

**University of Waterloo**  
**Department of Electrical & Computer Engineering**  
**ECE 682: Multivariable Control Systems**  
**Fall 2018 (tentative outline subject to change)**

**Lecture times, building and room number:** Tuesday 2:30pm to 5:20pm; EIT 3151.

**Instructor:** Prof. Christopher Nielsen.

**Office:** CEIT 4106.

**Office hours:** Friday 2:30pm to 4:30pm or, by appointment.

**Contact:** [cnielsen@uwaterloo.ca](mailto:cnielsen@uwaterloo.ca); ext. 32241.

**Website:** <http://learn.uwaterloo.ca/>

**Course description:** An introduction to control theory for linear time-invariant finite-dimensional systems from both the state-space and input-output viewpoints. State-space theory: the concepts of controllability, observability, stabilizability, and detectability; the pole-assignment theorem; observers and dynamic compensation; L.Q.R. regulators. Input-output theory: the ring of polynomials and the field of rational functions; the algebra of polynomial and rational matrices; coprime factorization of transfer matrices; Youla parametrization. Introduction to optimal control.

**Course prerequisites:** ECE 380 (or equivalent) and familiarity with basic linear algebra.

### **Textbook**

There is no required text for this course. Instructor will write notes on the board. A good optional text is: Linear System Theory and Design, 3rd edition, C.T. Chen.

Additional references:

- Finite-Dimensional Vector Spaces, P.R. Halmos.
- Linear Systems, T. Kailath.

### **Evaluation**

25% Assignments.

5% Tutorials (schedule to be determined).

20% Midterm.

50% Final exam.

## Tentative Topics List

### 1. Introduction to linear multivariable systems

Examples.

### 2. Linear state models

Deriving state models, Linearization, Solution of state equation, Realizations, Poles and zeros of a multivariable system.

### 3. Linear algebra

Vector spaces, Linear transformations, Quotient spaces, Invariant subspaces.

### 4. Controllability

Reachable states, Properties of controllability, PBH test, Equivalence of pole placement and controllability, Stabilizability.

### 5. Observability

The Kalman decomposition, Detectability, Observers, Observer based controllers.

### 6. Quadratic optimal control

Lyapunov equation, Riccati equation, The LQR problem, Properties of the optimal LQR feedback.

Academic integrity, grievance, discipline, appeals and note for students with disabilities: see [www.uwaterloo.ca/accountability/documents/courseoutlinestmts.pdf](http://www.uwaterloo.ca/accountability/documents/courseoutlinestmts.pdf). The text on that web site is listed below.

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