

2007

Validation and Verification of Aircraft Control Software for Control Improvement

Thien-Anh Pham
San Jose State University

Follow this and additional works at: https://scholarworks.sjsu.edu/etd_projects

Part of the [Computer Sciences Commons](#)

Recommended Citation

Pham, Thien-Anh, "Validation and Verification of Aircraft Control Software for Control Improvement" (2007). *Master's Projects*. 130.
https://scholarworks.sjsu.edu/etd_projects/130

This Master's Project is brought to you for free and open access by the Master's Theses and Graduate Research at SJSU ScholarWorks. It has been accepted for inclusion in Master's Projects by an authorized administrator of SJSU ScholarWorks. For more information, please contact scholarworks@sjsu.edu.

CS 298 Report

Validation and Verification of Aircraft Control Software for Control Improvement

Thien-Anh Pham (thienanhpham@hotmail.com)

Advisor: Chris Tseng (tseng@cs.sjsu.edu)

5/10/2007

Abstract

Validation and Verification are important processes used to ensure software safety and reliability. The Cooper-Harper Aircraft Handling Qualities Rating is one of the techniques developed and used by NASA researchers to verify and validate control systems for aircrafts. Using the Validation and Verification result of controller software to improve controller's performance will be one of the main objectives of this process. Real user feedback will be used to tune PI controller in order for it to perform better. The Cooper-Harper Aircraft Handling Qualities Rating can be used to justify the performance of the improved system.

Table of contents

Abstract	1
Table of contents	2
1. Introduction	3
1.1. Flight Control System	3
1.2. Flight Controllers.....	5
1.2.1. Classical Controller	5
1.2.2. Adaptive Flight Controller	6
1.2.3. Neural Network Adaptive Controller.....	7
1.3. Handling Quality	8
1.3.1. Cooper-Harper Aircraft Handling Qualities Rating	8
2. Validation & Verification (V&V) of Adaptive Control Software	9
2.1. Overview	9
2.2. V&V of safety-critical Software	10
2.3. Issues and Methods in V&V of adaptive systems	12
2.3.1. Issues	12
2.3.2. Design and analysis.....	13
3. Validation with Fuzzy Cooper-Harper Rules	14
3.1. Cooper-Harper Rating Rules	14
3.2. Fuzzy rule-based system.....	19
3.3. Fuzzy Cooper-Harper rating system.....	20
3.4. Validation of an F-14 Longitudinal Control System	22
4. Adaptive PI controller with Cooper-Harper Feedback	30
4.1. Fixed value F14 PI controller	30
4.2. Adaptive PI controller with Cooper-Harper Feedback VS. Adaptive PI Controller	30
4.3. Results	33
5. Conclusion.....	35
References	36

1. Introduction

Ever since the beginning of our existence on Earth, humans have always dreamed to fly like a bird. This dream came true in Dec 18, 1903 when the first airplane test flight was successful. Flight control system at that time was very primitive, but it has evolved a lot over time with new technology. I will explain more about flight control system technologies in this section.

Most hi-tech flight control systems are controlled by software nowadays. It is important to have processes to ensure software safety and reliability. Validation and Verification are the two processes to do this work. They become even more important for safety-critical software such as aircraft control software. The Cooper-Harper Aircraft Handling Qualities Rating is one of the techniques developed and used by NASA researchers to verify and validate control systems for aircrafts. Section two will explain about Validation and Verification processes for adaptive control software. Section three will explain how the Cooper Harper Aircraft Handling Qualities Rating is used to verify and validate control software.

The main objective of this research is to use the real Validation and Verification result of controller software to improve its performance. I use standard adaptive methodologies from the literature to design and implement an adaptive tuning software to improve the performance of the PI controller in F-14 aircrafts. This software is able to use the Cooper-Harper Air Aircraft Handling Qualities Rating value from the fixed controller in F-14 system to dynamically adjust the proportional gain value adaptively.

The innovation and challenge in this project is to use the Validation and Verification results as feedbacks to fine tune the controller software. The Cooper-Harper Aircraft Handling Qualities Rating results will be captured, and then passed to the adaptive tuning software to compute the correct amount of control value needed for the controller. With the new control value, the controller software will adapt more quickly and accurately to changes in the operating environment. In other words, the adaptive tuning control software uses the user feedback, to adjust its control value adaptively, whereas the fixed controller software uses system sensors. Section four will further explain how this method is implemented on the PI controller in F-14 aircrafts.

1.1. *Flight Control System*

In the early 20s, designer replaced the mechanical linkage with electrical wire to reduce system weight and increase reliability. Nowadays, the aircraft control system is a collection of thousands of integrated circuit which help aircraft perform at a much better rate than it did in the early days.

Any flight control system is required to have cockpit controls, flight control surfaces, linkage between cockpit control and flight control surfaces, and the actual mechanisms to control the aircraft. We will explain about the underlying mechanisms of flight control system in this section because it is the interest of this paper.

A basic cockpit control contains three components described below.

- “Control yoke for roll which moves the ailerons
- Control column for pitch which moves the elevators
- Rudder pedals for yaw which moves the rudder” [31]

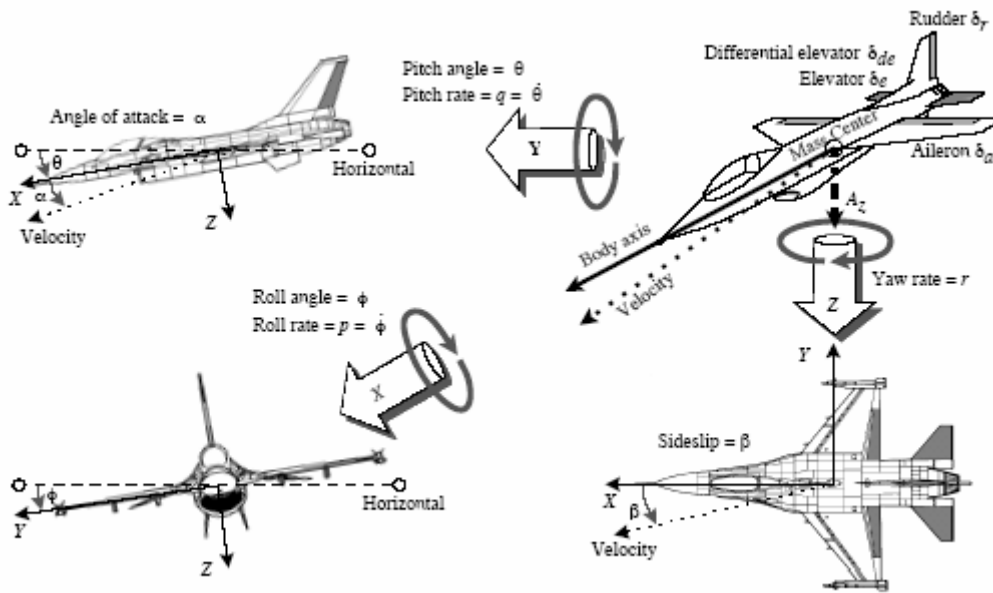


Figure 1.1: Aircraft axes of rotation [21]

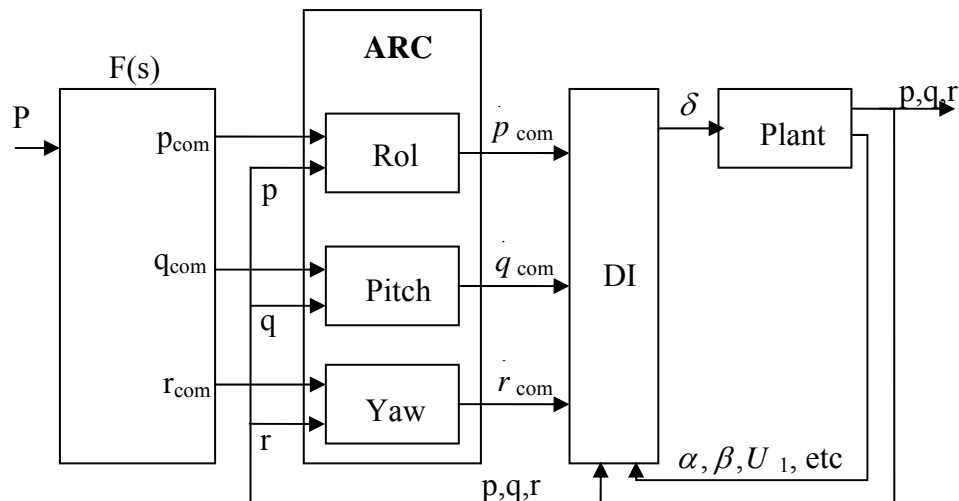


Figure 1.2: ARC implementation [8]

An example of a modern flight control system is the Adaptive Robust Control (ARC) shown in Figure 1.2. Pilot inputs will be converted to p_{com} , q_{com} , and r_{com} by the $F(s)$. The output of $F(s)$ together with aircraft current situation (p , q , r) will be passed to ARC to compute new values of control (P_{com} , q_{com} , r_{comp}). These new values P_{com} , q_{com} , r_{comp} will enter the DI (dynamic inversion) component. The DI inner loop will process these new values and compute an output vector δ (rudder, elevator, aileron). This vector will be passed to the plant. This plan will fly the aircraft and output new sensor values p , q , and r . These values will be passed back to the ARC as input for the next iteration.

1.2. Flight Controllers

1.2.1. Classical Controller

There are many classical controllers, but the Proportional-Integral-Derivative Controller (PID Controller) is the most widely used. Over 85% of all dynamic controllers are of the PID variety. [27]

A PID controller has 3 components: the Proportional component, Integral component, and Derivative component. Each component has its own purpose because each one contains a different algorithm. Sometimes one or two algorithms are left out because they are not needed in the control design. It is possible to have a PI, PD or just a P controller, but it is rare to have an ID controller

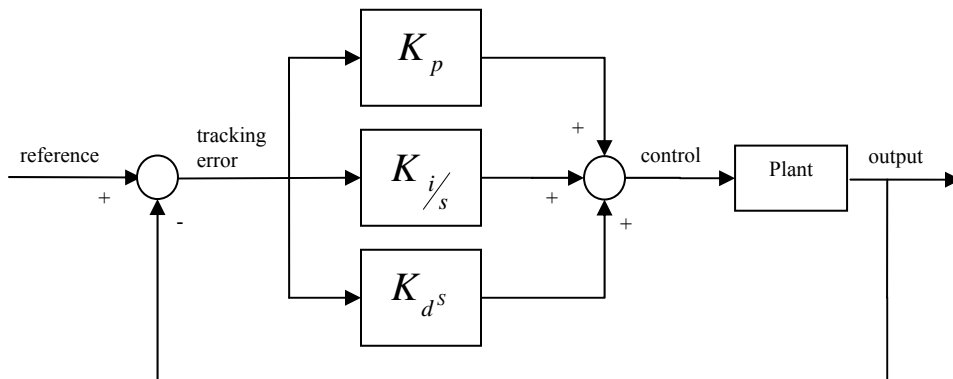


Figure 1.3: PID Controlled System [27]

Tracking error is computed by the difference of the reference and previous output value. This tracking error is passed into three different components K_p , $K_{i/s}$, and K_d^s . K_p indicates that the control in this component is proportional to the error. $K_{i/s}$ indicates that the control is an integral control. K_d^s indicates that this control is

a derivative control. Each component works independently of others to produce some values. The sum of these values will be the control for the plant. This plan will perform its task, and then yield new sensor values (output) for the next iteration.

A specific application is the ARC implementation explained in figure 1.2

1.2.2. Adaptive Flight Controller

Adaptive systems are systems “whose function evolves over time, as they improve their performance through learning.” And, “If learning and adaptation are allowed to occur after the control system is deployed, the system is called online adaptive system.” [28]. An Adaptive Flight Controller is a flight controller that can learn about changes in aircraft control, and adapt to those changes in order to keep the aircraft stable.

Figure 1.4 shows an adaptive controlled system with a PI controller. K_p and K_i/s are replaced by a Fuzzy Tuner for K_p and a Fuzzy Estimator for K_i , respectively. The two new components, using fuzzy logic tuning, are responsible for computing a new proportional control value u_p and integral control value u_i . The sum u of u_p and u_i will be passed to plant, and this plant will yield new sensor output. The difference of this output and the reference is the tracking error. This tracking error will be passed back to both Fuzzy Tuner for K_p and Fuzzy Estimator for K_i to continue with the next iteration.

