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Singular Perturbation Approximation of Balanced Systems

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Abstract

This paper relates the singular perturbation approximation technique for model reduction to the direct truncation technique if the system model to be reduced is stable, minimal, and internally balanced. It shows that these two methods constitute two fully compatible model reduction techniques for a continuous-time system, and both methods yield a stable, minimal, and internally balanced reduced order system with the same L_∞-norm error bound on the reduction. Although the upper bound for both reductions is the same, the direct truncation method tends to have smaller errors at high frequencies and larger errors at low frequencies while the singular perturbation approximation method will display the opposite character. It also shows that a certain bilinear mapping not only preserves the balanced structure between a continuous-time system and an associated discrete-time system, but also preserves the slow singular perturbation approximation structure. Hence, the continuous-time results on the singular perturbation approximation of balanced systems are easily extended to the discrete-time case. Examples are used to show the compatibility and the differences in the two reduction techniques for a balanced system.

1 Introduction

Recent control literature shows that an important role is played by the balanced realization truncation (weighted and unweighted) order reduction techniques in model and controller reduction procedures. For the open-loop model reduction problem, a technique of truncation of a balanced realization due to Moore [1] offers some advantages over some conventional model reduction techniques (See [2] for an overview of many of these reduction schemes). It is well known now that direct balanced realization truncation retains stability in the reduced order model (under a very weak condition) [3]. This reduced order system is also balanced and minimal [3] (in the continuous-time case). Further, there is an easily calculable frequency error bound available [4–6]. There are, however, some drawbacks of this reduction tec..nique. For instance, the reduction technique has a mismatch of the DC gains of the high order model and the reduced order model. As pointed out in Reference [7], the technique tends to give good approximation of the impulse response but have a large steady state error for the step response. In fact, if the order reduction is 1, the frequency domain error between the full order model and the reduced order model will achieve its upper bound (twice the smallest Hankel singular value of the full order model) at DC [5]. In contrast, at very high frequencies, the error of the reduction tends to zero. This is to say that the reduction error of the directly balanced truncation method of Moore tends to zero at very high frequencies but is in general nonzero at very low frequencies. The latter property at least is quite contradictory to what one would often seek in model and controller reduction. In most situations, one would expect a nice reduction procedure to retain as much as possible the low and medium frequency properties of the high order transfer function. Certainly, the introduction of frequency weighting into the balanced truncation method will overcome part of the problem. However, the price for this is the loss of the easily calculable frequency error bound (see [5] and [6]). Also, one still faces the problem of mismatch of the DC gains in the reduction. This motivated us to look for alternatives. Inspired by some interesting works of Fernando and Nicholson [8–12], we will show that the singular perturbation approximation of a balanced realization is a good candidate for model reduction problems on the grounds of the provable properties of the frequency domain error.

In the next section, we present a brief review of the properties of directly truncating a balanced system and the singular perturbation order reduction technique. Then in Section 3, we will show that by applying the singular perturbation approximation technique to a balanced realization (instead of truncation of the realization), one can obtain a reduced order system which matches the DC gain and still has an easily calculable frequency error bound (as for the direct truncation). Section 4 will extend the results to discrete-time systems. Some examples will be used in Section 5 to illustrate the above model reduction methods. Section 6 concludes the paper.

Due to lack of space, we present the main ideas and results without proofs; the reader is referred to the full paper [19] for details and proofs.

2 Preliminaries

Let us consider an n^{th} order, linear, time-invariant and asymptotically stable system $G(s)$ with a minimal realization

$$G(s) = C(sI_n - A)^{-1}B + E \tag{2.1}$$

The controllability gramian and the observability gramian of the system are defined as follows:

$$P = \int_0^\infty e^{At}BB^Te^{A^Tt}\,dt \tag{2.2a}$$

$$Q = \int_0^\infty e^{A^Tt}C^TCe^{At}\,dt \tag{2.2b}$$

It is well known that these gramians satisfy the following Lyapunov equations:

$$AP + PA^T + BB^T = 0 \tag{2.3a}$$

$$A^TQ + QA + C^TC = 0 \tag{2.3b}$$

A realization (A, B, C, E) of the system $G(s)$ is said to be internally balanced if

$$P = Q = \Sigma = \text{diag}\{\sigma_1, \sigma_2, \ldots, \sigma_n\} \tag{2.4}$$

with $\sigma_i \geq \sigma_{i+1}$, $i = 1, 2, \ldots, n-1$.

Now partition the balanced system (A, B, C, E) and the gramian Σ conformally as

$$A = \begin{bmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{bmatrix}, \quad B = \begin{bmatrix} B_1 \\ B_2 \end{bmatrix}, \quad C = [C_1 \quad C_2], \quad \Sigma = \begin{bmatrix} \Sigma_1 & 0 \\ 0 & \Sigma_2 \end{bmatrix} \tag{2.5}$$

where A_{11} and Σ_1 are $r \times r$ $(r < n)$ matrices.

Moore suggested [1] that the subsystem (A_{11}, B_1, C_1) should be a good approximation of the balanced system (A, B, C) if $\sigma_r \gg \sigma_{r+1}$. We call this r^{th} order system a direct truncation (DT) approximation of the balanced system. Several well known results concerning the approximation are available.

Lemma 2.1 [3]: *The subsystems (A_{ii}, B_i, C_i) $(i = 1, 2)$ are internally balanced with gramian Σ_i $(i = 1, 2)$.*

Lemma 2.2 [3]: *The matrices A_{ii} $(i = 1, 2)$ are asymptotically stable, i.e., $Re(\lambda_k\{A_{ii}\}) < 0$ for all k $(i = 1, 2)$ if Σ_1 and Σ_2 have no diagonal entries in common. Further, the subsystem (A_{11}, B_1, C_1) is controllable and observable.*

Lemma 2.3 [4,5,6]: *There is an upper bound for the approximation error.*

$$\begin{aligned}\|C(j\omega I - A)^{-1}B - C_1(j\omega I - A_{11})^{-1}B_1\|_\infty &\leq 2(\sigma_{r+1} + \cdots + \sigma_n) \\ &= 2\text{tr}(\Sigma_2)\end{aligned} \tag{2.6}$$

Here, the *infinity norm* is defined as

$$\|X(j\omega)\|_\infty \triangleq \sup_{\omega \in \mathbf{R}} \overline{\sigma}\{X(j\omega)\} = \sup_{\omega \in \mathbf{R}} \lambda_{\max}^{1/2}\{X(j\omega)X^T(-j\omega)\}.$$

Now let us focus on the application of the singular perturbation techniqu. to the order reduction of a linear, time-invariant system. The interested reader is referred to [13] and [14] for overviews of the technique.

