & -5 & -1 \end{bmatrix}$$

Using the obtained gain matrix and, therefore, the eigenvalues of the resulting closed-loop system, $(A + BF)$ are given as 0.2538, −5.2538, and −4, which are considerably different from the desired ones (i.e., −2, −3, −4), and the closed-loop system is unstable because the feedback gain F is obtained in the least square sense. This verifies the inconsistency of the desired eigenvalues and the achieved ones.

References

[1]Pradhan, S., Modi, V. J., Bhat, M. S., and Misra, A. K., "Matrix Method for Eigenstructure Assignment: The Multi-Input Case with Application," *Journal of Guidance, Control, and Dynamics*, Vol. 17, No. 5, 1994, pp. 983–989.

[2]Andry, A. N., Jr., Shapiro, E. Y., and Chung, J. C., "Eigenstructure Assignment for Linear Systems," *IEEE Transactions on Aerospace and Electronic Systems*, Vol. AES-19, No. 5, 1983, pp. 711–729.

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*Assistant Professor, Department of Control and Mechanical Engineering.
†Professor, Department of Control and Instrumentation Engineering.
‡Senior Engineer, Guidance and Control Technology Laboratory, Space Subsystems and Technology Department.
§General Manager, Guidance and Control Technology Laboratory, Space Subsystems and Technology Department.

Reply by the Authors to Choi et al.

S. Pradhan* and V. J. Modi†
University of British Columbia,
Vancouver, British Columbia V6T 1Z4, Canada

CHOI et al. point out two "crucial mistakes." The first one pertains to the feedback gain matrix F in Eq. (14). This is an

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*Postdoctoral Fellow, Department of Mechanical Engineering.
†Professor, Department of Mechanical Engineering. Fellow AIAA.