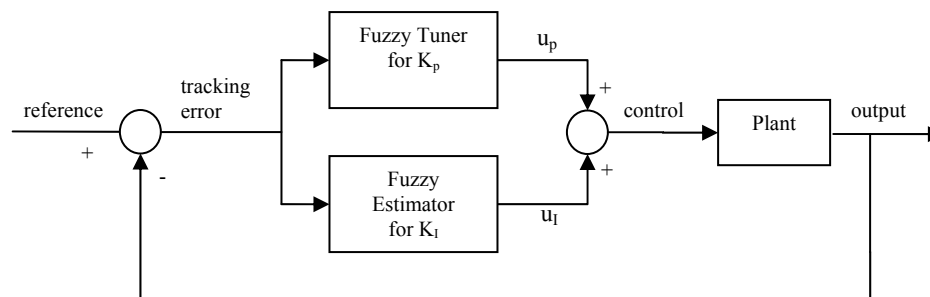


Figure 1.4: PI Controller with fuzzy tuning [15]

Another Flight Adaptive system is the Flight Control System with Neural-Network Controller. This system is also known as the Intelligent Flight Control System (IFCS) developed by the National Aeronautics and Space Administration (NASA).

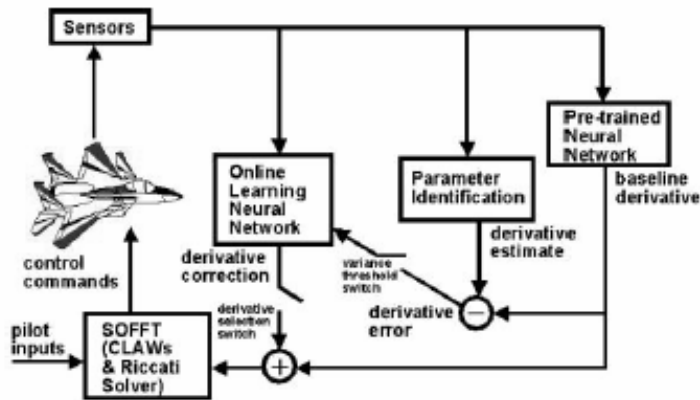


Figure 1.5: Flight Control System with Neural-Network Controller [26]

Figure 1.5 shows that sensor data from the aircraft such as altitude and airspeed are passed to three components: the Pre-Trained Neural Network (PTNN), Parameter Identification (PID) and Online Learning Neural Network (OLNN). The PTNN contains baseline derivative data is just a lookup table with data which is collected from the lab. Result output of the PTNN flows to the SOFFT (Stochastic Optimal Feed-Forward & Feedback Technology) controller. The SOFFT controller takes pilot inputs and computes a new command to feed back to the aircraft. It uses the stability and control derivatives data (PTNN output) to calculate a plant model that controls the aircraft so it can perform as desired.

For an online adaptive configuration, both switches on Figure 1.5 are closed. Data from sensor flows through both PID and OLNN components. Output from the PID and OLNN will be compared to output from the PTNN before passing to the SOFFT controller. The derivative estimate from the PID are used to train the OLNN, and OLNN is used to correct data produced by the PTNN.

1.2.3. Neural Network Adaptive Controller

Online Learning Neural Network is also referred to as Dynamic Cell Structure (DCS) neural network. “As an online storage function approximator, the DCS network is expected to approximate the differences between the parameter estimation of the stability and control derivatives by a PID and the baseline derivatives generated by the PTNN” [26]. The OLNN will update the aircraft when there are changes in control or when there are model inaccuracies. These model updates will happen in real-time during flights. According to Liu, “this system must be capable of providing aerodynamic derivatives to the aircraft controller at least 10 times per second”.

OLNN has two modes of operation: Learning and Non-Learning. During the Learning state, the difference between the derivative estimation PID and the baseline derivative from PTNN is used to train the network. During the Non-Learning state, only the baseline derivative value from PTNN is used. The Non-

Learning state is activated when the derivative estimation from the PID becomes unusable or inaccurate.

According to Liu, there are two conditions of the system.

- “We are confident in PID estimates –
There is no need to activate DCS.
Controller uses the derivatives generated by baseline network.
- We are not confident in PID estimates –
DCS must be activated for adaptation.
Controller uses the derivatives generated by PTNN plus the correction generated by DCS.” [26]

“We can be confident about the performance of Neural Network Controller in the first condition because system is running within the safe region. If abnormal events happened (when the PID output can not be trusted) then appropriate action will be taken. However under critical condition, we still can not guarantee safe behavior with an OLNN. Therefore verification and validation techniques are needed to ensure the system safety and reliability.” [26]

1.3. Handling Quality

In most flight control systems, performance assessment is carried out in terms of handling qualities. Handling qualities may be defined as those dynamic and static properties of a vehicle that permit the pilot to fully exploit its performance in a variety of missions and roles. Traditionally, handling quality is measured using the Cooper-Harper rating and done subjectively by the human pilot. In this work, we formulated the rules of the Cooper-Harper rating scheme as fuzzy rules with performance, control, and compensation as the antecedents, and pilot rating as the consequent. Appropriate direct measurements on the controller are related to the fuzzy Cooper-Harper rating system. A stability measurement like the rate of change of the cost function can be used as an indicator if the aircraft is under control. The tracking error is a good measurement for performance needed in the rating scheme. Finally, the change of the control amount or the output of a confidence tool can be used as an indication of pilot compensation. We use a number of known aircraft flight scenarios with known pilot ratings to calibrate our fuzzy membership functions. These include normal flight conditions and situations in which partial or complete failure of tail, aileron, engine, or throttle occurs.

1.3.1. Cooper-Harper Aircraft Handling Qualities Rating

The Cooper-Harper Aircraft Handling Qualities Rating is widely used since its introduction. Figure 1.6 depicts the various conditions used for the pilot to rate the

aircraft handling qualities. The rating system takes on a couple of factors and deduces the aircraft handling qualities in aircraft characteristics and pilot rating columns in Figure 1.6. The ten levels from “Excellent, Good, Fair,... Major Deficiencies”, as observed by the pilot, for various cases are summarized in the column of demand on the pilot in selected task or required operation in Figure 1.6. There three input factors that lead to this output column in the rating system. Pilot compensation, performance, and aircraft control status are the inputs that lead to Cooper-Harper rating scheme.

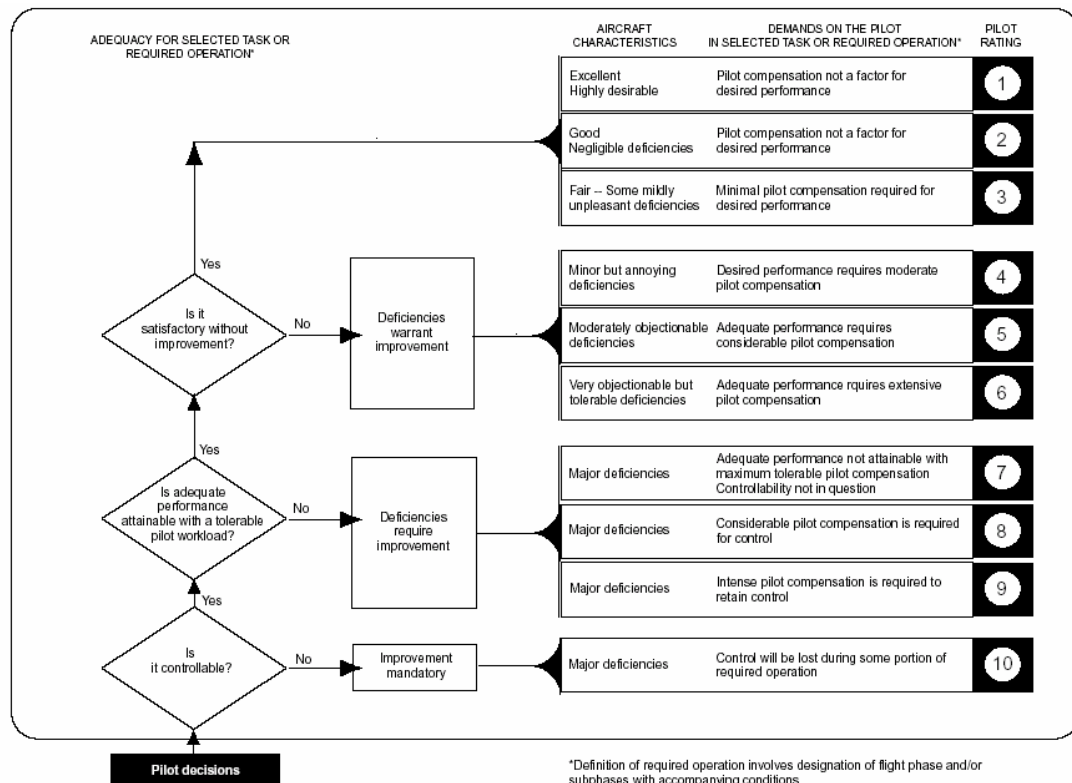


Figure 1.6 Cooper-Harper Aircraft handling Qualities Rating [36]

2. Validation & Verification (V&V) of Adaptive Control Software

2.1. Overview

Software Validation and Verification is a process to ensure software safety and reliability. Sommerville simply explains about the terms “validation” and “verification” in his book:

- “Validation: Are we building the right product?”

- Verification: Are we building the product right?” [29]

In other words, validation is a process to make sure the software was built based on the needs of users. In this process, users should have frequent updates after each phase of the project. Meeting with users frequently is a good way to ensure that the software product is consistent with users’ requirements. Another validation activity would be checking the specification with the design. Both users and developers should review the specification to make sure there is no misunderstanding between the developers’ interpretation and users’ interpretation.

Verification is a process to make sure the software product meets its specifications. Activities in the verification process include but is not limited to mathematical analysis, functional testing, module testing, integration testing, etc. Verification should be performed at each phase of the project to ensure the quality of the product. For example, each module should be tested individually, and when they are integrated together, the complete system should be tested as well.

“The goal of the V&V process is to establish confidence that the software system is ‘fit for purpose’. This does not mean that the program must be completely free of defects. Rather, it means that the system must be good enough for its intended use. The level of required confidence depends on the system’s purpose, the expectations of the system users and the current marketing environment of the system.” [29]

2.2. V&V of safety-critical Software

Traditional methods for software V&V are classified into three families:

- Fault Avoidance methods: These are the methods “which are based on the premise that we can derive systems that are fault-free by design”
- Fault Removal methods: These are the methods “which concede that fault avoidance is unrealistic in practice, and are based on the premise that we can remove faults from systems after their design and implementation are complete”
- Fault Tolerance methods: These are the methods “which concede that neither fault avoidance nor fault removal are feasible in practice, and are based on the premise that we can take measures to ensure that residual faults do not cause failure”[2]

These methods works well with traditional controllers. However, they are not applicable for modern adaptive system due to the following reasons:

- “Fault Avoidance methods: In traditional systems, we can determine their functional properties by analyzing the design and implementation. This does not work for adaptive systems because we can not predict the data which adaptive system will learn. Functions, which are computed by adaptive system, are based on both the system design and data it has learned.

- Fault Removal methods: Testing is used to determine system faults after implementations are complete. These methods work well with traditional systems but not with adaptive systems because adaptive systems' behaviors change over time. We can not predict what those behaviors are to test in order to find out system faults
- Fault Tolerance methods: These methods will make one or more duplicates of a system's functions to use as backups in case this system experience failure of functions. Therefore, fault tolerance methods required functions to be predetermined. In adaptive system, functions are not determined until new data is learned." [2]

Many modern missions require modern control systems which can handle critical changes in a system's behavior. Intelligent adaptive controllers are the right choice for those missions. However these adaptive controllers need to be verified and validated before being used to ensure the safety of missions.