Consider a linear, time-invariant system

$$\begin{bmatrix} \dot{x} \\ \dot{z} \end{bmatrix} = \begin{bmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{bmatrix}\begin{bmatrix} x \\ z \end{bmatrix} + \begin{bmatrix} B_1 \\ B_2 \end{bmatrix}u, \quad \begin{bmatrix} x(0) \\ z(0) \end{bmatrix} = \begin{bmatrix} x^0 \\ z^0 \end{bmatrix} \tag{2.7}$$

$$y = [C_1 \quad C_2]\begin{bmatrix} x \\ z \end{bmatrix} + Eu, \quad x \epsilon \mathbf{R}^r, \quad z \epsilon \mathbf{R}^{n-r}, \quad (r < n)$$

where $u(t) \epsilon \mathbf{R}^\ell$ is a control vector and $y(t) \epsilon \mathbf{R}^m$ is an output vector. In case z is a fast and stable variable (See [13] and [14]), (2.7) can be approximated by setting $\dot{z}$ to zero. More precisely, if

$$\min_i |\lambda_i\{A_{22}\}| > \max_j |\lambda_j\{A_{11} - A_{12}A_{22}^{-1}A_{21}\}| \tag{2.8}$$

and

$$Re(\lambda_i\{A_{22}\}) < 0 \qquad \forall i \tag{2.9}$$

we r.place (2.7) by

$$\begin{aligned} \dot{x}_s &= A_{11}x_s + A_{12}z_s + B_1u, \qquad x_s(0) = x^0 \\ 0 &= A_{21}x_s + A_{22}z_s + z_s + B_2u \\ y_s &= C_1x_s + C_2Z_s + Eu \end{aligned} \tag{2.10}$$

whence

$$\begin{aligned} \dot{x}_s &= \overline{A}x_s + \overline{B}u_s, \qquad x_s(0) = x^0 \\ y_s &= \overline{C}x_s + \overline{E}u_s \end{aligned} \tag{2.11}$$

where

$$\begin{aligned} \overline{A} &= A_{11} - A_{12}A_{22}^{-1}A_{21} \; (= A_{11} - A_{12}\widehat{A}_{22}^{-1}\widehat{A}_{21}) \\ \overline{B} &= B_1 - A_{12}A_{22}^{-1}B_2 \; (= B_1 - A_{12}\widehat{A}_{22}^{-1}\widehat{B}_2) \\ \overline{C} &= C_1 - C_2A_{22}^{-1}A_{21} \\ \overline{E} &= E - C_2A_{22}^{-1}B_2 \end{aligned} \tag{2.12}$$

It is generally accepted that (2.11) is a good approximation to (2.7) except near $t = 0$ (when a very fast change in $z(\cdot)$ occurs in a so-called boundary layer). In this paper, we shall examine approximation where (2.7) is balanced, but where (2.8) does *not* necessarily hold; we shall demonstrate that the frequency domain error between the transfer function matrices of (2.7) and (2.11) has attractive properties.

It is very interesting to note that singular perturbation approximations can be developed in the frequency domain [9]. For a system given as in (2.1) (not necessarily balanced), using the partition of the system of (2.5), then the transfer function can be written in the form

$$G(s) = [C_1 \quad C_2] \begin{bmatrix} sI_r - A_{11} & -A_{12} \\ -A_{21} & sI_{n-r} - A_{22} \end{bmatrix}^{-1} \begin{bmatrix} B_1 \\ B_2 \end{bmatrix} + E \qquad (2.13)$$

Now we can decompose additively the transfer function $G(s)$ as

$$G(s) = G_1(s) + G_2(s) \qquad (2.14)$$

where

$$\begin{aligned} G_1(s) &= \overline{C}(s)(sI_r - \overline{A}(s))^{-1}\overline{B}(s) + E \\ \overline{A}(s) &= A_{11} + A_{12}(sI_{n-r} - A_{22})^{-1}A_{21} \\ \overline{B}(s) &= B_1 + A_{12}(sI_{n-r} - A_{22})^{-1}B_2 \\ \overline{C}(s) &= C_1 + C_2(sI_{n-r} - A_{22})^{-1}A_{21} \\ G_2(s) &= C_2(sI_{n-r} - A_{22})^{-1}B_2 \end{aligned} \qquad (2.15)$$

Now we have the following result [9]:

Lemma 2.4: *Consider a continuous-time, linear, time-invariant, and stable system (A, B, C, E) defined as in (2.1). Partition the system conformally as in (2.5) and then decompose additively the transfer function $G(s) = G_1(s) + G_2(s)$ where $G_1(s)$ and $G_2(s)$ are defined as in (2.15). Now if the subsystem $G_2(s)$ is stable and "fast" (i.e., its states have very fast transient dynamics and decay rapidly to certain "steady values") in the neighbourhood of a given frequency $s = \sigma_0$, then by ignoring the dynamics of this fast subsystem, the system with transfer function $G(s)$ can be approximated by the reduced order system with transfer function*

$$\overline{G}(s) = \overline{C}(\sigma_0)\left[sI_r - \overline{A}(\sigma_0)\right]^{-1}\overline{B}(\sigma_0) + \overline{E}(\sigma_0) \qquad (2.16)$$

where

$$\overline{E}(\sigma_0) = E + C_2(\sigma_0 I_{n-r} - A_{22})^{-1}B_2$$

and $\overline{A}(s), \overline{B}(s)$ and $\overline{C}(s)$ are defined as in (2.15).

This model order reduction method is termed the *generalized (slow) singular perturbation approximation* at frequency $s = \sigma_0$ [9].

The meaning of the modification of the feedthrough term in (2.16) is very clear. It will ensure that the magnitude of the reduced order system (2.16) matches the magnitude of the high order system (2.1) at the frequency $s = \sigma_0$, i.e., the reduction error becomes zero at $s = \sigma_0$. If $\sigma_0 = 0$, then we can match the DC gains in the reduction.

It should be pointed out that, theoretically speaking, the frequency σ_0 can be any complex number. However this would cause the transfer function $\overline{G}(s)$ of the reduced order system to become a complex coefficient transfer function. This is not attractive at all. Hence, one should concentrate on a real frequency σ_0 in the generalized singular perturbation approximation.

Now we consider two extreme cases of the generalized singular perturbation reduction method:

(i) $\sigma_0 = 0$; then we have the reduced order model as

$$\overline{G}(s) = \overline{C}(0)[sI_r - \overline{A}(0)]^{-1}\overline{B}(0) + \overline{E}(0)$$

where

$$\begin{aligned} \overline{A}(0) &= A_{11} - A_{12}A_{22}^{-1}A_{21} \\ \overline{B}(0) &= B_1 - A_{12}A_{22}^{-1}B_2 \\ \overline{C}(0) &= C_1 - C_2A_{22}^{-1}A_{21} \\ \overline{E}(0) &= E - C_2A_{22}^{-1}B_2 \end{aligned} \qquad (2.17)$$

Hence, we obtain the familiar singular perturbation approximation as in (2.12).

