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Active Fault Diagnosis of Linear Hybrid Systems

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Abstract: A method for active fault diagnosis of linear discrete time hybrid systems is presented. The algorithm generates appropriate test signals that can be used for sanity check during system commissioning or later in the normal phase to detect faults which are impossible to detect by means of passive diagnosis methods because of regulatory actions of the controller. The algorithm is illustrated on a two tank benchmark example.

1. INTRODUCTION

In complex large control systems there are many components with strong interaction between them. Hence the overall system depends crucially on the individual performance of the components. Therefore a fault in a single component may degrade the overall performance of the system and may even lead to unacceptable loss of system functionality. Thus fault diagnosis is of crucial importance in automatic control of complex large systems.

There are two main approaches to fault diagnosis: active and passive. In the passive approach the diagnoser observes the input and output of the system and based on the measured I/O decides whether a fault has occurred or not. Most of the available methods for fault diagnosis are of this kind.

In active fault diagnosis the diagnoser generates a test signal which excites the system to decide whether the system represents the normal behaviour or the faulty behaviour and if possible decides which faulty behaviour occurs. The test signal should be designed such that it affects the overall system as little as possible although enough to make fault diagnosis possible. The advantage of the active approach is in the operating points where the normal system and faulty system represents the same behaviour. Under such circumstances it is possible to detect faults faster by active diagnosis. Active fault diagnosis can also be used to provide sanity check in the commissioning phase by generating an appropriate test signal.

Modelling of complex systems are captured by hybrid system theory, which has been subject of intensive research in recent years, for an overview see Antsaklis and Koutsoukos [2003]. Generally speaking, a hybrid system is a dynamical system with both continuous and discrete behaviours and non-trivial interaction between continuous evolutions and discrete transitions.

Fault diagnosis of hybrid systems has been investigated recently, for a survey one can look at Mohammadi et al. [2007], Narasimhan and Biswas [2007], Zhao et al. [2005]. A class of approaches for diagnosis of hybrid systems uses discrete/temporal abstraction of the continuous dynamics Lunze [2000]. In Mohammadi et al. [2007], the diagnoser uses a discrete event abstraction of the system and the continuous dynamics information is used when it becomes necessary. In Zhao et al. [2005], the authors use a Petri net abstraction for dealing with continuous behaviour of hybrid systems. In Narasimhan and Biswas [2007] a model based diagnosis method based on a hybrid bond graph modelling framework is proposed. Particle filtering methods are another class of methods for diagnosis of hybrid systems; Koutsoukos et al. [2003], Hofbaur and Williams [2002].

All of the aforementioned approaches are in the area of passive diagnosis. In Campbell and Nikoukhah [2004], Niemann [2006] the problem of active diagnosis for linear system using an auxiliary signal for fault detection is investigated. The results of Campbell and Nikoukhah [2004] is extended for nonlinear systems in Andjelkovic et al. [2008] using linearization and also a direct optimization approach. In the field of discrete event systems, some approaches have been proposed for active diagnosis. Active diagnosis of DES is studied in Lin [1994] and input sequence for diagnosis is computed. Sampath et al. [1998] studied the active diagnosis problem of DES as a supervisory control problem.

To the knowledge of the authors there is no research considering directly active fault diagnosis of hybrid systems. In this paper an active fault diagnosis method for diagnosis of linear hybrid system in discrete time is proposed. The idea is based on reach set computations for the faulty and the normal system. For both systems, those states that the system can reach in forthcoming steps considering all possible excitations are considered. Reach sets are computed as long as the faulty system and the normal system have
In order to make this idea precise, we define following terms.