“Space missions are good examples when adaptive controllers are used. Most space missions are long and autonomous. It is important that the control system can recognize and correct problems dynamically. These abilities can not be addressed with traditional controllers. Spacecraft mission such as CEV or JIMO requires controllers to perform in different environments than Earth environments. These controllers must control the individual systems reliably and safely in the situations which would be impossible to analyze ahead of time on Earth. Manual repair in space sometimes is not possible in case of components failures. The entire system must cope with these changes as fast as possible to maintain stability. Traditional fixed-gain controllers do not have the required capabilities. Hence the need for Intelligent Flight Controller System, but this system must be certified to use on these missions. NASA has several V&V standards for Intelligent Flight Controller System:

- NASA Guidebook for Safety Critical Software, NASAGB- 1740.13-96
- Trial-Use Standard for Information Technology Software Life Cycle Processes - Software Development, JSTD-016-1995
- IEEE Standard for Software Test Documentation, IEEE Std 829-1998 (Revision of IEEE Std 829-1983)
- NASA Procedures and Guidelines (NPG) 2820.DRAFT and NASA Software Guidelines and Requirements.
This document references IEEE/EIA Standards 12207.0, 12207.1, and 12207.2 which in turn reference standards published in 1995 as ISO/IEC 12207.
- NASA Procedures and Guidelines (NPG) 8730.DRAFT 2, Software Independent Verification and Validation
- (IV&V) Management. This standard discusses the requirements for independent verification and validation. In a nutshell, a manned mission and any mission or program costing more than \$100M will require IV&V1” [31]

There is also a guidance which has V&V process integrate to Software Life Cycle. At every phrase of the Software Life Cycle, V&V are performed to ensure the

correctness of product. These V&V phrases are used to enhance but not to replace traditional testing. Figure 2.1 shows the Software Life Cycle with integrated V&V process

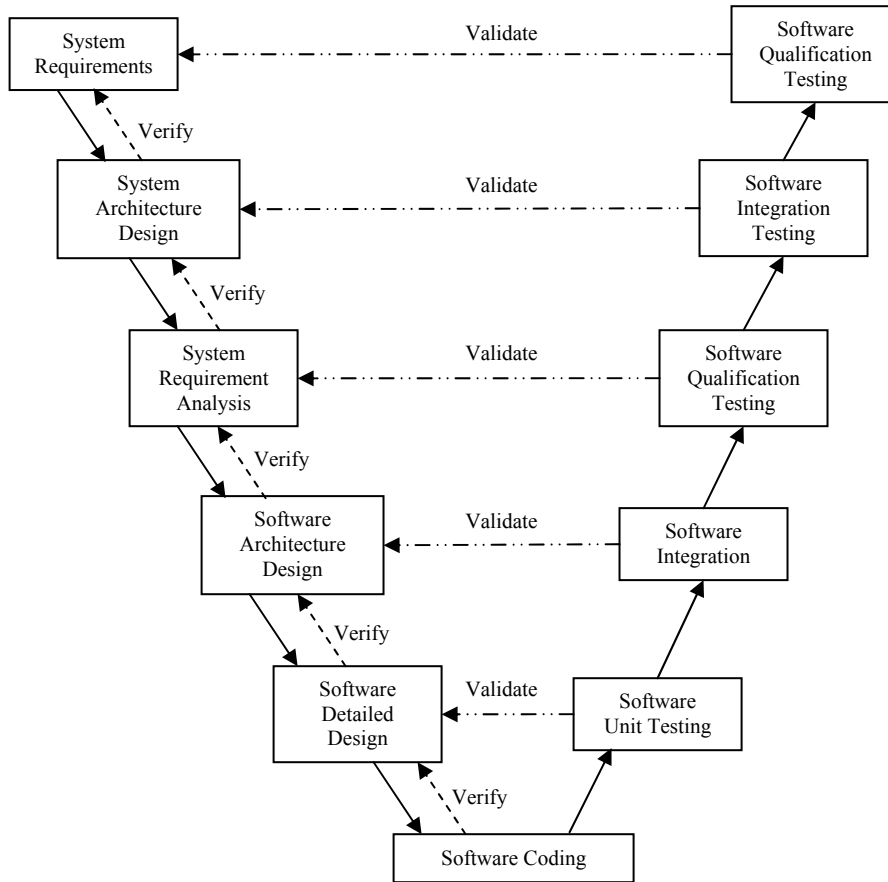


Figure 2.1: Software Life Cycle with integrated V&V process [31]

2.3. Issues and Methods in V&V of adaptive systems

2.3.1. Issues

It is clear that we can not use traditional V&V methods on adaptive systems. New V&V methods must be developed to ensure safety and reliability of adaptive systems. According to Mili, V&V of on-line learning systems can be summarized in the following premises:

- “We establish the correctness of the system, not by analyzing the process by which the system has been designed, but rather by analyzing the functional properties of the final product, and how these functional properties evolve through learning.

- Qualifying the first premise, we capture the functional properties of the system not by the exact function that the system defines at any stage in its learning process, but rather by a functional envelope, which captures the range of possible functions of the system for a given learning history.
- In order to make testing meaningful, we need to ensure that the system evolves in a way that preserves or enhances its behavior under test. Of course, on-line learning systems are supposed to get better as they acquire more learning data, but our definition of better is very specific: it means that the functional envelope of the system grows increasingly more refined with learning data
- In order to support some form of correctness verification, we must recognize that the variability of learning data and the focus on functional envelope (rather than precise function) weaken considerably the kinds of functional properties that can be established by correctness verification. Typically, all we can prove are minimal safety conditions;” [2]

2.3.2. Design and analysis

Lyapunov’s functions are well-known in the control studies and implementations to prove systems’ stability or instability of fixed points in dynamical systems and autonomous differential equations [37]. I will briefly explain the idea of Lyapunov’s functions in this section.

“Often the designer is first concerned about investigating the stability properties of a system, since it is often the case that if the system is unstable there is no chance that any other performance specifications will hold.” [21]

An undisturbed motion is consider being stable if there is a small disturbance to it, and this motion remains close to the unperturbed one for all time [31]. More specifically, Lyapunov’s ideas about stability are as below:

- “If for small disturbances, the effect on the motion is small, then the undisturbed motion is ‘stable’
- If for small disturbances, the effect is considerable, then the undisturbed motion is ‘unstable’
- If for small disturbances, the effect tends to disappear, then the undisturbed motion is ‘asymptotically stable’
- If regardless of the magnitude of the disturbances, the effect tends to disappear, then the undisturbed motion is ‘asymptotically stable in the large’”[31]

Definition

“Let

$$f : D \subset R^n \rightarrow R^n \tag{2.1}$$

be a vector field in R^n which is two times continuously differentiable with

$$f(p) = 0 \quad (2.2)$$

for some p in D . Given an open neighbourhood U of p contained in D a scalar function

$$V : U \rightarrow R \quad (2.3)$$

is called Lyapunov function for f and p if

- V is continuous on U and continuously differentiable on $U \setminus \{p\}$
- $V(p) = 0$ and $V(x) > 0$ for all x in $U \setminus \{p\}$, that is V is a positive-definite function
- $\text{grad}V(x) \circ f(x) \leq 0$ for all x in $U \setminus \{p\}$, in other words the derivative of V in direction $f(x)$ is decreasing.

If additionally the stronger condition $\text{grad}V(x) \circ f(x) < 0$ is satisfied, we call V a strict Lyapunov function.”[37]

3. Validation with Fuzzy Cooper-Harper Rules

3.1. Cooper-Harper Rating Rules

We will use the magnitude of control as an indication of pilot compensation effort. When high/low compensation is needed to maintain the aircraft desired performance, corresponding extent of high/low control effort is applied accordingly. The status of the aircraft being under control or not can be observed by examining the stability of the flight system. The rate of change of an appropriate Lyapunov function will be a good indication of how the flight system is under control. In accordance with the Lyapunov function theory, a negative rate of change of Lyapunov function is an indication of the given system being stable whereas a positive rate change would indicate instability. [35]

Lyapunov function

$$J = \frac{1}{2}(e^2 + \dot{e}^2) \quad (3.1)$$

Negative rate of change of Lyapunov

$$-\Delta J(k) = -(J(k) - J(k-1)); k \in \mathbb{N}, k \geq 1 \quad (3.2)$$

In the case of aircraft performance, we shall use the magnitude of tracking error as an indicator. Obviously, when the tracking error is small the flight system exhibits a good performance and vice versa.

With these indicators, typical rating rules can be like the following:

Group 1: Rating 1, 2 and 3. According to the flowchart on Figure 1.6, the aircraft is controllable, adequate performance is attainable with a tolerant pilot workload, and it is satisfactory without improvement. This means aircraft control in this group is **stable**. Pilot needs only a **little** effort to control the aircraft.

Pilot Rating is 1

Cooper-Harper Statement: “Aircraft characteristics are excellent (highly desirable). Pilot compensation is not a factor for desired performance.”

Interpretation: Rating 1 indicates that aircraft performance is at its excellent condition. The control is stable. None or a small amount of the control-effort is needed to have the desired performance.

Rule 1: If **Control-Effort** is *small* and **Control** is *stable* and **Performance** is *excellent*, then Rating is 1

Pilot Rating is 2

Cooper-Harper Statement: “Aircraft characteristics are good (negligible deficiencies). Pilot compensation is not a factor for desired performance.”

Interpretation: Rating 2 indicates that aircraft performance is in good condition. The control is stable. It has some deficiencies, but they are negligible. None or a small pilot control-effort is needed to have the desired performance.

Rule 2: If **Control-Effort** is *small* and **Control** is *stable* and **Performance** is *good*, then Rating is 2

Pilot Rating is 3

Cooper-Harper Statement: “Aircraft characteristics are fair (some mildly unpleasant deficiencies). Minimal pilot compensation required for desired performance.”

Interpretation: Rating 3 indicates that aircraft performance is in good condition. There are some mildly unpleasant deficiencies, but desired performance is still attainable with minimal pilot control-effort. “Desired performance” is the key phrase to decide that the performance is good in this rating. Control is stable

Rule 3: If **Control-Effort** is *minimal* and **Control** is *stable* and **Performance** is *good*, then Rating is 3

Group 2: Rating 4, 5 and 6. According to the flowchart on Figure 1.6, the aircraft is controllable, adequate performance is attainable with a tolerant pilot workload, but it is not satisfactory without improvement. This means control of aircraft in this group is **stable**. Pilot has to put in some trivial efforts to control the aircraft.

Pilot Rating is 4

Cooper-Harper Statement: “Aircraft characteristics have minor (but annoying) deficiencies. Desired performance requires moderate pilot compensation.”

Interpretation: Rating 4 indicates that aircraft performance is in good condition. There are some minor deficiencies, but desired performance is still attainable with moderate pilot control-effort. “Desired performance” is the key phrase to decide that the performance is good in this rating. Control is stable

Rule 4: If **Control-Effort** is *moderate* and **Control** is *stable* and **Performance** is *good*, then Rating is 4

Pilot Rating is 5

Cooper-Harper Statement: “Aircraft characteristics have moderately objectionable deficiencies. Adequate performance requires considerable pilot compensation.”

Interpretation: Aircraft performance in this rating is adequate. Control is stable, but it has some moderately objectionable deficiencies. Pilot has to put in considerable control-effort to maintain the aircraft in good condition.

Rule 5: If **Control-Effort** is *considerable* and **Control** is *stable* and **Performance** is *adequate*, then Rating is 5

Pilot Rating is 6

Cooper-Harper Statement: “Aircraft characteristics are very objectionable (but tolerant deficiencies). Adequate performance requires extensive pilot compensation.”

Interpretation: Rating 6 indicates that the aircraft performance is adequate. Control is stable, but it is very objectionable. Extensive pilot compensation is needed to maintain the aircraft.

Rule 6: If **Control-Effort** is *extensive* and **Control** is *stable* and **Performance** is *adequate*, then Rating is 6

Group 3: Rating 7, 8 and 9. In this group, the aircraft is controllable, but adequate performance is not attainable with a tolerant pilot workload. Pilot has to put in a lot of efforts to control the aircraft.

Pilot Rating is 7

Cooper-Harper Statement: “Aircraft characteristics have major deficiencies. Adequate performance is not attainable with maximum tolerable pilot compensation, but controllability is not in question.”

Interpretation: Rating 7 indicates aircraft performance is not adequate. Control is stable, but it has major deficiencies. Pilot has to put in maximum effort to control the aircraft. “Controllability not in question” is the key phrase to decide the stability of the aircraft.

Rule 7: If **Control-Effort** is *maximum* and **Control** is *stable* and **Performance** is *not adequate*, then Rating is 7

Pilot Rating is 8

Cooper-Harper Statement: "Aircraft characteristics have major deficiencies. Considerable pilot compensation is required for control."

Interpretation: Aircraft performance is not adequate because aircraft characteristics have major deficiencies in this rating.

"Considerable pilot compensation is required for control" means when pilot compensation is lower than "considerable", the aircraft will be unstable. Therefore control in this rating is unstable.