(ii) $\sigma_0 \to \infty$; we obtain

$\overline{A}(\sigma_0) \to A_{11}$, $\overline{B}(\sigma_0) \to B_1$, $\overline{C}(\sigma_0) \to C_1$, $\overline{E}(\sigma_0) \to E$, *as* $\sigma_0 \to \infty$

Hence, this case corresponds to the direct truncation reduction method. (Although to this point in this paper, we have not assumed that we are working with a balanced realization).

Now we consider the singular perturbation approximation method in the discrete-time case. As in the continuous-time case, for the discrete-time system defined by

$$\begin{aligned} x(k+1) &= \Phi x(k) + \Gamma u(k) \\ y(k) &= Hk(k) + E_d u(k), \end{aligned} \qquad (2.18)$$

with the system partitioned conformally as

$$\Phi = \begin{bmatrix} \Phi_{11} & \Phi_{12} \\ \Phi_{21} & \Phi_{22} \end{bmatrix}, \quad \Gamma = \begin{bmatrix} \Gamma_1 \\ \Gamma_2 \end{bmatrix}, \quad H = [H_1 \quad H_2] \qquad (2.19)$$

the transfer function $G(z)$ can be decomposed additively as

$$\begin{aligned} G(z) &= H(zI_n - \Phi)^{-1}\Gamma + E_d \\ &= G_1(z) + G_2(z) \end{aligned} \qquad (2.20)$$

where

$$\begin{aligned} G_1(z) &= \overline{H}(z)\left[zI_r - \overline{\Phi}(z)\right]^{-1}\overline{\Gamma}(z) + E_d \\ \overline{\Phi}(z) &= \Phi_{11} + \Phi_{12}(zI_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ \overline{\Gamma}(z) &= \Gamma_1 + \Phi_{12}(zI_{n-r} - \Phi_{22})^{-1}\Gamma_2 \\ \overline{H}(z) &= H_1 + H_2(zI_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ G_2(z) &= H_2(zI_{n-r} - \Phi_{22})^{-1}\Gamma_2 \end{aligned} \qquad (2.21)$$

Now we have [11]:

Lemma 2.5: *Consider a discrete-time, linear, time-invariant, and stable system (Φ, Γ, H, E_d) defined as in (2.18) with transfer function matrix $G(z)$ as in (2.20). Partition the system conformally as in (2.19) and decompose additively $G(z) = G_1(z) + G_2(z)$ where $G_1(z)$ and $G_2(z)$ are defined as in (2.21). Now if the subsystem $G_2(z)$ is stable and "fast" near the frequency $z = z_0$, we then obtain by neglecting the dynamics of this fast subsystem a low order approximation of $G(z)$ with transfer function*

$$\overline{G}(z) = \overline{H}(z_0)\left[zI_r - \overline{\Phi}(z_0)\right]^{-1}\overline{\Gamma}(z_0) + \overline{E}_d(z_0) \qquad (2.22)$$

where

$$\overline{E}_d(z_0) = E_d + H_2(z_0 I_{n-r} - \Phi_{22})^{-1}\Gamma_2 \qquad (2.23)$$

and $\overline{\Phi}(z)$, $\overline{\Gamma}(z)$ and $\overline{H}(z)$ are defined as in (2.21) and $0 < |z_0| \le 1$.

Two extreme cases can be considered:

(i) $z_0 = 1$; we obtain the slow singular perturbation approximation defined as follows:

$$\begin{aligned} \overline{\Phi}(1) &= \Phi_{11} + \Phi_{12}(I_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ \overline{\Gamma}(1) &= \Gamma_1 + \Phi_{12}(I_{n-r} - \Phi_{22})^{-1}\Gamma_2 \\ \overline{H}(1) &= H_1 + H_2(I_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ \overline{E}_d(1) &= E_d + H_2(I_{n-r} - \Phi_{22})^{-1}\Gamma_2\,; \end{aligned} \qquad (2.24)$$

(ii) if $z_0 \to 0$ and Φ_{22}^{-1} exists, we have

$$\begin{aligned} \overline{\Phi}(0) &= \Phi_{11} - \Phi_{12}\Phi_{22}^{-1}\Phi_{21} \\ \overline{\Gamma}(0) &= \Gamma_1 - \Phi_{12}\Phi_{22}^{-1}\Gamma_2 \\ \overline{H}(0) &= H_1 - H_2\Phi_{22}^{-1}\Phi_{21} \\ \overline{E}_d(0) &= E_d - H_2\Phi_{22}^{-1}\Gamma_2 \end{aligned} \qquad (2.25)$$

We have seen that the singular perturbation approximation method for model reduction can be developed in the time domain as well as the frequency domain. The generalized slow singular perturbation approximation when we take $\sigma_0 = 0$ ($z_0 = 1$ for the discrete-time case) will match the DC gains in the reduction. Now the question arises: If we apply this reduction technique instead of direct truncation to a balanced system, will we secure the advantages of both reduction methods? That is: can the reduction method have very good behaviour at low frequencies while it still has a very easily calculable frequency error bound? We will address these problems in the next two sections.

3 Properties of Singular Perturbation Approximation of Balanced Systems — Continuous-Time Case

Before we state the properties of the singular perturbation approximation (SPA) of internally balanced systems, we first establish some more properties of balanced systems.

Let us consider a continuous-time, linear, time-invariant, and stable system $G(s) = C(sI_n - A)^{-1}B + E$ with (A, B, C, E) being minimal and balanced with gramian $\Sigma = \mathrm{diag}\{\sigma_1, \sigma_2, \ldots, \sigma_n\}$, $\sigma_i \ge \sigma_{i+1} > 0$, $i = 1, 2, \ldots, n-1$, i.e., we have

$$A\Sigma + \Sigma A^T + BB^T = 0 \qquad (3.1a)$$

$$A^T\Sigma + \Sigma A + C^TC = 0 \qquad (3.1b)$$

Now define (using the partition (2.5))

$$\begin{aligned} \overline{A} &= A_{11} - A_{12}A_{22}^{-1}A_{21} \\ \overline{B} &= B_1 - A_{12}A_{22}^{-1}B_2 \\ \overline{C} &= C_1 - C_2A_{22}^{-1}A_{21} \\ \overline{E} &= E - C_2A_{22}^{-1}B_2. \end{aligned} \qquad (3.2)$$

Then we know from the last section that the reduced order system ($\overline{A}$, $\overline{B}$, $\overline{C}$, $\overline{E}$) is the slow singular perturbation approximation of the balanced system (A, B, C, E) if A_{22} is stable and its eigenvalues are fast. However, we will not henceforth require the property that the eigenvalues are fast. This means that the approximation may not enjoy all the time domain properties usually associated with a singular perturbation approximation. As we shall see however, it still has useful properties.