Definition 1. (Hybrid Automaton). A hybrid automaton \( \mathcal{H} \) is a collection \( \mathcal{H} = (Q, X, U, Y, Init, f, h, Inv, E, G, J) \) where,

- \( Q \) is a set of finite discrete modes, \( Q = \{ q_1, q_2, \ldots, q_m \} \),
- \( X \) is a finite set of continuous state variables,
- \( U \) is a finite collection of input variables,
- \( Y \) is a finite collection of output variables,
- \( Init \subseteq Q \times X \) is a set of initial states, 
- \( f : Q \times X \times U \to \mathbb{R}^n \) is a vector field,
- \( h : Q \times X \times U \to Y \) is an output map,
- \( Inv : Q \to 2^X \) assigns to each \( q \in Q \) an invariant set \( Inv(q) \subseteq X \times U \),
- \( E \subseteq Q \times Q \) is a set of discrete transitions, 
- \( G : E \to 2^X \times U \) assigns to each \( e = (q, q') \in E \) a guard \( g(e) \subseteq X \times U \),
- \( J : E \times X \times U \to 2X \) is a jump function that assigns a jump set \( J(e, x, u) \subseteq X \times U \) to each pair \( e \in E \) and \( x \in g(e) \).

In the case of linear hybrid systems the vector field \( f_q \) is represented by a linear difference equation: \( x_{i+1} = A_q x_i + B_q u_i \) and the output map is of the form \( y_{i+1} = C_q x_i + D_q u_i \).

The tuple \((q, x, y, y') \in Q \times X \times U \times Y\) is called a point of \( \mathcal{H} \), \((q, x) \in Q \times X\) is called the state of \( \mathcal{H} \), and \( x \in U \) the input and \( y \in Y \) is called the output of \( \mathcal{H} \). Also we refer to \((u, y) \in U \times Y\) as an observation of \( \mathcal{H} \).

Definition 2. (Execution). An execution of a hybrid automaton is a sequence \( \chi = (\sigma_0, \ldots, \sigma_i, \sigma_{i+1}, \ldots) \) where \( \sigma_0 = (q_0, x_0, u_0, y_0) \), \( \sigma_i = (q_i, x_i, u_i, y_i) \) and \( \sigma_{i+1} = (q_{i+1}, x_{i+1}, u_{i+1}, y_{i+1}) \) such that:

- Initial condition \((q_0, x_0) \in Init\),
- Continuous evolution: for all \( i, q_i = q_{i+1}, (x_{i+1}, u_{i+1}) \in Inv(q_i)\):
  \[ x_{i+1} = A_q x_i + B_q u_i \]
  \[ y_{i+1} = C_q x_i + D_q u_i \]
- Transition: for all \( i, e = (q_i, q_{i+1}) \in E, (x_i, u_i) \in G(e) : x_{i+1} = J(e, x_i, u_i), (x_{i+1}, u_{i+1}) \in Inv(q_{i+1}) \)

For modelling of faults in hybrid systems two types of faults can be considered: discrete faults and continuous faults. Discrete faults can be considered as a new mode or location in a hybrid system. Here continuous faults are also modelled as a new mode as in Mohammadi et al. [2007]. It is supposed that events that describe transitions from a normal location to a faulty location are unobservable events. The system can be in a normal condition \( N \) or a faulty condition \( F \) where each condition is a subset of \( Q \). A condition set \( K = \{ N, F_1, \ldots, F_p \}, p > 1 \) is a set of conditions that is a complete partition of the mode set \( Q \).

For every condition \( \kappa \in K \), the corresponding dynamical system, \( \Sigma_{\kappa} \), is denoted by:

\[ \Sigma_{\kappa} = \{ \kappa, X, U, Y, Init, f, Inv, E_{\kappa}, G, J \} \]

where \( E_{\kappa} = \{ e = (q, q') | q \in \kappa, q' \in \kappa \} \) and \( Init_{\kappa} \subseteq \kappa \times X \).

3. THE PROPOSED ALGORITHM

The diagnoser is a system that gives us an estimate \( \hat{\kappa}(k) \) of the current system condition \( \kappa(k) \). A passive diagnoser
receives a sequence of observations \((u(k - m), y(k - m)), \ldots, (u(k), y(k))\) as input and generates an estimate of the current condition \(\hat{\kappa}(k)\) as output. The excitation signal or the input comes from the controller.