Due to the poor stabilities of the aircraft control in this rating, pilot will have to apply different levels of effort to control the aircraft. Pilot control-effort can range from small, minimal, to moderate effort. This will give three more rules for rating 8

Rule 8: If **Control-Effort** is *small* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 8

Rule 9: If **Control-Effort** is *minimal* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 8

Rule 10: If **Control-Effort** is *moderate* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 8

Pilot Rating is 9

Cooper-Harper Statement: "Aircraft characteristics have major deficiencies. Intense pilot compensation is required to retain control."

Interpretation: Aircraft performance is not adequate because aircraft characteristics have major deficiencies in this rating. "Intense pilot compensation is required to retain control" means when pilot compensation is lower than "intense", the aircraft will be unstable. This means control is unstable in this rating

Aircraft requires higher level of pilot effort to keep control it. Pilot effort can range from small to extensive, but we already cover the case of pilot compensation from small to moderate in rating 8. Therefore we will have just two more rules for rating 9 to cover the case when control-effort is considerable and extensive.

Rule 11: If **Control-Effort** is *considerable* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 9

Rule 12: If **Control-Effort** is *extensive* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 9

Group 4: Rating 10. In this group, the aircraft is not controllable. Highest level of pilot’s effort is needed to control the aircraft.

Pilot Rating is 10

Cooper-Harper Statement: “Aircraft characteristics have major deficiencies - improvement is mandatory, Control will be lost during some portion of required operation.”

Interpretation: This rating is the highest rating in Cooper-Harper rating. Aircraft performance is not adequate due to the Cooper-Harper statement “aircraft characteristics have major deficiencies. Control is highly unstable because ‘control will be lost during some portion of required operation’.

It needs all of control-effort levels from the pilot. Pilot compensation can range from small to maximum, but we already cover the cases of pilot compensation from small to extensive in rating 8 and 9. Therefore we will have just two more rules for rating 10 to cover the case when control-effort is intense and maximum.

Rule 13: If **Control-Effort** is *intense* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 10

Rule 14: If **Control-Effort** is *maximum* and **Control** is *unstable* and **Performance** is *not adequate*, then Rating is 10

Based on these rules, we summarize the Cooper-Harper aircraft handling qualities rating system as shown in Table 3.1 below.

Rule	Compensation (Control)	Control (Stability)	Performance (Tracking)	Rating
1	Small	Stable	Excellent	1
2	Small	Stable	Good	2
3	Minimal	Stable	Good	3
4	Moderate	Stable	Good	4
5	Considerable	Stable	Adequate	5
6	Extensive	Stable	Adequate	6
7	Maximum	Stable	Not Adequate	7
8	Small	Unstable	Not Adequate	8
9	Minimal	Unstable	Not Adequate	8
10	Moderate	Unstable	Not Adequate	8
11	Considerable	Unstable	Not Adequate	9
12	Extensive	Unstable	Not Adequate	9

13	Intense	Unstable	Not Adequate	10
14	Maximum	Unstable	Not Adequate	10

Table 3.1 Cooper-Harper Rating Rules

3.2. Fuzzy rule-based system

Fuzzy system has four major components as shown in Figure 3.1

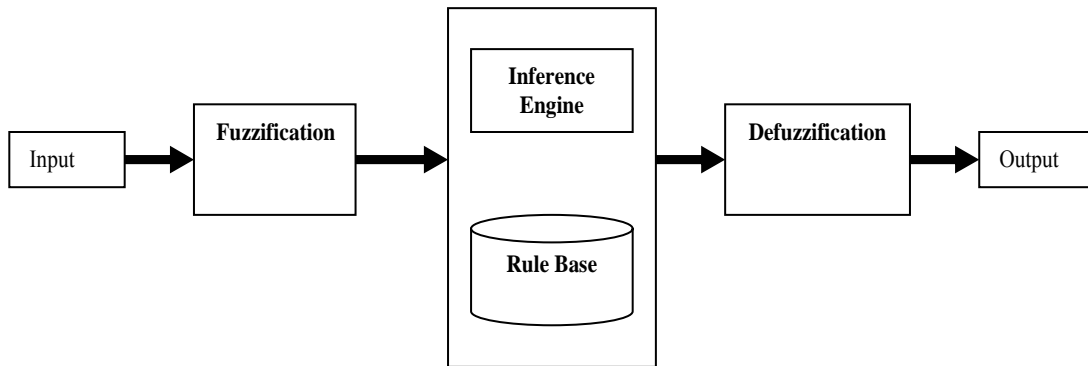


Figure 3.1 - Fuzzy Inference System Component .

Fuzzification:

“Each linguistic variable, e.g., performance, is associated with membership functions that are defined for the affiliated Fuzzy sets e.g., excellent, good, etc. This component receives a crisp input value for each linguistic variable and evaluates the degree of membership of this variable with respect to each affiliated Fuzzy set.

- **Fuzzy Rule Base**

Fuzzy systems use Fuzzy IF-THEN rules. A Fuzzy IF-THEN rule is of the form:
 IF $X_1 = A_1$ and $X_2 = A_2$... and $X_n = A_n$ THEN $Y = B$

Where X_i and Y are linguistic variables and A_i and B are linguistic values. The collection of Fuzzy IF-THEN rules is stored in the Fuzzy Rule Base, which is accessed by the Fuzzy Inference Engine when inputs are being processed. In our case, we have 14 rules based on Cooper-Harper aircraft handling qualities rating.

- **Fuzzy Inference Engine**

This component receives all the crisp input values that have been fuzzified with respect to their respective linguistic membership functions and process them based on the Fuzzy Rule Base to deduce the conclusive output. The two main steps in the inference process are aggregation and composition. Aggregation is the process of computing for the membership values of the IF part of the rules while composition is the process of computing for the membership values of the THEN part of the rules.

During aggregation, each condition in the IF part of a rule is assigned a degree of truth based on the degree of membership of the corresponding linguistic membership functions. Typically, the minimum or the product of the degrees of truth of all the conditions is computed as the overall degree of truth of the IF part. For the case of crisp output design, this aggregated truth value is also the truth value of the associated rule subject to the inputs.

- **Defuzzification**

The process of generalizing the fuzzified values with respect to the fuzzy rule base back to crisp output values is called defuzzification. There are different ways to defuzzify. Some common defuzzification methods include centroid and maximum height ”[35]

3.3. Fuzzy Cooper-Harper rating system

“Cooper-Harper rating system takes on three indexes from the system under control and deduces a rating based on the fuzzy engine as shown in Figure 3.2. The three indexes, i.e., performance, control, and compensation, are in accordance with the original Cooper-Harper aircraft handling system. A real-time rating between numerical values of 1 to 10 will be produced based on the actual inputs at application stage. In view of the fact that measurement data will never be precise, due to sensor or other possible design errors, fuzzy logic proves to be an effective scheme to counteract these issues that are also present in our problem. Furthermore, fuzzy logic has the well-known generalization capability that will enable us to deal with various cases that may or may not match our 10 rules exactly in the application stage.

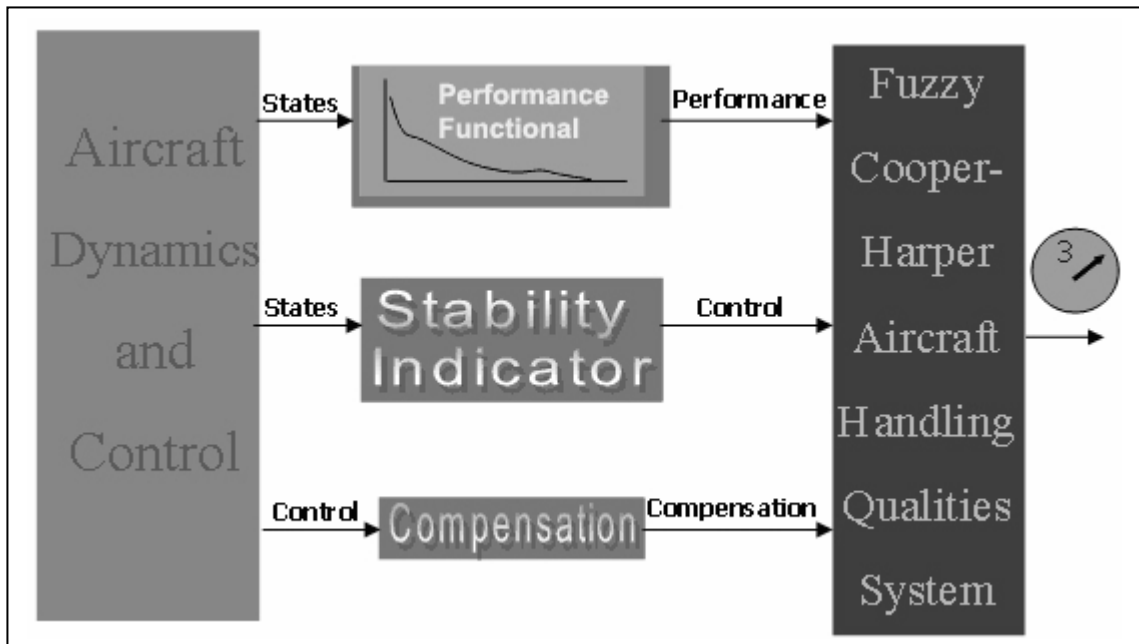


Figure 3.2 Fuzzy Cooper-Harper rating system

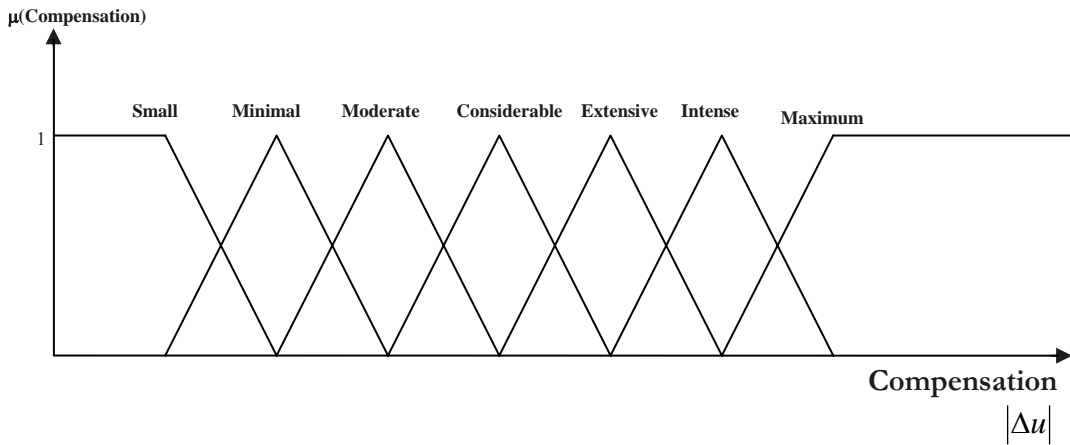


Figure 3.3 Membership function for linguistic variable compensation

Compensation:

$$\Delta u(k) = u(k) - u(k - 1); k \geq 1 \quad (3.3)$$

In application stage, associated membership function values for each linguistic value can be computed based on the given input as illustrated in Figure 3.3.

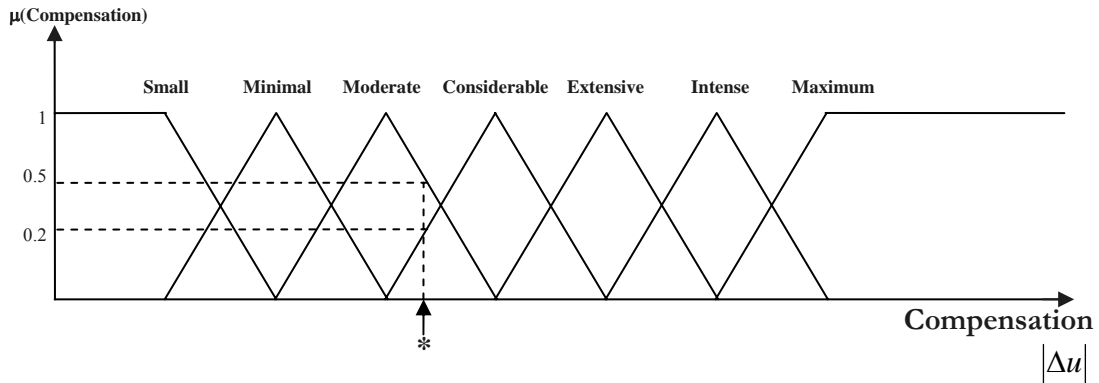


Figure 3.4 Computing membership values

For the case illustrated in Figure 3.4, we have the computed membership values as $\mu_{\text{Moderate}}(\text{Compensation}) = 0.5$ and

$\mu_{\text{Considerable}}(\text{Compensation}) = 0.2$

Similarly, Figures 3.5 and 3.6 show the membership functions for the control and the performance linguistic variables, respectively.