Now define the "reciprocal system" $(\widehat{A}, \widehat{B}, \widehat{C})$ of (A, B, C) by [10]:

$$\widehat{A} \triangleq A^{-1}, \quad \widehat{B} \triangleq A^{-1}B, \quad \widehat{C} \triangleq CA^{-1} \qquad (3.3)$$

assuming that A is nonsingular. We have [10]:

Lemma 3.1: *Let (A, B, C) be the minimal and internally balanced realization with gramian Σ of a linear, time-invariant and stable system. Then the reciprocal system $(\widehat{A}, \widehat{B}, \widehat{C})$ (defined as in (3.3)) is also stable and internally balanced with gramian Σ.*

Partition the system $(\widehat{A}, \widehat{B}, \widehat{C})$ and the gramian Σ conformally as

$$\widehat{A} = \begin{bmatrix} \widehat{A}_{11} & \widehat{A}_{12} \\ \widehat{A}_{21} & \widehat{A}_{22} \end{bmatrix}, \quad \widehat{B} = \begin{bmatrix} \widehat{B}_1 \\ \widehat{B}_2 \end{bmatrix}, \quad \widehat{C} = [\widehat{C}_1 \quad \widehat{C}_2], \quad \Sigma = \begin{bmatrix} \Sigma_1 & 0 \\ 0 & \Sigma_2 \end{bmatrix} \tag{3.4}$$

Then we have (by Lemma 2.1 and Lemma 2.2):

Lemma 3.2: *Let the hypothesis of Lemma 3.1 hold and the reciprocal system $(\widehat{A}, \widehat{B}, \widehat{C})$ be partitioned as in (3.4). Then the subsystem $(\widehat{A}_{ii}, \widehat{B}_i, \widehat{C}_i)$ $(i = 1, 2)$ is also internally balanced with gramian Σ_i $(i = 1, 2)$.*

Lemma 3.3: *Let the hypothesis of Lemma 3.2 hold. Then the subsystem matrix $\widehat{A}_{ii}$ $(i = 1, 2)$ is asymptotically stable if Σ_1 and Σ_2 have no common diagonal element. Further, the subsystem $(\widehat{A}_{ii}, \widehat{B}_i, \widehat{C}_i)$ $(i = 1, 2)$ is controllable and observable.*

Also, we have the following frequency error bound by Lemma 2.3:

Lemma 3.4: *Let the hypothesis of Lemma 3.2 hold. Then we have*

$$\left\| \widehat{C}(j\omega I_n - \widehat{A})^{-1}\widehat{B} - \widehat{C}_1(j\omega I_r - \widehat{A}_{11})^{-1}\widehat{B}_1 \right\|_\infty \le 2\mathrm{tr}(\Sigma_2). \tag{3.5}$$

Now if we apply the singular perturbation approximation technique to the internally balanced system (A, B, C, E) instead of the direct truncation method, what kind of properties can we expect for this reduction? To answer this question, the key is to exploit the "reciprocal system" of (A, B, C, E).

Notice from (3.3) and (3.4) and the block matrix inversion lemma [15] that

$$\overline{A} = \widehat{A}_{11}^{-1}, \qquad \overline{B} = \widehat{A}_{11}^{-1}\widehat{B}_1, \qquad \overline{C} = \widehat{C}_1\widehat{A}_{11}^{-1}, \tag{3.6}$$

i.e., the system $(\overline{A}, \overline{B}, \overline{C})$ (defined as in (3.2)) is the "reciprocal system" of $(\widehat{A}_{11}, \widehat{B}_1, \widehat{C}_1)$. Hence, we immediately obtain some properties of the singular perturbation approximation reduction method.

Lemma 3.5 [12]*: Let (A, B, C, E) be the minimal and internally balanced realization with the gramian Σ of a continuous-time, linear, time-invariant and asymptotically stable system. Partition the system conformally as in (2.5). Then the slow singular perturbation approximation $(\overline{A}, \overline{B}, \overline{C}, \overline{E})$ defined in (3.2) of the system (A, B, C, E) is also internally balanced with gramian Σ_1 (Σ_1 is defined as in (2.5)).*

Theorem 3.1: *Let the hypothesis of Lemma 3.5 hold true. Then the singular perturbation reduced order system $(\overline{A}, \overline{B}, \overline{C}, \overline{E})$ defined as in (3.2) of the system (A, B, C, E) is also asymptotically stable and controllable and observable if Σ_1 and Σ_2 (as defined in (2.5)) have no common diagonal element.*

The proof of this result is straightforward by noting Lemma 3.3 and the relation (3.6). Next, we have a main result of this paper.

Theorem 3.2: *Let the hypothesis of Lemma 3.5 hold true. Then there is a frequency error bound available for the singular perturbation approximation $(\overline{A}, \overline{B}, \overline{C}, \overline{E})$ defined in (3.2) of the stable and internally balanced system (A, B, C, E):*

$$\left\| C(j\omega I_n - A)^{-1}B + E - \overline{C}(j\omega I_r - \overline{A})^{-1}\overline{B} - \overline{E} \right\|_\infty \le 2\mathrm{tr}(\Sigma_2) \tag{3.7}$$

where Σ_2 is defined as in (3.4).

The significance of this theorem is very clear. To use the singular perturbation approximation technique (3.2) to reduce the order of the internally balanced system (A, B, C, E), it is *not* necessary that the time scale separation properties (2.9) should hold true. In fact, as long as the balanced system (A, B, C, E) has a weakly controllable and weakly observable subsystem, i.e., the sum of the singular values corresponding to this weak subsystem, $\mathrm{tr}(\Sigma_2)$, is small, then the result of Theorem 3.2 guarantees a good reduction from the sigular perturbation approximation technique in the sence that the reduction error will be over bounded by a small quantity $2\mathrm{tr}(\Sigma_2)$.