In active diagnosis the diagnoser generates an input sequence \((u(k + 1), \ldots, u(k + m))\), applies it to the system and observes the output sequence \((y(k + 1), \ldots, y(k + m))\) to determine the system condition. The output of the diagnoser could be an estimate of the current condition of the system \(\hat{\kappa}(m')\) or the condition of the system for some finite transition into the past \(\kappa(m' - k')\). So, the active diagnosis problem can be defined as follows:

**Problem 3.** (Active diagnosis problem). Given a hybrid automaton \(\mathcal{H}\), find a sequence of input \((u(0), \ldots, u(m))\) such that the condition \(\kappa(0)\) is determined by observing the sequence \((y(0), \ldots, y(m))\).

If the input sequence exists, then we can ask for the optimal one, where optimality can be interpreted in different senses. The algorithm that is proposed in this paper looks for the shortest sequence of the inputs that can diagnose the system.

Here, it is supposed that an observer-based passive diagnoser for the hybrid system is designed which gives us the initial state of the system. For detailed description of this diagnoser, the interested reader is referred to Balluchi et al. [2002] and Mohammadi et al. [2007]. But briefly, the diagnoser consists of a bank of observers, each one designed for a discrete mode \(q_i\) of the hybrid system. The inputs of the observers are a sequence of observations \((u, y)\). Based on the output of the observers, a residual vector \(\rho = \{\tau_1, \ldots, \tau_n\}\) is generated. A zero residual \(\tau_i\) shows that the corresponding mode, \(q_i\), is consistent with the input and output sequence. If the current state of the system, \((q(k), x(k))\), is determined uniquely then the condition is also determined . A problem arises when both the faulty mode and the normal mode are recognized as consistent modes with the I/O sequence. This is because these two modes have indistinguishable executions, where indistinguishable executions are defined as follows.

**Definition 4.** (Indistinguishability). Given a hybrid system \(\mathcal{H}\) and \(\delta \in \mathbb{N}\), modes \(q\) and \(q'\) are indistinguishable on the time interval \([i, i + \delta]\) if there exist executions \(\chi = (\sigma_1, \ldots, \sigma_{i+\delta})\) and \(\chi' = (\sigma'_1, \ldots, \sigma'_{i+\delta})\), where the corresponding continuous outputs are equal.

This problem may happen very often. Consider a simple hybrid system with two discrete modes \(q_1\) an \(q_2\) and a switch between them (like an on/off valve) which forces the system to switch between these two modes. If the switch is stuck in one position, say, such that the mode \(q_1\) is active, then the faulty system has exactly the same properties as the mode \(q_1\). Therefore, the faulty mode and \(q_1\) are indistinguishable. An advantage of our method is that there is no need for modelling efforts to make these two modes distinguishable.

### 3.1 The Algorithm for a system with one faulty mode

In this subsection, the proposed algorithm is described for a system with one faulty mode. Therefore, the condition set is \([N, F]\). The possibility for expansion of the method for more than one faulty mode is discussed in the next subsection.

The idea of the proposed method is to find two executions \(\chi_1\) and \(\chi_2\) respectively from the system in normal condition, \(\Sigma_N\), and the faulty system, \(\Sigma_F\), which are distinguishable. This task is done by finding all possible outputs that both systems could reach in the future time steps considering all admissible inputs and starting from the given initial state. As soon as they represent different outputs then the required executions are found and the algorithm terminates.

To find all possible outputs that a system could reach in the future, reach set of the system and the corresponding output should be computed.

**Definition 5.** (Reach Set). Reach Set of a hybrid automata \(\mathcal{H}\) at time \(k\) denoted by \(\text{Reach}_k(\mathcal{H}, x(0), U)\) is the set of all states \((q, x) \in Q \times X\) that are reachable by a given hybrid automata \(\mathcal{H}\) at time step \(k\), starting from any initial state \(x(0) \in X(0)\) and with all possible inputs \(u \in U\).