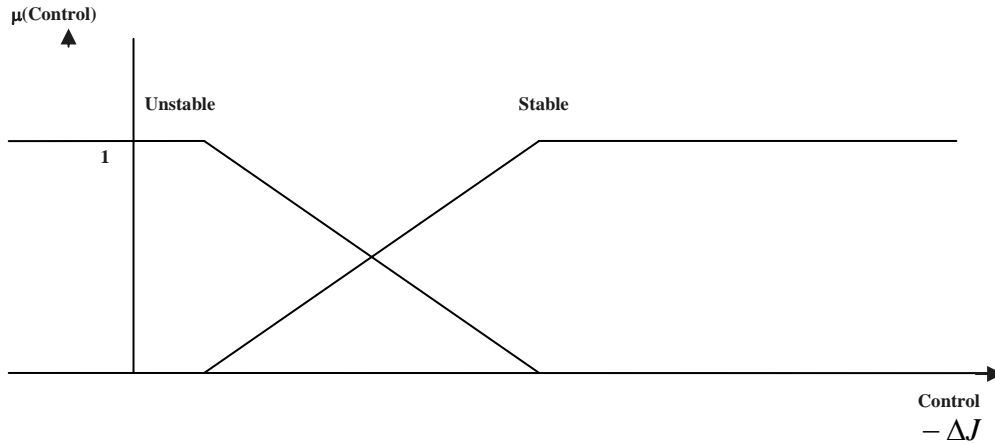


Figure 3.5 Membership function for linguistic variable control

J is the square of tracking error in the given problem.

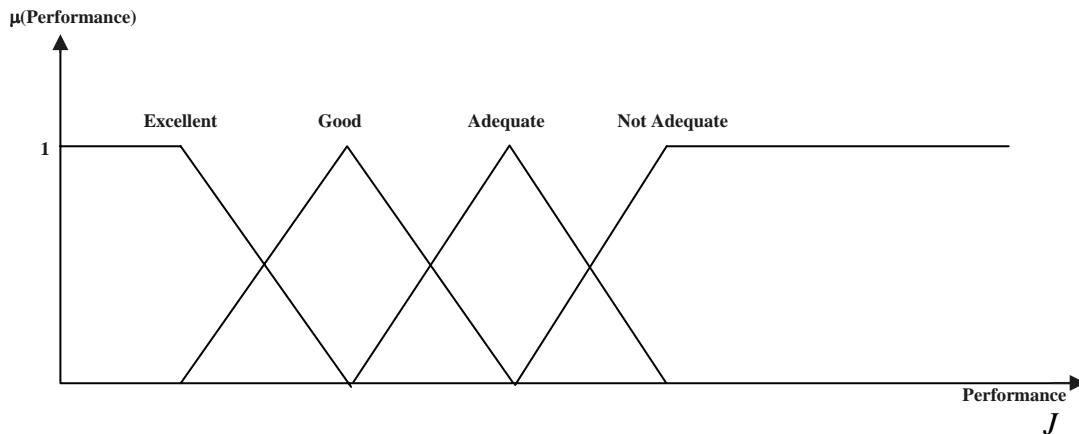


Figure 3.6 Membership function for linguistic variable performance

Note other membership function types, e.g., Gaussian type, can be used as well” [35].

3.4. Validation of an F-14 Longitudinal Control System

We apply our proposed fuzzy Cooper Harper rating system to a simplified F-14 Longitudinal control system. This system is modified from a Matlab demo example as shown in Figure 3.7 [13]. The generalized control objective is to ensure the alpha angle track the pilot input.

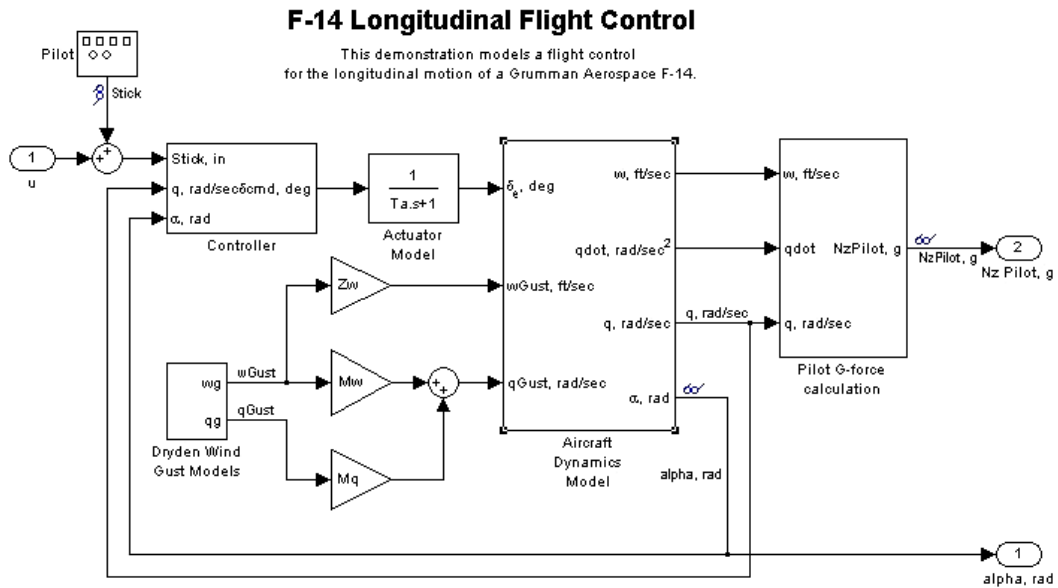


Figure 3.7 F-14 longitudinal control system

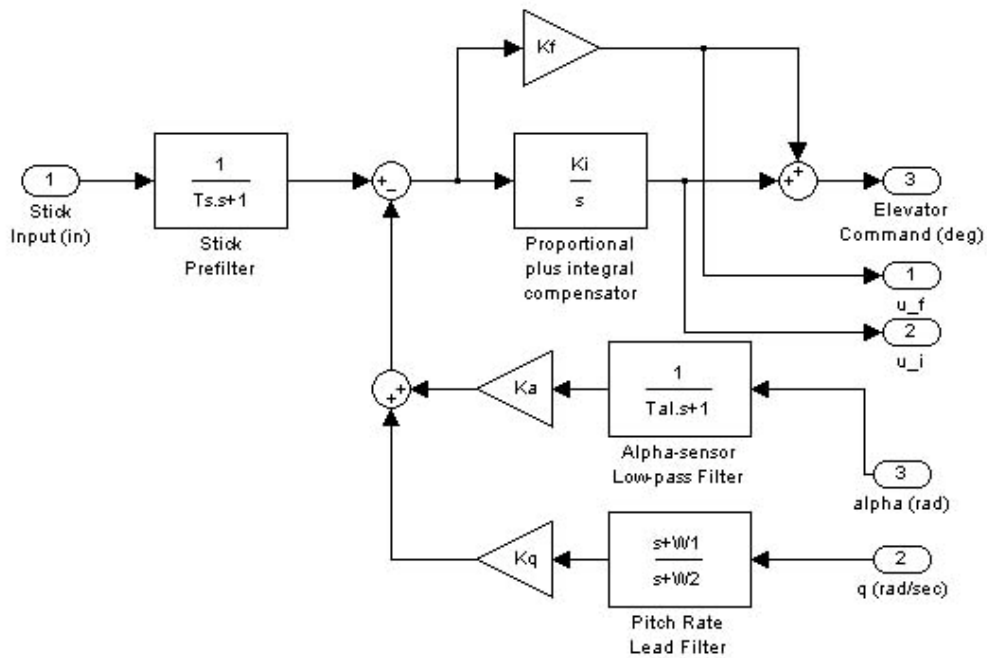


Figure 3.8: F-14 PI Controller

A fuzzy Harper-Cooper rating system is augmented to the given F-14 control to validate aircraft handling qualities. Matlab F-14 control model use PI controller with K_f is the Proportional Controller Gain and K_i is the Integral Proportional Controller Gain as shown in Figure 3.8.

The fuzzy Cooper-Harper rating system is firstly calibrated against several standard cases and its fuzzy membership functions tuned

The values we used for all fuzzy membership functions in our simulations are shown in table 3.2, 3.3, 3.4.

Small	Minimal	Moderate	Considerable	Extensive	Intense	Maximum
0.015 (Trapezoidal)	0.0925 (Triangular)	0.2 (Triangular)	0.2475 (Triangular)	0.325 (Triangular)	0.4025 (Triangular)	0.48 (Trapezoidal)

Table 3.2: Numerical values for various means Compensation linguistic variables

Unstable	Stable
-0.2 (Trapezoidal)	0 (Trapezoidal)

Table 3.3: Numerical values for various means Control linguistic variables

Excellent	Good	Adequate	Not Adequate
0.0001 (Trapezoidal)	0.08 (Triangular)	0.17 (Triangular)	0.35 (Trapezoidal)

Table 3.4: Numerical values for various means Performance linguistic variables

In the application stage, we use a square wave with alternating magnitude of +/- 0.5 as pilot input. The resultant tracking profile of alpha is as shown in Figure 3.9

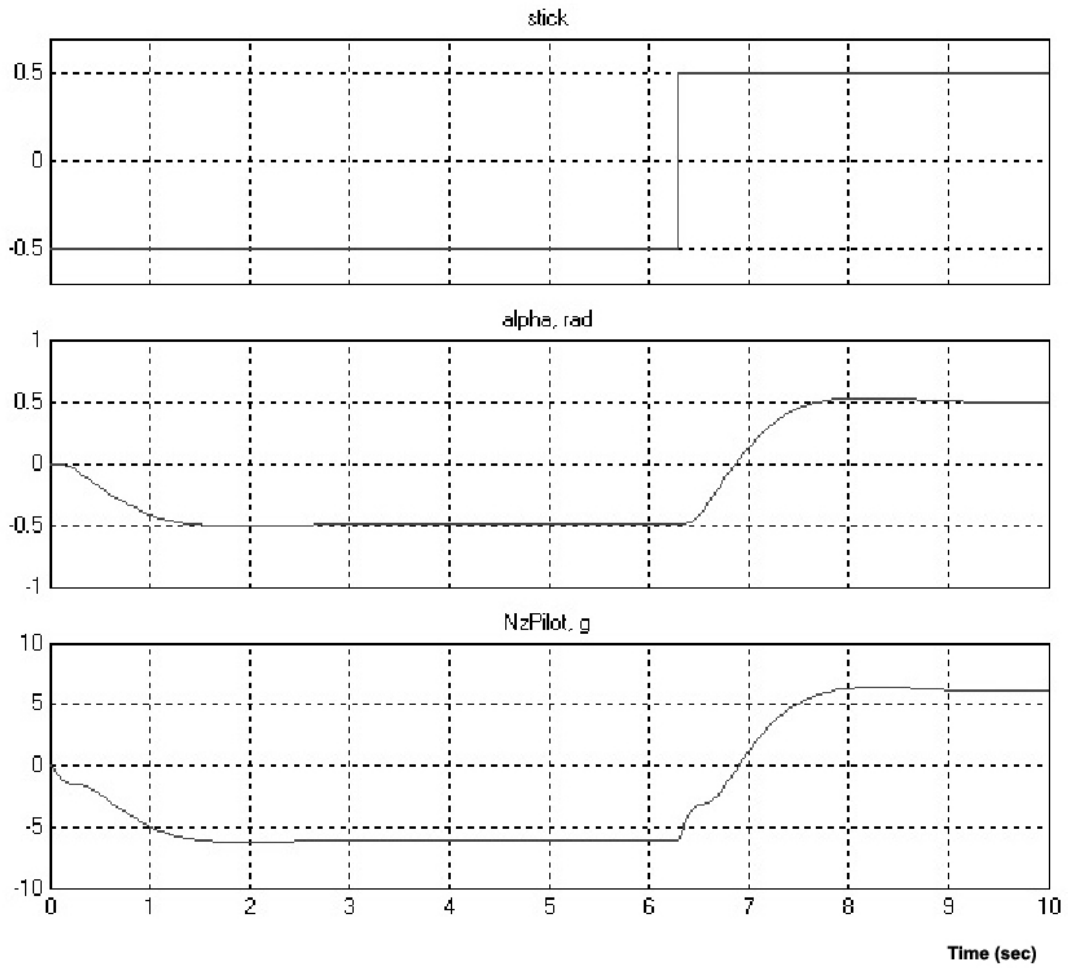


Figure 3.9 input and output profiles

After simulation is complete, we will have the profiles of three indicators which will help to determine Cooper-Harper rating.