It is interesting to note that if the high order balanced system is strictly proper, i.e., $E = 0$, then in (3.2), $\overline{E} = -C_2A_{22}^{-1}B_2$. Hence if the system to be reduced is strictly proper, its singular perturbation approximation will usually be a proper but not strictly proper reduced order model. If one insists on a strictly proper singular perturbation approximation as in [8,9,12,18], one must expect a larger frequency error bound:

Corollary 3.1: *Assume the same hypotheses as Theorem 3.2, then there holds*

$$\left\| C(j\omega I_n - A)^{-1}B - \overline{C}(j\omega I_r - \overline{A})^{-1}\overline{B} \right\|_\infty \le 4\mathrm{tr}(\Sigma_2). \tag{3.8}$$

Now we have seen that if we use direct truncation on a stable and balanced system to obtain a low order approximation, we can have a very good reduction error (near zero) at very high frequencies, but not such a good one at low frequencies. If we use the singular perturbation approximation technique on a stable and balanced system to find the low order model, we have the reverse conclusion. Hence, one can imagine that a mixed use of these two reduction techniques on a stable balanced system will "average" the behaviour of both methods at high and low frequencies. We have

Theorem 3.3: *Assume that the hypothesis of Lemma 3.5 hold true. Then the techniques of direct truncation (DT) and singular perturbation approximation (SPA) can be used in a mixed way to reduce the order of a linear, time-invariant, minimal, stable, and internally balanced system. That is to say the reduction is done by several sequential steps, and for each step, either the direct truncation or the singular perturbation approximation method can be employed to reduce the order. Further, the final reduced order model is also minimal, internally balanced and stable. The frequency error bound of the reduction will remain the same as if the reduction has been done by either method in one step.*

In the next section, we will consider the discrete-time case.

4 Properties of Singular Perturbation Approximation of Balanced Systems — Discrete-Time Case

In the last section, we have shown that the singular perturbation approximation of a balanced system is fully compatible with Moore's direct truncation method in the continuous-time case. Now we want to examine if this is still true for discrete-time systems. To do so, we first establish some properties of the bilinear mapping between the complex s-plane and z-plane.

We start with a continuous-time, linear, time-invariant, minimal, and stable system with the transfer function $C(sI_n - A)^{-1}B + E$. Assume that the discrete-time, linear, time-invariant, minimal, and stable system $H(zI_n - \Phi)^{-1}\Gamma + E_d$ is obtained from the continuous-time system *via* the following bilinear mapping

$$s = \frac{z-1}{z+1} \quad (\text{inverse}: z = \frac{1+s}{1-s}) \tag{4.1}$$

which maps the left half complex s-plane, $Re(s) \le 0$ onto the unit circle $|z| \le 1$ in the z-plane; then we have the relations

$$\begin{aligned} A &= (\Phi + I_n)^{-1}(\Phi - I_n) \\ B &= \sqrt{2}(\Phi + I_n)^{-1}\Gamma \\ C &= \sqrt{2}H(\Phi + I_n)^{-1} \\ E &= E_d - H(\Phi + I_n)^{-1}\Gamma \end{aligned} \tag{4.2}$$

or in another form

$$C(sI_n - A)^{-1}B + E \underset{z=\frac{1+s}{1-s}}{\overset{s=\frac{z-1}{z+1}}{\rightleftarrows}} H(zI_n - \Phi)^{-1}\Gamma + E_d \tag{4.3}$$

Then we obtain

Lemma 4.1 [16,17]*: The bilinear mapping (4.1) preserves the internally balanced property of the linear, time-invariant system, in the sense that if the stable continuous-time system (A, B, C, E) is internally balanced with gramian Σ, then the discrete-time system (Φ, Γ, H, E_d) obtained by the above bilinear mapping (4.1) and (4.2) is also internally balanced with the same gramian Σ, and vice versa.*

Now partition the balanced system (Φ, Γ, H, E_d) conformally as in (2.19). Define

$$\begin{aligned} \overline{\Phi} &= \Phi_{11} + \Phi_{12}(I_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ \overline{\Gamma} &= \Gamma_1 + \Phi_{12}(I_{n-r} - \Phi_{22})^{-1}\Gamma_2 \\ \overline{H} &= H_1 + H_2(I_{n-r} - \Phi_{22})^{-1}\Phi_{21} \\ \overline{E}_d &= E_d + H_2(I_{n-r} - \Phi_{22})^{-1}\Gamma_2 \ ; \end{aligned} \tag{4.4}$$

Then from Section 2, we know that the low order system ($\overline{\Phi}$, $\overline{\Gamma}$, $\overline{H}$, $\overline{E}_d$) is the slow singular perturbation approximation of the balanced system (Φ, Γ, H, E_d) if Φ_{22} is fast and stable. Once more, we can afford to drop the assumption about fast eigenvalues, and simply require stability.

Further, we have as a new result:

Theorem 4.1: *The bilinear mapping (4.1) and (4.2) preserves the slow singular perturbation approximation, in the sense that if the linear, time-invariant, and stable continuous-time system (A, B, C, E) and the linear, time-invariant, and stable discrete-time system (Φ, Γ, H, E_d) are linked by the bilinear mapping (4.1) and (4.2), then their slow singular perturbation approximations $(\overline{A}, \overline{B}, \overline{C}, \overline{E})$ defined as in (3.2) and $(\overline{\Phi}, \overline{\Gamma}, \overline{H}, \overline{E}_d)$ defined* as in (4.4) are also linked by the same bilinear mapping, i.e.,

$$\overline{C}(sI_r-\overline{A})^{-1}\overline{B}+\overline{E} \underset{z=\frac{1+s}{1-s}}{\overset{s=\frac{z-1}{z+1}}{\rightleftarrows}} \overline{H}(zI_r-\overline{\Phi})^{-1}\overline{\Gamma}+\overline{E}_d. \qquad (4.5)$$

and in particular we have the relations

$$\begin{aligned} \overline{A} &= (\overline{\Phi}+I_r)^{-1}(\overline{\Phi}-I_r) \\ \overline{B} &= \sqrt{2}(\overline{\Phi}+I_r)^{-1}\overline{\Gamma} \\ \overline{C} &= \sqrt{2}\,\overline{H}(\overline{\Phi}+I_r)^{-1} \\ \overline{E} &= \overline{E}_d-\overline{H}(\overline{\Phi}+I_r)^{-1}\overline{\Gamma} \end{aligned} \qquad (4.6)$$

From the above two results, we immediately have

Theorem 4.2: *Assume that the minimal realization of a discrete-time, linear, time-invariant system, (Φ, Γ, H, E_d) is asymptotically stable and internally balanced with the gramian Σ; then its slow singular perturbation approximation, viz., the reduced order system $(\overline{\Phi}, \overline{\Gamma}, \overline{H}, \overline{E}_d)$ defined as in (4.4), is also minimal, internally balanced, asymptotically stable if Σ_1 and Σ_2 have no diagonal element in common, and controllable and observable.*

Certainly, we also have

Theorem 4.3: *Assume the same hypothesis as in Theorem 4.2; then there is a frequency error bound available for the singular perturbation reduction of the balanced system*

$$\left\|H(e^{j\theta}I_n-\Phi)^{-1}\Gamma+E_d-\overline{H}(e^{j\theta}I_r-\overline{\Phi})^{-1}\overline{\Gamma}-\overline{E}_d\right\|_\infty \le 2\mathrm{tr}(\Sigma_2).$$

Note that the same claim of this theorem has appeared in [16] and [17]; however, the proof technique is different.