As described in Algorithm 1, the reach set of both the normal system, \(\mathcal{R}_N(0)\) and the faulty system, \(\mathcal{R}_F(0)\) are calculated for time \(k\). It is assumed that the area of tolerable performance is given by the set \(T\). The area of untolerable performance is excluded from the reach sets. The corresponding outputs are denoted by \(Y(\mathcal{R}_N(0))\) and \(Y(\mathcal{R}_F(0))\). If the set \(\Delta_k = (Y(\mathcal{R}_N(0)) \cup Y(\mathcal{R}_F(0)) \cup Y(\mathcal{R}_N(0) \cap Y(\mathcal{R}_F(0)))\) is not empty then there exist distinguishable executions in the time interval \([0, k]\). The set \(\Delta_k\) is called the *discriminating set*. Now, there are two possible ways to determine the condition of the system. Assume that at time \(k = K_{max}\) the discriminating set \(\Delta_{K_{max}} \neq \emptyset\). It can be assumed that the system at time \(0\) is in the Normal condition. We choose a point which uniquely belongs to the future behaviour of the normal system i.e \(\mathcal{y}(K_{max}) \in (\Delta_{K_{max}} \cap Y(\mathcal{R}_N_{K_{max}}))\). After choosing the point, the optimal input to reach \(\mathcal{y}(K_{max})\) is computed and applied to the system. If \(\mathcal{y}(K_{max}) = \mathcal{y}(K_{max})\) then system is in the normal condition otherwise it is in the faulty condition. Since the termination of the algorithm is not guaranteed, \(K_{max}\) may not exist. For practical applications a bound \(\beta\) on \(K_{max}\) is set. If the algorithm does not terminate after \(\beta\) steps, it is recognized as indiagnosable by this method.

Another strategy is to assume that \(\mathcal{y}(0) = F\) and choose \(\mathcal{y}(K_{max}) \in (\Delta_{K_{max}} \cap Y(\mathcal{R}_F_{K_{max}}))\). If \(\mathcal{y}(K_{max}) = \mathcal{y}(K_{max})\) then the system is in faulty condition otherwise it is the normal condition. In Algorithm 1, the first strategy is chosen.

In the case of linear systems, having the convex polyhedral of \(X(0), U\), the reach set can be computed as:

\[
\text{Reach}(\Sigma, X(0), U) = AX(0) \oplus BU,
\]

where \(\oplus\) is the geometric or Minkowski sum. The first part considers the effect of the autonomous part of the system, \(x(k + 1) = Ax(k)\), which is computed as mapping of the convex set \(X(0)\) through the matrix \(A\). Because the mapping of a convex set by a linear transformation yields a convex set, the resulting set is also convex. Similarly, in the second part of (1) the effect of input is computed by mapping the set \(U\) by matrix \(B\) which again results in a convex set. Finally, the reach set is computed as
The cost function calculates the union of results. The algorithm to each polytope separately and at the end polytopes. In this case it is enough to apply the above procedure repeats until \( K_{\text{max}} = 1 \). For all \( k \) the algorithm starts with \( x_{k-1} \). At time \( k \), the information that the diagnoser is using for predicting the reach set is the output reference signal, \( u_k(k) \) the input reference signal and \( x_f \) is the final desired state.

Table 1. Active Fault Diagnosis

<table>
<thead>
<tr>
<th>Algorithm 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>Given ( x_0, \beta, \Sigma_N, \Sigma_F, (\Sigma_N \neq \Sigma_F) )</td>
</tr>
<tr>
<td>Find condition ( \kappa )</td>
</tr>
<tr>
<td>( k = 0, I = x_0; R_{N_0} = R_{F_0} = x_0 )</td>
</tr>
<tr>
<td>Repeat</td>
</tr>
<tr>
<td>( R_{N_k} = \text{Reach}(\Sigma_N, R_{N_{k-1}}, U) )</td>
</tr>
<tr>
<td>( R_{F_k} = \text{Reach}(\Sigma_F, R_{F_{k-1}}, U) )</td>
</tr>
<tr>
<td>( I = Y(R_{N_k}) \setminus Y(R_{F_k}) )</td>
</tr>
<tr>
<td>( k = k + 1 )</td>
</tr>
<tr>
<td>Until ( (I \neq \emptyset \land k &gt; \beta - 1) )</td>
</tr>
<tr>
<td>IF ( I = \emptyset ) The fault ( F ) is undiagnosable</td>
</tr>
<tr>
<td>Else</td>
</tr>
<tr>
<td>Solve the optimization problem</td>
</tr>
<tr>
<td>( \min_{u_{K_{\text{max}}}} J(x_{K_{\text{max}}}, u_{K_{\text{max}}}, y_{K_{\text{max}}}) )</td>
</tr>
<tr>
<td>s.t. ( \Sigma_N )</td>
</tr>
<tr>
<td>( x_0 = x_0, x_f \in Y^{-1}(I) )</td>
</tr>
<tr>
<td>Apply ( u_{K_{\text{max}}} ) to the system</td>
</tr>
<tr>
<td>IF ( y_{K_{\text{max}}} \in Y(I) ) Then ( \kappa = N ) Else ( \kappa = F )</td>
</tr>
</tbody>
</table>