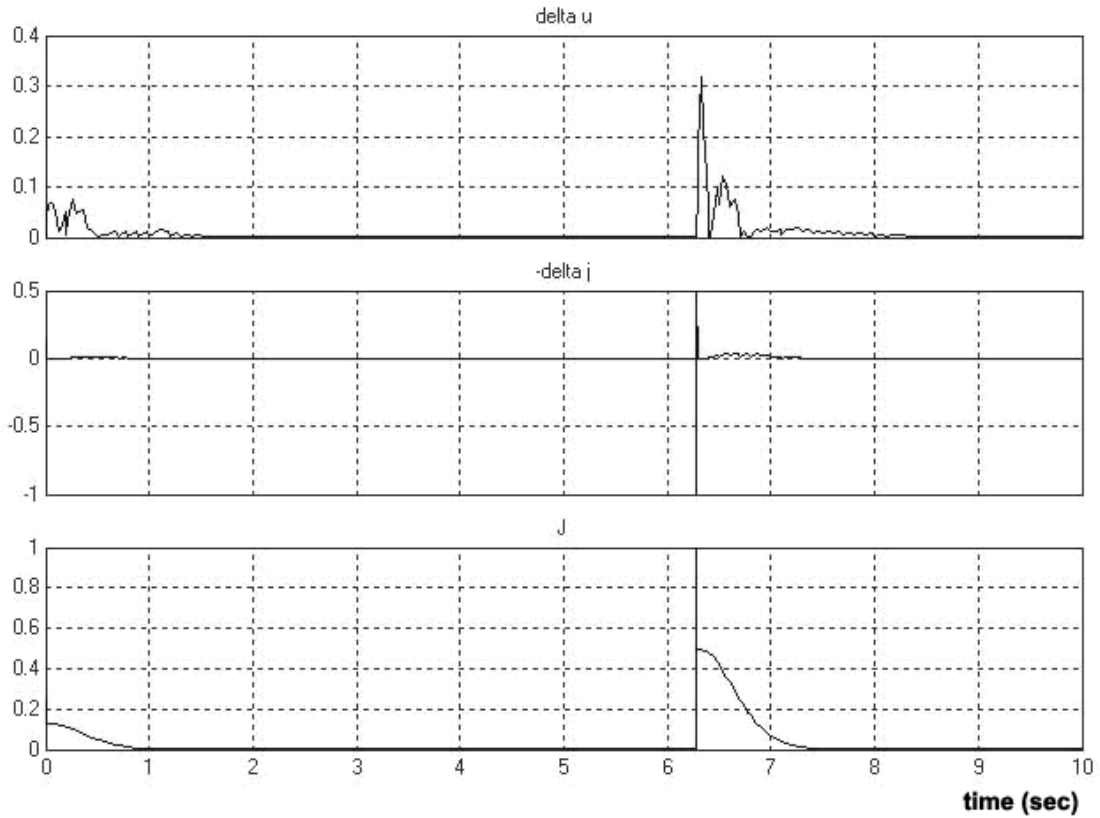


Figure 3.10: Indicator profiles for aircraft when $K_f = -1.7$. J , $-\Delta J$, and Δu are defined in (3.1), (3.2), (3.3).

Our fuzzy Cooper-Harper rating system yields the rating profile as shown in Figure 3.11. The y-axis represents the Cooper-Harper rating generated from our fuzzy Cooper-Harper rating system during the 10-second simulation interval.

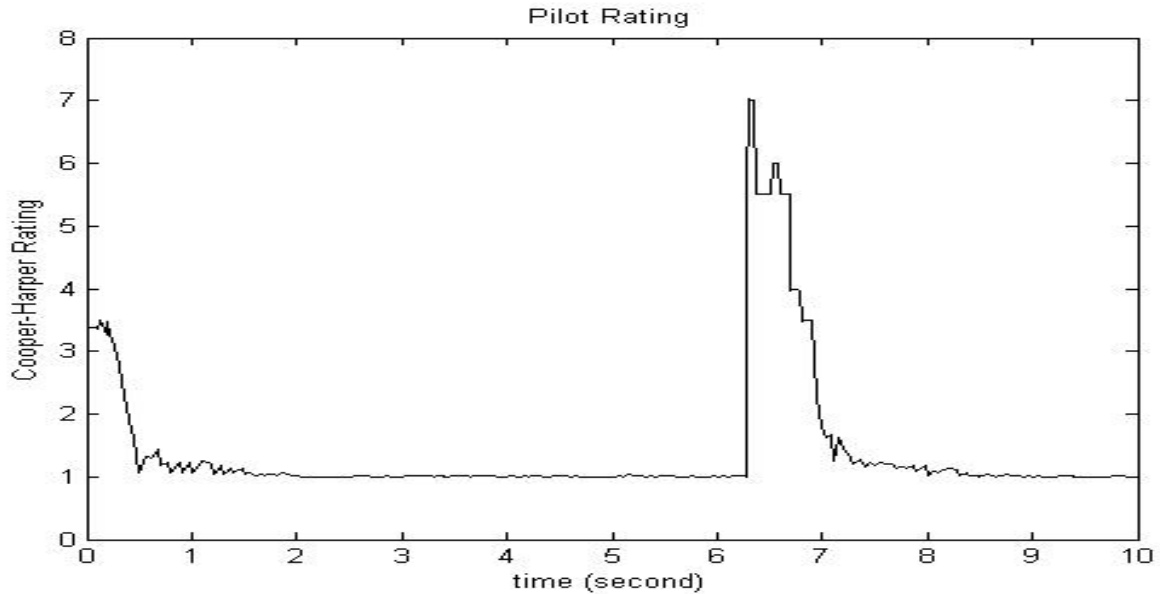


Figure 3.11 aircraft handling qualities rating profile with $K_f = -1.7$

At the beginning of the simulation $t=0$, we can see the three numerical values for compensation, control and performance variables are 0.08, 0, and 0.15 accordingly. This means compensation is minimal, control is stable and performance is good. According to Table 3.1, Cooper-Harper rating system will generate a rating 3. Figure 3.11 showed that at the beginning of the simulation, Cooper-Harper rating is 3.3, which is very close to 3.

In another simulation, we change the value K_f of the control to be 0.1. This will make the control unstable. We can see this in the tracking profile of α in the figure below

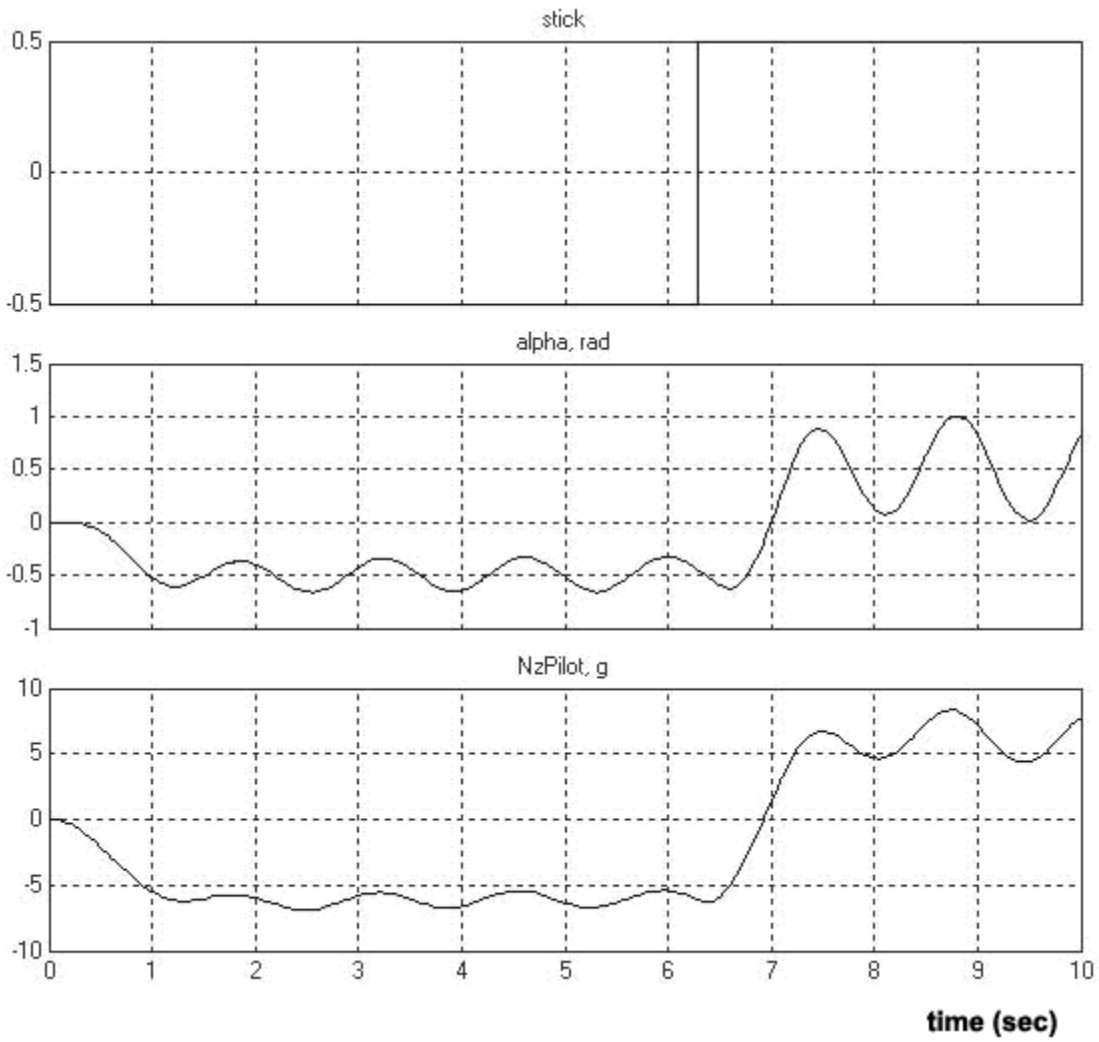


Figure 3.12 input and output profiles with $K_f = 0.1$

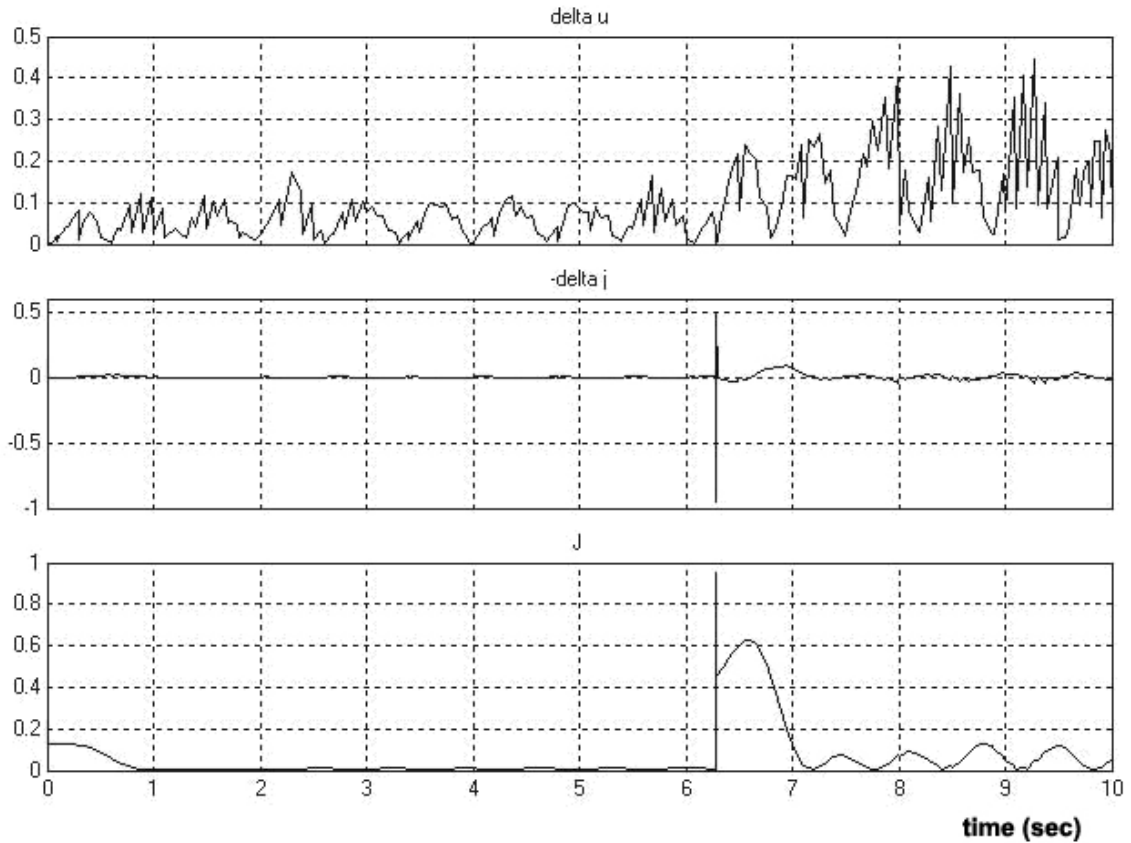


Figure 3.13: Indicator profiles for aircraft when $K_f = 0.1$. J , $-\Delta J$, and Δu are defined in (3.1), (3.2), (3.3).