As a final remark, it should be pointed out that in the discrete-time case, directly truncating a balanced system to reduce the system order is *not* fully compatible with the singular perturbation approximation of the balanced system. The problem is that the reduced order system obtained by direct truncation of a balanced system is not balanced any more. Hence, we cannot, in contrast to the continuous-time case (Theorem 3.3), mix freely the two reduction techniques into one reduction procedure. However, we can state:

Theorem 4.4: *Assume the same hypothesis as in Theorem 4.2. Then the techniques of the direct truncation and the slow singular perturbation approximation can be used in the following way to reduce the order of a discrete-time, linear time-invariant, minimal, stable, and internally balanced system: Assume that the reduction is done by two sequential steps. For the first step, the slow singular perturbation approximation method is used . In the second step, the direct truncation technique is employed to reduce the order. Then the final reduced order model is also minimal, stable (but not internally balanced). The frequency error bound of the reduction will be the same as if the reduction had been done by either technique in one step.*

As for continuous-time systems, we hope this mixed reduction procedure will display behaviour between those of the two reduction techniques from which it is composed.

Figure 1 shows the relations among the reduction methods in this paper.

In the next section, some examples are used to illustrate the reduction methods proposed in this paper.

5 Examples

5.1 Example 1

To illustrate the two different approaches (and their mixture) in the model order reduction problem, consider the continuous-time, linear, time-invariant and stable system described by the transfer function

$$G(s) = \frac{s+4}{(s+1)(s+3)(s+5)(s+10)} \qquad (5.1)$$

which has appeared in many references such as [1], [12] and [18]. The system can be realized in the following internally balanced format [1], $G(s) = C(sI_4-A)^{-1}B+E$, where

$$A = \begin{bmatrix} -0.43781 & 1.1685 & 0.41426 & 0.05098 \\ -1.1685 & -3.1353 & -2.8352 & -0.32885 \\ 0.41426 & 2.8352 & -12.4753 & -3.2492 \\ -0.05098 & -0.32885 & 3.2492 & -2.9516 \end{bmatrix}, \quad B = \begin{bmatrix} -0.11814 \\ -0.1307 \\ 0.05634 \\ -0.006875 \end{bmatrix} \qquad (5.2)$$

$$C = [-0.11814 \quad 0.1307 \quad 0.05634 \quad -0.006875], \quad E = 0, \qquad (5.3)$$

and the balanced gramian matrix Σ is given by

$$\Sigma = \mathrm{diag}\{1.5938\times10^{-2},\ 2.7243\times10^{-3},\ 1.272\times10^{-4},\ 8.006\times10^{-6}\}. \quad (5.4)$$

Now, we want to use Moore's direct truncation, the singular perturbation approximation and a mixture as order reduction techniques to find a second order system approximating the above balanced system. We have four different cases:

Case I (DT): Moore's direct truncation reduction method. Partition the system conformally and then eliminate the weakly controllable and observable subsystem; we obtain the reduced order system as

$$A_{11} = \begin{bmatrix} -0.43781 & 1.1685 \\ -1.1685 & -3.1353 \end{bmatrix}, \quad B_1 = \begin{bmatrix} -0.11814 \\ -0.1307 \end{bmatrix}$$

$$C_1 = [-0.11814 \quad 0.1307], \quad E = 0$$

$$G_r(s) = C_1(sI_2-A_{11})^{-1}B_1+E.$$

Note that the reduced order system remains internally balanced with gramian

$$\Sigma_1 = \mathrm{diag}\{1.5938\times10^{-2},\ 2.7243\times10^{-3}\},$$

and is controllable and observable, and is also asymptotically stable with matrix A_{11} having the eigenvalues $\lambda\{A_{11}\} = \{-1.1129,\ -2.4601\}$.

Case II (SPA): The slow singular perturbation approximation method. Using (3.2), we obtain the reduced order system as

$$\overline{A} = \begin{bmatrix} -0.42491 & 1.2565 \\ -1.2565 & -3.7354 \end{bmatrix}, \quad \overline{B} = \begin{bmatrix} -0.11638 \\ -0.14266 \end{bmatrix}$$

$$\overline{C} = [-0.11638 \quad 0.14266], \quad \overline{E} = 2.384\times10^{-4}$$

$$G_r(s) = \overline{C}(sI_2-\overline{A})^{-1}\overline{B}+\overline{E}.$$

Again, the reduced order system is balanced with gramian Σ_1, controllable and observable, and also asymptotically stable with $\overline{A}$ having the eigenvalues $\lambda\{\overline{A}\} = \{-1.0026,\ -3.1578\}$.

Case III (DT/SPA): The mixture of Moore's direct truncation and singular perturbation approximation method. In this case, we first use the direct truncation to obtain a third order approximation, then we use the singular perturbation approximation to this third order system to obtain the second order approximation as

$$A_{m1} = \begin{bmatrix} -0.42405 & 1.2626 \\ -1.2626 & -3.7796 \end{bmatrix}, \quad B_{m1} = \begin{bmatrix} -0.11626 \\ -0.1435 \end{bmatrix}$$

$$C_{m1} = [-0.11626 \quad 0.1435], \quad E_{m1} = 2.5441\times10^{-4}$$

$$G_r(s) = C_{m1}(sI_2-A_{m1})^{-1}B_{m1}+E_{m1}.$$

This reduced order system is balanced with gramian Σ_1, controllable and observable, and also asymptotically stable with A_{m1} having the eigenvalues $\lambda\{A_{m1}\} = \{-0.99696,\ -3.2067\}$.

Case IV (SPA/DT): The mixture of the singular perturbation approximation and Moore's direct truncation reduction method. In this case, we first employ the singular perturbation approximation method to find a third order reduction, then use the direct truncation to obtain the second order approximation as

$$A_{m2} = \begin{bmatrix} -0.43869 & 1.1628 \\ -1.1628 & -3.0986 \end{bmatrix}, \quad B_{m2} = \begin{bmatrix} -0.11825 \\ -0.12993 \end{bmatrix}$$

$$C_{m2} = [-0.11825 \quad 0.12993], \quad E_{m2} = -1.6012\times10^{-5}$$

$$G_r(s) = C_{m2}(sI_2-A_{m2})^{-1}B_{m2}+E_{m2}.$$

Again, this reduced order system is internally balanced with gramian Σ_1, controllable and observable, and also asymptotically stable with A_{m2} having the eigenvalues $\lambda\{A_{m2}\} = \{-1.1231,\ -2.4142\}$.