the Minkowski sum of these two sets. For computational reasons, the representation used for the reach set and input set consists of sets which are closed under linear transformation and Minkowski sum such as polytopes, ellipsoids or zonotopes Girard et al. [2006].

In the case of hybrid systems, as is shown in Algorithm 2 in Table 2, enabled transitions should also be considered and the corresponding jump functions should be applied. Note that in general the reach set could be nonconvex and disconnected i.e., a finite union of \( p \) disconnected convex polytopes. In this case it is enough to apply the above algorithm to each polytope separately and at the end calculate the union of results.

The cost function \( J(x_k, u_k, y_k) \) is the same as the cost function for the controller, which can have the following from:

\[
\Sigma_{k=0}^{K_{\text{max}}} \| y(t+k) - r(k) \| + |u(t+k) - u_k(k)| + \| x(t+k) - x_f \|,
\]

where \( r(k) \) is the output reference signal, \( u_k(k) \) the input reference signal and \( x_f \) is the final desired state.

Table 2. Reach Set Computation

<table>
<thead>
<tr>
<th>Algorithm 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Given ( H, R_k, U )</td>
</tr>
<tr>
<td>( R = \emptyset, R_G = \emptyset )</td>
</tr>
<tr>
<td>( Q_R = { q \mid q(x) \in R_k } )</td>
</tr>
<tr>
<td>For all ( q \in Q_R )</td>
</tr>
<tr>
<td>( X = { x \mid q(x) \in R_k } )</td>
</tr>
<tr>
<td>( X_q = X \cap \text{int}(q) )</td>
</tr>
<tr>
<td>( R_X = A_q X_q \cup B_q U )</td>
</tr>
<tr>
<td>( E_q = { e \mid (q, q') \in E } )</td>
</tr>
<tr>
<td>For all ( e \in E_q )</td>
</tr>
<tr>
<td>( G_e = X \circ g(e) )</td>
</tr>
<tr>
<td>( G_{\text{trans}} = \text{execute_transition}(G_e) )</td>
</tr>
<tr>
<td>( R_{G_e} = A_q G_{\text{trans}} \cup B_q U )</td>
</tr>
<tr>
<td>( R_G = R_G \cup R_{G_e} )</td>
</tr>
<tr>
<td>End</td>
</tr>
<tr>
<td>( R = R \cup R_G \cup R_{G_e} )</td>
</tr>
<tr>
<td>End</td>
</tr>
<tr>
<td>( \text{Reach}_{k+1}(H, R_k, U) = R )</td>
</tr>
</tbody>
</table>

In the above formulation we have assumed that the system is in the normal condition and therefore the optimization problem is solved by constraining the variables to the hybrid dynamic of the normal system \( \Sigma_N \). In the case which the system is in the faulty condition and it is not possible to remain in the area of required performance, it is required that the system will remain in a region of tolerable performance. Suppose that the area of tolerable performance is described by the polytope \( T = \{ x \in \mathbb{R}^n \mid x \in M \} \). To ensure that system states will still remain in the polytope of the tolerable performance, the following constraints should be added to the optimization problem:

\[
\mathcal{P}_x(i) \leq M_{i+k}^\text{max} - M_{i}^\text{max}.
\]