The Cooper-Harper rating in figure 3.14 is different from figure 3.11 because the aircraft control is now unstable

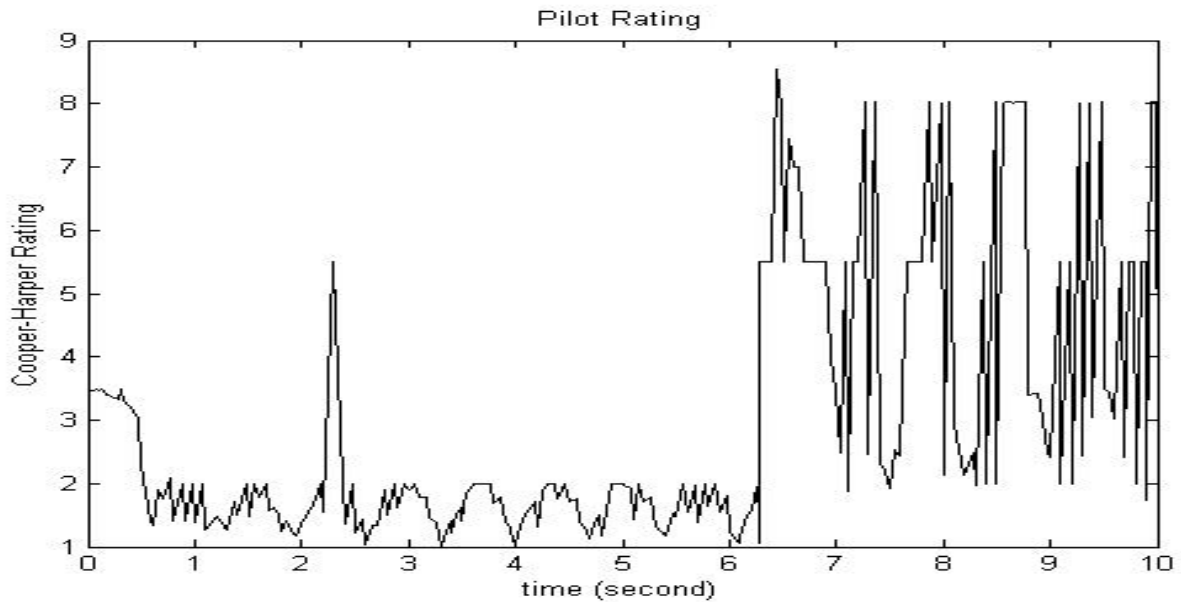


Figure 3.14 aircraft handling qualities rating profile with $K_f = 0.1$

At the end of the simulation $t=10$, we can see the three numerical values for compensation, control and performance variables are 0.24, 0, and .095 accordingly. This means compensation is considerable, control is stable and performance is adequate. According to Table 3.1, Cooper-Harper rating system will generate a rating 5. Figure 3.14 showed that Cooper-Harper rating is also 5 at the end of the simulation.

This shows that our proposed fuzzy Cooper-Harper rating system can be used to effectively validate the aircraft handling qualities.

4. Adaptive PI controller with Cooper-Harper Feedback

4.1. Fixed value F14 PI controller

A fixed value controller is a controller which use a fixed gain value K_f in its control. Figure 3.8 shows the fixed value F-14 PI Controller. It uses a fixed value $K_f = 1.746$ to adjust its controller. Tracking error will always multiply with a fixed value of 1.746 to compute a new control value. In order for this controller to perform better, the fixed gain value K_f should be adjustable based on some sensors values. This is the main drive the work in the next sections.

To distinguish the two gain values in this paper, we will use the notation K_f for fixed gain value and K_p for adjustable gain value.

4.2. Adaptive PI controller with Cooper-Harper Feedback VS. Adaptive PI Controller

Adaptive feedback loop controller is well-known and widely implemented. Tracking error, which is the difference between reference and plant sensors' output data, is passed to an adaptive controller to generate new controlled data values to control the plant. Figure 4.1 illustrates this idea.

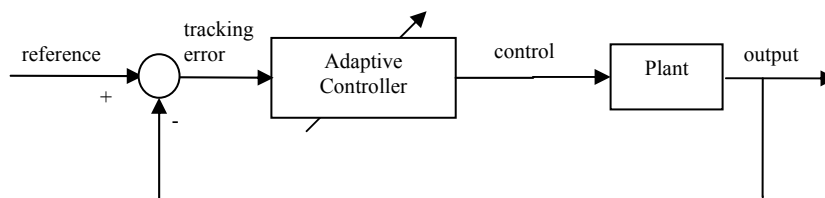


Figure 4.1: Adaptive control system without human feedback

The adaptive control system in Figure 4.1 uses plant sensors' data to adjust its controller. However, these data are very difficult to understand by human user. In this

section, we propose a system which uses the same idea, but with another additional input to the adaptive controller. This additional input is a human readable rating value. This human readable rating value is important because user can understand the value which will adjust the controller directly.

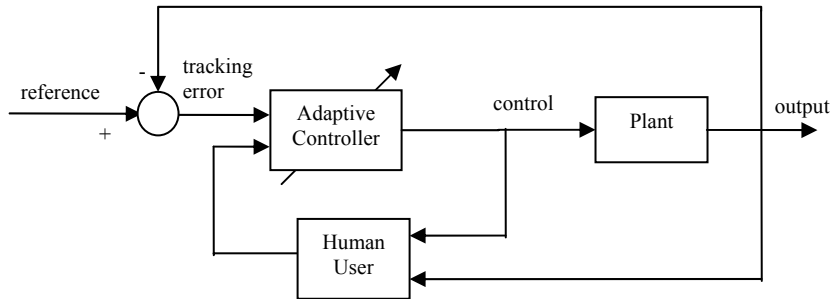


Figure 4.2: Adaptive control system with human feedback

Figure 4.2 illustrates the proposed system we mentioned above. Sensors' output data values, together with control data are passed to a human user component. This component will generate the human readable rating value. The adaptive controller will acquire both the tracking error and the human readable rating value to compute and generate new control for the next iteration.

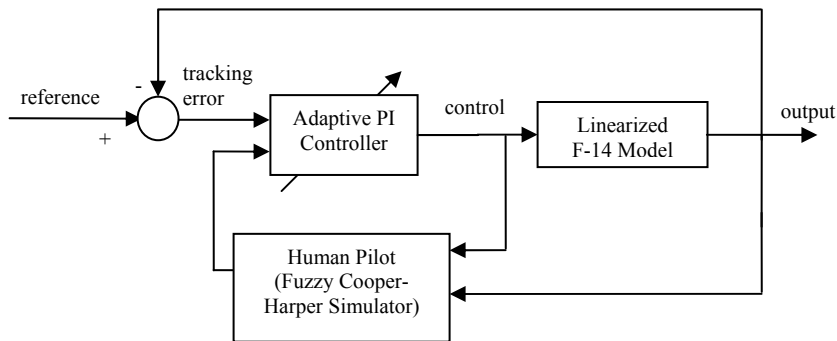


Figure 4.3: F-14 control system with human feedback

Fuzzy Cooper-Harper Rating can be used to implement the idea we propose above. The Fuzzy Cooper-Harper Rating will take both sensors' output data from the plant and controlled data to generate a human reading rating value.

Figure 4.3 shows how we implement this system using Matlab Linearized F14 Model. Matlab Fuzzy tool box is used to implement the Fuzzy Cooper-Harper Simulator. This simulator will generate a rating from 1 to 10 and pass it to the PI controller. The PI controller takes this rating, and adjusts the proportional gain value adaptively. When this gain value is adjusted adaptively, new control data are generated to control the F-14 model.

Implementation

At every simulation step, the Cooper-Harper Aircraft Handling Qualities Rating and the K_p value are passed to the adaptive controller. This controller will adjust the gain value K_p based on the following:

Change in Cooper-Harper Aircraft Handling Qualities Rating:

$$\Delta R(k) = R(k) - R(k-1); k \in N, k \geq 1 \quad (4.1)$$

and

$$\frac{\partial R}{\partial K_p}(t) \approx \frac{\Delta R(k)}{\Delta K_p(k)}; k \in N, k \geq 1 \quad (4.2)$$

$$\frac{\Delta R(k)}{\Delta K_p(k)} = \frac{R(k) - R(k-1)}{K_p(k) - K_p(k-1)}; k \in N, k \geq 1 \quad (4.3)$$

Then we will use the decision tree in Figure 4.4 below to determine the value of ΔK_p

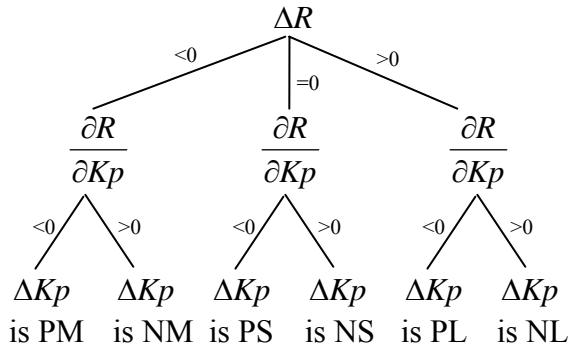


Figure 4.4: Decision Tree for ΔK_p ; PM: Positive Medium; NM: Negative Medium; PS: Positive Small; NS: Negative Small; PL: Positive Large; NL: Negative Large

Where the value of PM, NM, PS, NS, PL, NL are shown in the table 2.1 below

NL	NM	NS	PS	PM	PL
-0.15	-0.08	-0.018	0.018	0.02	0.025

Table 2.1: PM, NM, PS, NS, PL, NL values

When ΔK_p is determined, it will be used to calculate the value of K_p for next iteration:

$$K_p(k+1) = \Delta K_p(k) + K_p(k); k \in N, k \geq 1 \quad (4.4)$$

We also have a control sampling rate. This sampling rate will control the controller when to update the K_p value based on Matlab simulation steps.

Time Performance Index

Time Performance Index (TPI) from both the fixed value PI controller and the adaptive PI controller is used to evaluate the improvement of the adaptive system.

$$TPI = TotalAreaUnderTheCurve \quad (4.5)$$

In order to determine which system performs better, we introduce an improvement value. An improvement value is the difference between the TPI of both fixed value PI controller and adaptive PI controller. It will be use to determine how well the adaptive PI controller perform.

$$Improvement\ value = TPI_{Fixed\ Value\ PI\ Controller} - TPI_{Adaptive\ PI\ Controller} \quad (4.6)$$

A large positive improvement value means the adaptive controller performs better. A large negative improvement value means the fixed value PI controller performs better.

For viewing purpose, we also define a formula to calculate the improvement percentage of the adaptive control system over the fixed control system.

$$Improvement\ percentage = \frac{Improvement\ value}{TPI_{Fixed\ Value\ PI\ Controller}} * 100\% \quad (4.7)$$

4.3. Results

We simulate the F14 Adaptive Controller with many different pilot input frequencies, pilot input signals (Sine, Sawtooth, Square) and sampling rates. Sampling rate is the number of Matlab simulation steps this adaptive controller takes to update gain value Kp

Sampling Rate	Sine	Sawtooth	Square
2	2.6398	0.2964	0.5276
5	2.3576	0.1569	0.8596
10	1.4199	0.0163	0.1790

Table 4.1: Improvement value results with different control variables. Frequency = 1 Hz

Sampling Rate	Sine	Sawtooth	Square
2	2.2205	0.5586	-0.4993
5	1.6545	0.8241	-0.4032
10	1.2274	0.6416	-0.7103

Table 4.2: Improvement value results with different control variables. Frequency = 2 Hz

Observation from the result on tables 4.1 and 4.2 shows:

- Improvement value will drop when sampling rate is high. When this system takes too long to update the Kp value, it will not perform as well. We also experience with a sampling rate =1, which means updating Kp value every simulation step, but Matlab became unstable and crashed. This is a known problem with adaptive system. When it updates too quickly, it will become unstable.
- Sine input signal has the highest improvement overall, follow by Sawtooth, then Square. Sine input signal means input value keep changing, and the adaptive controller shows its power when input value change more frequently

Based on the values on table 4.1, 4.2, and (4.7), we generate the improvement percentage tables 4.3 and 4.4 below.