Now we consider the frequency errors for the above reductions. The Bode plot of the high order system $G(s)$ and the reduced order systems of the above four cases are shown in Figure 2 and Figure 3. Figure 4 depicted the frequency error $\overline{\sigma}\{G(j\omega)-G_r(j\omega)\}$ where $G_r(s)$ is obtained from the above four cases. It is clear that the singular perturbation approximation method has very good reduction errors at low frequencies (when $\omega \le 2$ rads/sec). And the frequency error is smaller than the frequency error of the direct truncation method until around $\omega = 15$ rads/sec. Now looking again at the Bode plot of the system Figure 2, we see that this system is a typical low-pass filter. When $\omega = 15$, the magnitude of the system has decayed about -40dB from its value in the pass band. Hence, $0 \le \omega \le 15$ rads/sec can be regarded as the working frequency range for this system, and within this range, the singular perturbation approximation method gives a better reduction than the direct truncation method. Figure 5 shows the relative frequency errors of the reductions, $\overline{\sigma}\{G(j\omega)-G_r(j\omega)\}/\overline{\sigma}\{G(j\omega)\}$.

For this system, we can consider the peak frequency error of the reductions, $\left\|G(j\omega)-G_r(j\omega)\right\|_\infty$; this criterion still favours the singular perturbation approximation method, as shown in Table 1. Note that the theoretical error bound for all the above reductions is $2\mathrm{tr}(\Sigma_2) = 2\times(1.272\times10^{-4}+8.006\times10^{-6}) = 2.7042\times10^{-4}$. It is also interesting to compare the exact errors at DC of the four reduction method, as shown in Table 1 as well. In fact, for Cases II, III and IV, one can write down directly the exact errors at DC, since the singular perturbation approximation gives no error at DC, and the direct truncation reduction of order 1 gives the exact error at DC as $2\sigma_4$ and $2\sigma_3$ respectively.

5.2 Example 2

Now we consider a discrete-time system. For comparison purposes, we

Table 1 Frequency Errors of the Reduction (Example 1) ($\times 10^{-4}$)

	DT	SPA	DT/SPA	SPA/DT	Theo. Bound
$\|G(j\omega) - G_r(j\omega)\|_\infty$	2.4802	2.3693	2.5284	2.6402	2.7042
Exact Error at DC	2.384	0.0	0.16012	2.5441	—

simply use the bilinear mapping (4.1) to discretize the system in Example 1, (5.1). We have using the relation (4.2) together with (5.2) and (5.3) to deduce that

$$G(z) = H(zI_4 - \Phi)^{-1}\Gamma + E_d$$

where

$$\Phi = \begin{bmatrix} -0.1372 & -0.30259 & 0.02607 & -0.01093 \\ 0.30259 & 0.65545 & 0.07482 & -0.02894 \\ 0.02607 & -0.07482 & 0.89126 & 0.09597 \\ 0.01093 & -0.02894 & -0.09597 & 0.57533 \end{bmatrix}, \Gamma = \begin{bmatrix} -0.12405 \\ -9.688 \times 10^{-3} \\ 6.1354 \times 10^{-5} \\ -3.26 \times 10^{-6} \end{bmatrix}$$

$$H = [-0.12405 \quad -9.6875 \times 10^{-3} \quad 6.1354 \times 10^{-5} \quad -3.2595 \times 10^{-6}]$$

$$E_d = 9.4697 \times 10^{-3}$$

Now, from the result of Lemma 4.1, we know that this realization is also (discrete-time) internally balanced with the same gramian Σ as shown in (5.4).

As in the continuous-time case, we now use the direct truncation method, the singular perturbation approximation method, and their mixture to obtain a second order approximation of the above system. We have

Case I (DT): The direct truncation of the balanced system. We obtain

$$\Phi_{11} = \begin{bmatrix} -0.1372 & -0.30259 \\ 0.30259 & 0.65545 \end{bmatrix}, \quad \Gamma_1 = \begin{bmatrix} -0.12405 \\ -9.6875 \times 10^{-3} \end{bmatrix}$$

$$H_1 = [-0.12405 \quad 9.6875 \times 10^{-3}], \quad E_d = 9.4697 \times 10^{-3}$$

$$G_r(z) = H_1(zI - \Phi_{11})^{-1}\Gamma_1 + E_d$$

Notice now that this reduced order system is *not* balanced any more. However, it is still controllable and observable and asymptotically stable with Φ_{11} having the eigenvalues $\lambda\{\Phi_{11}\} = \{3.163 \times 10^{-3},\ 0.51509\}$.

Case II (SPA): The slow singular perturbation approximation method. Using the reduction method defined in (4.4), we obtain

$$\overline{\Phi} = \begin{bmatrix} -0.13124 & -0.31964 \\ 0.31964 & 0.60667 \end{bmatrix}, \quad \overline{\Gamma} = \begin{bmatrix} -0.12404 \\ -9.6494 \times 10^{-3} \end{bmatrix}$$

$$\overline{H} = [-0.12404 \quad 9.6494 \times 10{-3}], \quad \overline{E}_d = 9.4697 \times 10^{-3}$$

$$G_r(z) = \overline{H}(zI - \overline{\Phi})^{-1}\overline{\Gamma} + \overline{E}_d$$

Now, this reduced order system is internally balanced with the gramian $\Sigma_1 = \text{diag}\{1.5938 \times 10^{-2},\ 2.7243 \times 10^{-3}\}$, controllable and observable, and asymptotically stable with $\overline{\Phi}$ having the eigenvalues $\lambda\{\overline{\Phi}\} = \{5.3446 \times 10^{-2},\ 0.42199\}$.

Case III (SPA/DT): The mixture of the singular perturbation approximation method and the direct truncation approximation (Theorem 4.4). In this case, we first reduce the system to a third order one by the singular perturbation approximation, then truncate directly this third order system to obtain the reduced order system as

$$\Phi_m = \begin{bmatrix} -0.13748 & -0.30184 \\ 0.30184 & 0.65742 \end{bmatrix}, \quad \Gamma_m = \begin{bmatrix} -0.12405 \\ -9.6872 \times 10^{-3} \end{bmatrix}$$

$$H_m = [-0.12405 \quad 9.6872 \times 10^{-3}], \quad E_{dm} = 9.4697 \times 10^{-3}$$

$$G_r(z) = H_m(zI - \Phi_m)^{-1}\Gamma_m + E_{dm}$$

Now, again, this reduced order system is *not* internally balanced. But it is controllable and observable, and asymptotically stable with Φ_m having the eigenvalues $\lambda\{\Phi_m\} = \{1.3957 \times 10^{-3},\ 0.51855\}$.

Consider the frequency errors for the above model reductions. The frequency errors $\overline{\sigma}\{G(e^{j\theta}) - G_r(e^{j\theta})\}$ are depicted in Figure 6 where the $G_r(z)$ are obtained from the above three cases. This figure shows clearly that the singular perturbation reduction method has much smaller reduction errors at low frequencies. The relative frequency errors $\overline{\sigma}\{G(e^{j\theta}) - G_r(e^{j\theta})\}/\overline{\sigma}\{G(e^{j\theta})\}$ for the above reduction are shown in Figure 7.

