

Feedback Representations of Critical Controls for Well-Posed Linear Systems

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This is the first part in a three part study on the suboptimal full information H^∞ problem for a well-posed linear system with input space U , state space H , and output space Y . We define a cost function $Q(x_0, u) = \int_{\mathbf{R}^+} \langle y(s), Jy(s) \rangle_Y ds$, where $y \in L^2_{\text{loc}}(\mathbf{R}^+; Y)$ is the output of the system with initial state $x_0 \in H$ and control $u \in L^2_{\text{loc}}(\mathbf{R}^+; U)$, and J is a self-adjoint operator on Y . The cost function Q is quadratic in x_0 and u , and we suppose (in the stable case) that the second derivative of $Q(x_0, u)$ with respect to u is nonsingular. This implies that, for each $x_0 \in H$, there is unique critical control u^{crit} such that the derivative of $Q(x_0, u)$ with respect to u vanishes at $u = u^{\text{crit}}$. We show that u^{crit} can be written in feedback form whenever the input/output map of the system has a coprime factorization with a (J, S) -inner numerator; here S is a particular self-adjoint operator on U . A number of properties of this feedback representation are established, such as the equivalence of the (J, S) -losslessness of the factorization and the positivity of the Riccati operator on the reachable subspace.