Sampling Rate	Sine	Sawtooth	Square
2	34.02%	6.19%	6.16%
5	30.38%	3.27%	16.19%
10	18.30%	3.40%	2.09%

Table 4.3: Improvement percentage results with different control variables. Frequency = 1 Hz

Sampling Rate	Sine	Sawtooth	Square
2	19.82%	7.72%	-5.17%
5	14.77%	11.39%	-4.17%
10	10.96%	8.87%	-7.35%

Table 4.4: Improvement percentage results with different control variables. Frequency = 2 Hz

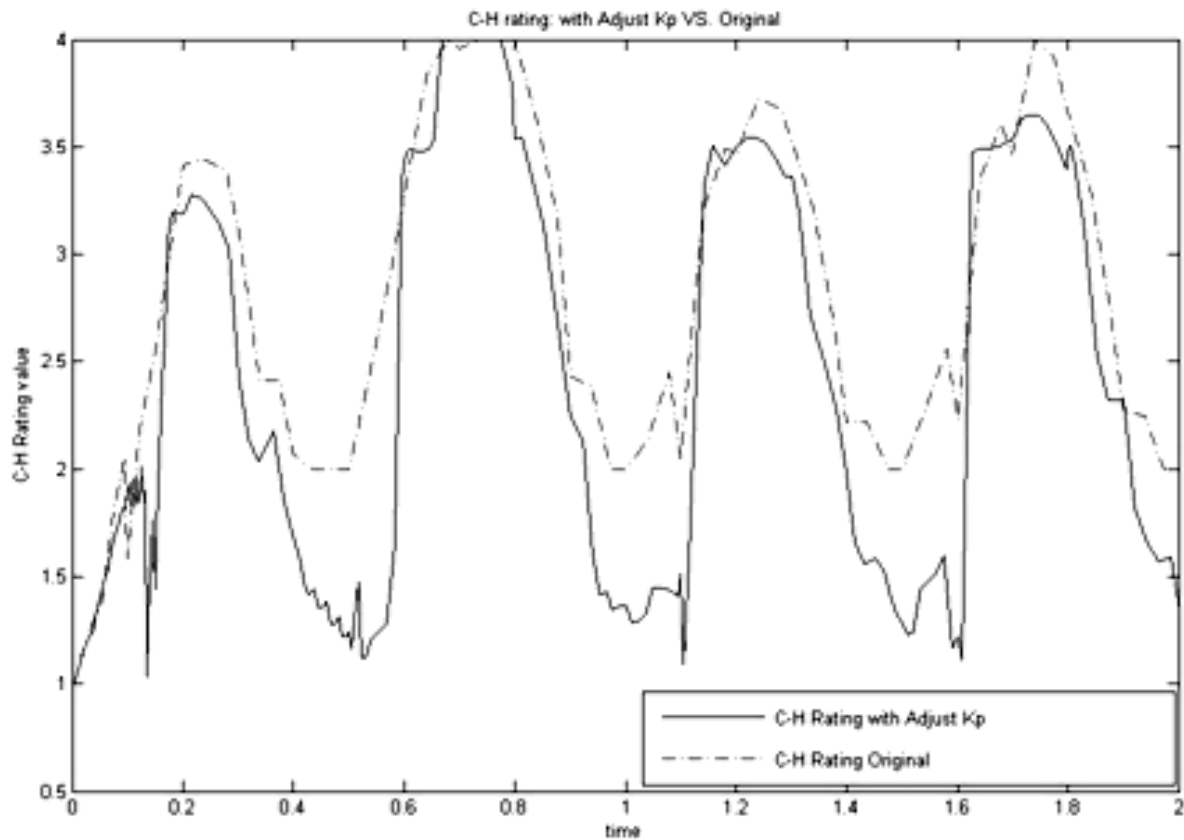


Figure 4.4: Cooper-Harper Rating values plot of Fixed value PI controller VS. Improved PI controllers; Pilot input frequency = 1Hz, Sine curve, Sampling Rate = 2

Figure 4.4 is a graph of the Cooper-Harper Rating values between the fixed value PI controller and the adaptive PI controller. At $t = 1.6$ second, the adaptive controller yields a Cooper-Harper Rating of 1 while the fixed value PI controller yields a rating of 2.25.

This graph shows that the adaptive controller performs much better than the fixed value controller. The goal of this research is to design an adaptive controller which will help the controller perform better by bringing the Cooper-Harper rating closer to 1. Figure 4.4 is one of many good examples to show that our goal is reached.

5. Conclusion

Validation and Verification are important processes used to ensure software safety and reliability. There are many Validation and Verification techniques, but The Cooper-Harper Aircraft Handling Qualities Rating is shown to be affective in this research.

This rating can also be used as feed back to improve PI adaptive control system. The Cooper-Harper Aircraft Handling Qualities Rating is the real feedback from the control

system which human can understand. The idea of this research is to use real human feedback to control system adaptively, and we showed that it's possible.

References

[1] M. G. Perhinschi, J. Burken, M. R. Napolitano, G. Campa, and M. L. Fravolini, "Performance comparison of different neural augmentation for the NASA Gen-2 IFCS F-15 control laws," in Proc. of American Control Conference 2004, vol. 4, pp. 3180- 3184, Jul 2004.

[2] A. Mili, G. Jiang, B. Cukic, Y. Liu, and R. B. Ayed, "Towards the Verification and Validation of Online Learning Systems: General Framework and Applications," in Proc. of the 37th Annual Hawaii International Conference on System Sciences (HICSS'04), track 9, vol. 9, 2004

[3] Y. Liu, S. Yerramalla, B. Cukic, and S. Gururajan, "Adaptive control software: can we guarantee safety?" in Proc of 28th Annual International on Computer Software and Applications Conference, 2004. COMPSAC 2004, vol. 2, pp. 100-103, Sep 2004.

[4] D. M. Rodvold, "A software development process model for artificial neural networks in critical applications," Neural Networks, 1999. IJCNN '99. International Joint Conference, (Washington, DC) vol. 5, pp. 3317-3322, 1999.

[5] Anthony J. Calise and Rolf T. Rysdyk, "Nonlinear Adaptive Flight Control using Neural Networks," page14-25, issue 6, Volume 18, IEEE Control Systems Magazine, 1998

[6] Johann Schumann and Pramod Gupta, "Monitoring the Performance of a neuro-adaptive Controller," pp. 289-296, Volume 735, Issue 1, November 16, American Institute of Physics conference, 2004.

[7] K. Gundy-Burlet, "Augmentation of an Intelligent Flight Control System for a Simulated C-17 Aircraft," Journal of Aerospace Computing, Information, and Communication, vol. 1, no. 12, pp. 526-542, 2004.

[8] Fisher, SC Smith, and J Burken, "Adaptive Robust Control of an F- 15 Aircraft," American Control Conference, 2004.

[9] C. Papageorgiou and Keith Glover, "Robustness Analysis of Nonlinear Flight Controllers," Vol. 28, No. 4, Journal Of Guidance, Control, and Dynamics, Jul-Aug 2005

[10] D. Bedford, G Morgan, and J Austin, "Requirements for a Standard Certifying the use of Artificial Neural Networks in Safety Critical Applications," International Conference on Artificial Neural Networks, 1996.

- [11] V. Crum, D. Homan, and R. Bortner, "Certification Challenges for Autonomous Flight Control System," AIAA Guidance, Navigation, and Control Conference and Exhibit, Providence, Rhode Island, Aug 2004
- [12] S. Yerramalla, B. Cukic, M. Mladenovski, and E. Fuller, "Stability Monitoring and Analysis of Learning in an Adaptive System," in Proc. of International Conference on Dependable Systems and Networks, 2005
- [13] V. Gazi, K. M. Passino, "Direct Adaptive Control Using Dynamic Structure Fuzzy System", in Proc. of the American Control Conference, 2000
- [14] P. A. Ioannou, P. V. Kokotovic, "Robust Redesign of Adaptive Control" Vol. AC-29, No. 3, IEEE Transaction on Automatic Control, Mar, 1984
- [15] H. C. Tseng, V. H. Hwang, "Servocontroller Tuning with Fuzzy Logic", Vol. I, No. 4, IEEE Transactions on Control Systems Technology, Dec 1993
- [16] S. Yerramalla, B. Cukic, M. Mladenovski, "Stability Monitoring and Analysis of Learning in an Adaptive System", in Proc. of the International Conference on Dependable Systems and Networks, 2005
- [17] A. Nürnberger, D. Nauck, R Kruse, "Neuro-Fuzzy Control Based on the NEFCON-Model Under MATLAB/SIMULINK", University of Magdeburg Institute for Information and Communication Systems, Neural Networks and Fuzzy Systems, Jun 1997
- [18] H. G. Zimmermann, "Advanced Neural Networks in System Identification & Forecasting Safe Modeling by Design," Siemens Corporate technology, 2005
- [19] A. Allen, P. Phattanarsi, K. A. Loparo, F. Soares "ANCT User's Guide," EECS Department, Case Western Reserve University, Contek Research, Inc, CA, 2005
- [20] F. T.Sheldon, A. Mili, "Characterization of Software Quality Assurance Methods: Five Methods for Verification of Learning Systems," Int'l Neural Networks Joint Conference: V&V Workshop Montreal, August 5, 2005
- [21] K. M. Passino, S. Yurkovich, "Fuzzy Control," Addison Wesley Longman, Inc., 1998
- [22] J. J. Burken, F. Soares, "Reconfigurable Flight Control Design using a Robust Servo LQR and Radial Basis Function Neural Network," in conjunction with IJCNN, 2005, International Joint Conference on Neural Networks, Montreal, Canada, August 5th, 2005
- [23] R. D. Fresnedo, "Statistics and the Verification Validation & Testing of Adaptive Systems", M&CT, Phantom Works, The Boeing Company, Aug 2005

- [24] P. Phattanasri, K. A. Loparo, F. Soares, "Verification and Validation of Complex Adaptive Systems," EECS Department, Case Western Reserve University, Contek Research, Inc., April 2005
- [25] S. Piche, "Verification and Validation of Neuro-Adaptive Controllers in the Power Industry", Pegasus Technologies, 2005
- [26] Y. Liu, "Verification and Validation of Online Adaptive Systems", Ph. D Thesis, Dept. of Computer Science and Electrical Engineering, West Virginia University, 2002
- [27] R. Paz, "The Design of the PID Controller", Klipsch School of Electrical and Computer Engineering, June 2001
- [28] A. Mili, B. Cukic, Y. Liu and R.B. Ayed, "Towards the verification and validation of online adaptive systems", accepted for Special Volume of CI in SE, October, 2002.
- [29] I. Sommerville, "Software Engineering", 6th edition, Addison Wesley Publishing Company, Aug 2000
- [30] C. Spitzer, "The Avionics Handbook", CRC Press, December, 2000
- [31] M. A. Pai, "Power System Stability By Lyapunov's method", N.Holland Publishing, 1981
- [32] J. Schumann, S. Nelson, "Toward V&V of Neural Network Based Controllers, WOSS, Charleston, SC, November 2002
- [33] D. M. Rodvold, "A Software Development Process Model for Artificial Neural Networks in Critical Applications", in Proceedings of the 1999 International Joint Conference on Neural Networks. Washington D.C., July 1999
- [34] R. M. Murray, Z. Li, S. S. Sastry, "A Mathematical Introduction to Robotic Manipulation", CRC Press, 1993
- [35] C. Tseng, P. Gupta, J. Schumann, "Analysis of Aircraft Control Performance using a Fuzzy Rule Base Representation of the Cooper-Harper Aircraft Handling Quality Rating" IEEE Aerospace Conference, 4-11 2006
- [36] <http://history.nasa.gov/SP-3300/fig66.htm>
- [37] http://en.wikipedia.org/wiki/Lyapunov_function