Table 2 Frequency Errors of the Reduction (Example 2) ($\times 10^{-4}$)

	DT	SPA	SPA/DT	Theo. Bound
$\|G(e^{j\theta}) - G_r(e^{j\theta})\|_\infty$	2.2602	2.4803	2.3552	2.7042
Exact Error at DC	2.2602	0.0	2.3553	—

The theoretical upper bound for the L_∞-norm frequency error of the above reductions is again $2tr(\Sigma_2) = 2.7024 \times 10^{-4}$. For comparison, we list the L_∞-norm errors actually reached by the above reductions in Table 2. We also can compare the reduction errors at DC (i.e., $z = 1$) for the three reduction methods. However, we cannot write down the exact error at DC for Case III now as in the continuous-time case, since, for discrete-time systems, the reduction error *bound* for the direct truncation of a balanced system is not tight any more, even when the order reduction is 1, see, e.g., [16].

6 Conclusions

In this paper, we have shown that direct truncation reduction and the slow singular perturbation approximation of a stable internally balanced continuous-time system are two fully compatible model order reduction techniques, in the sense that both methods yield a minimal, stable, and balanced reduced order system with the same L_∞-norm frequency error bound on the reduction. We have also shown that though the upper bound for both methods is the same, the actual frequency errors of these two reduction methods are quite different. The direct truncation reduction tends to have smaller errors at high frequencies and larger errors at low frequencies while the singular perturbation approximation will have larger errors at high frequencies and smaller errors at low frequencies, while directly matching the DC gain of the reduced order system with the DC gain of the original system.

We have also established that a certain bilinear mapping not only preserves the balanced structure between the continuous-time system and the discrete-time system, but also preserves the singular perturbation approximation structure between the reduced order continuous-time system and the reduced order discrete-time system. Hence, the results on the singular perturbation approximation of the continuous-time, stable and balanced system can be easily extended to the discrete-time case. However, it should be pointed out that in the discrete-time case, the direct truncation reduction method is *not* fully compatible with the singular perturbation reduction method in the sense that the former method gives a stable, minimal, but not balanced reduced order system.

Finally, we mention that the above two model order reduction techniques can be used in a mixed way in the order reduction procedure of a balanced system (certain restrictions must be imposed in the discrete-time case).

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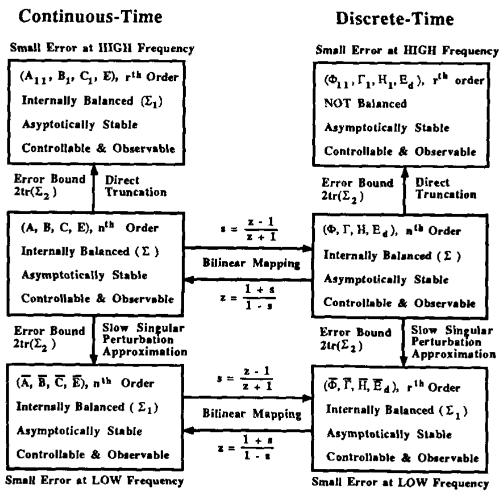

Fig.1 Summary of the Model Reduction Methods for the Balanced System

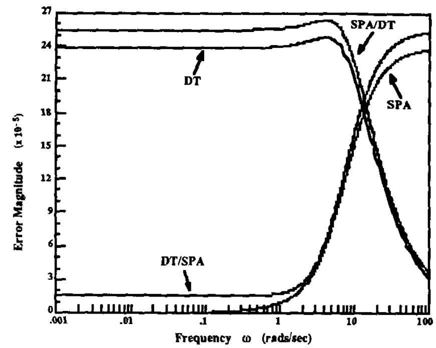

Fig.4 Frequency Errors of the Reduction (Continuous-Time)

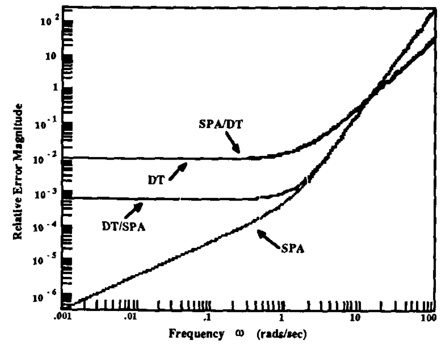

Fig.5 Relative Frequency Errors of the Reduction (Continuous-Time)

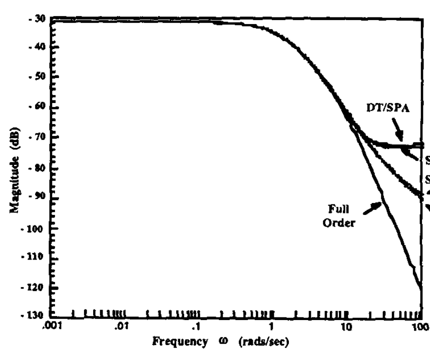

Fig.2 Bode Plot (Magnitude) of the Systems

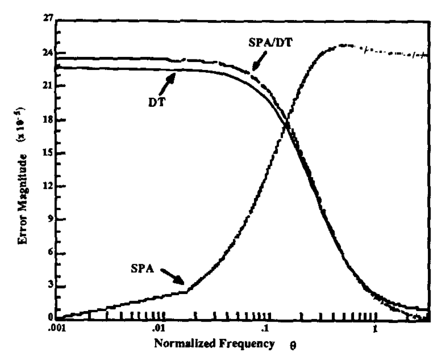

Fig.6 Frequency Errors of the Reduction (Discrete-Time)

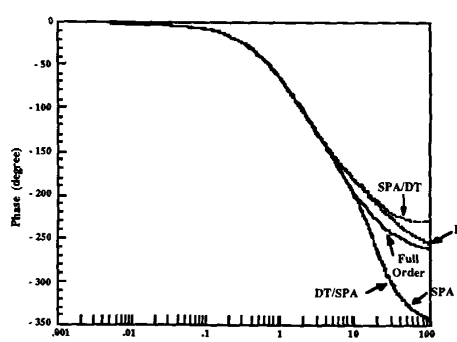

Fig.3 Bode Plot (Phase) of the Systems

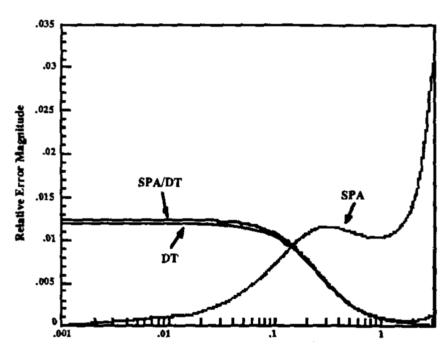

Fig.7 Relative Frequency Errors of the Reduction (Discrete-Time)