Since we have supposed that there exist an observer that gives us the current state at each time, this new information can be used in the algorithm. Suppose that at time \( k - 1 \) the algorithm starts with \( x_{k-1} \). At time \( k \), the information that the diagnoser is using for predicting the behaviour of the system at time \( k + 1 \) is the polytope \( \text{Reach}_k(\Sigma, x_{k-1}, U) \). While the information from the observer for the current state is more exact. So based on this information, the diagnoser can predict the future behaviour of the system more precisely. Therefore, the overall algorithm can be described as follows. At each time step the output of the observer is given as the input to the main algorithm as described in Algorithm 1. When the optimal input sequence \( u(k), \ldots, u(k + K_{\text{max}}) \) is computed only the first element, \( u(k) \), is applied to the system. The overall procedure repeats until \( K_{\text{max}} = 1 \), which means that only in one step it is possible to find the point that uniquely belongs to the normal predicted behaviour of the system. The diagnoser applies the optimal input to the system and then the status of the system can be determined. The modified version of the algorithm is more computationally demanding but it can diagnose the fault faster because it also uses available information from the observer.

3.2 Extension for more than one faulty mode

The algorithm can be extended as follows when there is more than one faulty mode. At first, the algorithm tries to choose a state that its corresponding output uniquely belongs to one of the sets \( Y(R_{x_k}, \kappa) \in K \). Then the optimal input for driving the system to the chosen state is applied to the system. If the system could reach the target state then it is in the condition \( \kappa \). Otherwise if the current output is consistent with just one of the modes then the corresponding condition is the system condition. But if it is consistent with more than one mode, then the same procedure should be repeated for these modes starting from the new initial condition.

4. EXAMPLE

The proposed method is tested on the two tank system depicted in Fig. 2. The system consists of two cylindrical tanks with cross sectional area \( A \). These two tanks are connected together by two pipes at the bottom and at level \( h_v \). The flows through the pipes, denoted by \( Q_{12}V_{12} \) and \( Q_{12}V_1 \), are controlled using two on/off valves \( V_{12} \) and \( V_1 \). There is a flow \( Q_1 \) through a pump to tank 1 which is a continuous input. Dynamical equations of the system is described as follows.
Fig. 2. Two-tank system
\[ \dot{h}_1 = \frac{1}{A} (Q_1 - Q_{12}V_{12} - Q_{12}V_1 - Q_L), \] (2)
\[ \dot{h}_2 = \frac{1}{A} (Q_{12}V_{12} + Q_{12}V_1 - Q_N), \] (3)
where \( h_1 \) and \( h_2 \) denote the levels of tanks 1 and 2 respectively. The flow \( Q_{12}V_{12} \) is described as:
\[ Q_{12}V_{12} = V_{12}k_{12}\text{sign}(h_1 - h_2)\sqrt{2g|h_1 - h_2|}, \]
where \( g \) is the gravity constant and \( k_{12} \) is a constant. Similarly \( Q_L = V_{12}k_L\sqrt{2gh_1} \) and \( Q_N = V_Nk_N\sqrt{2gh_2} \). The flow through the valve \( V_1 \) is described by:
\[ Q_{12}V_1 = V_1k_1\text{sign}(\max\{V_{max}, h_1\} - \max\{h_v, h_2\}) \]
\[ \sqrt{2g(\max\{h_v, h_1\} - \max\{h_v, h_2\})}. \]

In order to apply the reach set computation algorithm to the above system, the dynamic of the system should be described as a discrete time linear hybrid system. This task is done in three steps. First, four discrete modes corresponding to four combinations of binary inputs are generated. In each of these modes the governing equations are obtained by substituting the corresponding values of binary inputs. The system switches between these four discrete modes based on the binary input vector \( V = [V_{12}, V_1] \). Then, the nonlinear relation \( \sqrt{x} \) is approximated by a straight line \( x \). The resulting equations are piecewise affine. Finally, differential equations 2, 3 are discretized in time by Euler approximation \( \dot{h}_i(t) \approx \frac{h_i(t+1) - h_i(t)}{T_s} \), where \( T_s \) is sample time.

To compute \( \mathcal{R}_k \) from \( \mathcal{R}_{k-1} \), all possible binary and continuous inputs must be considered. Algorithms 2 considers all possible continuous inputs. To consider the effect of all possible binary inputs, for every corresponding discrete mode, the reach set is computed via algorithm 2 and \( \mathcal{R}_k \) is obtained by calculating the union of the results.

The proposed active fault diagnosis algorithm is used for sanity check of the valve \( V_1 \). A stuck ON fault is considered in \( V_1 \) and the algorithm is used to generate the shortest test signal sequence to diagnose this fault. Nine different scenarios as shown in Table 3 are considered. In each scenario, a binary input is used or fixed during the diagnosis to 0 or 1.

Fig. 3 and 4 show the results for scenario 1 where both discrete inputs are used. In order to make the difference between \( Y(\mathcal{R}_{N_2}) \) and \( Y(\mathcal{R}_{F_5}) \) observable, the discriminating set in algorithm 1 is changed to \( I = Y(\mathcal{R}_{N_2}) \setminus (Y(\mathcal{R}_{F_5}) \oplus B(0, d)) \), where \( B(0, d) \) is a box defined as \( B(0, d) = \{ x \in \mathbb{R}^n | 0 \leq x_i \leq d \} \). The algorithm terminates after \( k = 5 \) steps. \( Y(\mathcal{R}_{N_2}) \) and \( Y(\mathcal{R}_{F_5}) \oplus B(0, 0.01) \) are shown in Fig. 3.

As it is shown in Table 3, scenarios 4, 5, 6 are not applicable. Because \( V_1 \) is fixed as 1 and therefore the model of the normal system becomes exactly the same as the model of the faulty system. Moreover, it shows that using a valve as a free input variable causes more computational complexity than fixing it. The reason is that the main source for the computational complexity of the algorithm is nonconvexity of the reach set which is caused by either crossing a gaurd (\( h_v \) here) or a switching input. It should be noted that however using both valves is the most computationally demanding scenario but for

<table>
<thead>
<tr>
<th>Scenario</th>
<th>( V_1 )</th>
<th>( V_{12} )</th>
<th>( K_{max} )</th>
<th>CPU time (sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>x</td>
<td>x</td>
<td>5</td>
<td>8.9</td>
</tr>
<tr>
<td>2</td>
<td>x</td>
<td>1</td>
<td>6</td>
<td>0.87</td>
</tr>
<tr>
<td>3</td>
<td>x</td>
<td>0</td>
<td>5</td>
<td>0.71</td>
</tr>
<tr>
<td>4</td>
<td>1</td>
<td>x</td>
<td>NA</td>
<td>-</td>
</tr>
<tr>
<td>5</td>
<td>1</td>
<td>1</td>
<td>NA</td>
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<td>0</td>
<td>1</td>
<td>6</td>
<td>0.54</td>
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this scenario the algorithm will find the shortest input sequence for diagnosis while by fixing valves it may not find the shortest sequence e.g. as it is the case in scenarios 2, 9.

Fig. 5 demonstrates the case where the faulty and the normal system exhibit same dynamic behaviour. In this example a model predictive controller is designed for the two tank system. Fig. 5 shows the simulation of the closed loop system. As one can see the control variable $V_1$ is manipulated such that the output of the system in the normal condition and in the faulty one is exactly the same. In this situation if a stuck ON fault happens, no passive diagnoser would be able to diagnose it, while the active diagnoser proposed here is capable of detecting this fault. Our active diagnoser was started at $t = 200$ sec. and the result is shown in Fig. 6.

5. CONCLUSION AND FUTURE WORKS

This paper presented an approach for active fault diagnosis of hybrid systems based on reach sets computation of both the normal and the faulty modes. The proposed method can be used for sanity check of the system at the commissioning phase and also periodically during normal operation for faster detection of faults or detection of faults when it is impossible to detect them by a passive diagnoser.

During the diagnosis it is assumed that the system is in the normal mode of the operation. To ensure that if the system is faulty, it will remain in the tolerable performance region, the optimization problem is solved subject to constraints describing polytope of the tolerable area. It might happen that the optimization become infeasible by these constraints. This issue is subject to future investigations.

REFERENCES


