

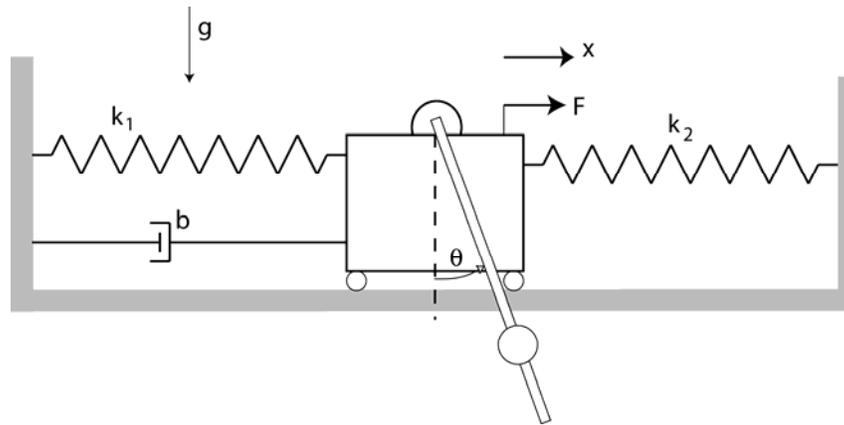
ECE-320: Linear Control Systems
Homework 9a

Due: Tuesday May 17 at 10 AM

Preparation for Lab 10

1) *In this derivation we will make a state variable model for a regular pendulum (a pendulum hanging down) attached to the first cart. It will be easier to measure the parameters for a regular pendulum since it is a stable system. In the lab we will initially try and control the regular pendulum. Once this is working, we will try to control an inverted pendulum. To go from the model of a regular pendulum to the model of an inverted pendulum we use the substitution $l \rightarrow -l$.*

Consider the configuration for the regular pendulum shown below:



The equations of motion for the regular pendulum can be written as

$$\begin{aligned} (J + ml^2)\ddot{\theta} + ml \cos(\theta)\ddot{x} + mgl \sin(\theta) &= 0 \\ (M + m)\ddot{x} + ml\ddot{\theta} \cos(\theta) - ml\dot{\theta}^2 \sin(\theta) + c\dot{x} + kx &= F \end{aligned}$$

The mass of the cart is M , the mass at the center of mass of the pendulum is m , the moment of inertia of the pendulum about its center of mass is J , L is the length of the pendulum, and l is the distance from the pivot to the center of mass of the pendulum. The angle θ is measured counterclockwise from straight up, x is the displacement of the first cart (positive to the right), and g is the gravitational constant.

a) Using a small angle/small velocity assumption, show that we can approximate the above equations of motion as

$$\begin{aligned} (J + ml^2)\ddot{\theta} + ml\ddot{x} + mgl\theta &\approx 0 \\ (M + m)\ddot{x} + ml\ddot{\theta} + c\dot{x} + kx &\approx F \end{aligned}$$

b) We can rewrite the first equation above as

$$\frac{1}{\omega_\theta^2} \ddot{\theta} + \frac{1}{g} \ddot{x} + \theta = 0$$

What is ω_θ^2 ?

c) If we assume the cart is fixed, then $\ddot{x} = 0$ and we have

$$\ddot{\theta} + \omega_\theta^2 \theta = 0$$

This is the equation for a simple pendulum. If the pendulum is deflected a small angle and released, it will oscillate with frequency ω_θ . If we measure the period of the oscillations T_θ how do we find ω_θ ?

d) We can rewrite the second equation from (a) as

$$\frac{1}{\omega_1^2} \ddot{x} + \frac{2\zeta_1}{\omega_1} \dot{x} + x + K_1 \ddot{\theta} = K_2 F$$

Find expressions for ω_1 , ζ_1 , K_1 , and K_2 in terms of m , M , k , and l . If we assume there is no input ($F = 0$) and the pendulum does not move very much ($\ddot{\theta} \approx 0$) then we can use the log-decrement method to get initial estimates of ω_1 and ζ_1 .

e) Assuming we apply a step input of amplitude A to the cart, show that in steady state we get

$$K_2 = \frac{x_{ss}}{A}$$

f) Show that

$$\frac{\Theta(s)}{X(s)} = -\frac{\omega_\theta^2}{g} \left(\frac{s^2}{s^2 + \omega_\theta^2} \right)$$

We need to measure the gravitational constant in cm, since all other distances are measured in cm.

g) Show that

$$\frac{X(s)}{F(s)} = \frac{\omega_1^2 K_2 (s^2 + \omega_\theta^2)}{\left(1 - K_1 \omega_1^2 \frac{\omega_\theta^2}{g} \right) s^4 + (2\zeta_1 \omega_1) s^3 + (\omega_1^2 + \omega_\theta^2) s^2 + (2\zeta_1 \omega_1 \omega_\theta^2) s + \omega_1^2 \omega_\theta^2}$$

We can use this expression to determine K_1 and get better estimates of ω_1 and ζ_1 .

h) We can rewrite our linearized dynamical equations as

$$\begin{aligned}\ddot{\theta} &\approx -\frac{1}{g}\omega_{\theta}^2\ddot{x} - \omega_{\theta}^2\theta \\ \ddot{x} &\approx -2\zeta_1\omega_1\dot{x} - \omega_1^2x - K_1\omega_1^2\ddot{\theta} + K_2\omega_1^2F\end{aligned}$$

By substituting the second equation into the first equation, show that we get

$$\ddot{\theta} \approx \frac{1}{\Delta} \left(\frac{\omega_1^2 \omega_{\theta}^2}{g} \right) x + \frac{1}{\Delta} \left(\frac{2\zeta_1 \omega_1 \omega_{\theta}^2}{g} \right) \dot{x} + \frac{1}{\Delta} (-\omega_{\theta}^2) \theta + \frac{1}{\Delta} \left(-\frac{\omega_1^2 \omega_{\theta}^2 K_2}{g} \right) F$$

where

$$\Delta = 1 - \left(\frac{K_1 \omega_1^2 \omega_{\theta}^2}{g} \right)$$

and substituting the first equation into the second equation we get

$$\ddot{x} \approx \frac{1}{\Delta} (-\omega_1^2) x + \frac{1}{\Delta} (-2\zeta_1 \omega_1) \dot{x} + \frac{1}{\Delta} (K_1 \omega_1^2 \omega_{\theta}^2) \theta + \frac{1}{\Delta} (K_2 \omega_1^2) F$$

i) Defining $q_1 = x$, $q_2 = \dot{x}$, $q_3 = \theta$, and $q_4 = \dot{\theta}$, show that we get the following state equations

$$\begin{bmatrix} \dot{q}_1 \\ \dot{q}_2 \\ \dot{q}_3 \\ \dot{q}_4 \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 & 0 \\ -\left(\frac{\omega_1^2}{\Delta}\right) & -\left(\frac{2\zeta_1 \omega_1}{\Delta}\right) & \left(\frac{K_1 \omega_1^2 \omega_{\theta}^2}{\Delta}\right) & 0 \\ 0 & 0 & 0 & 1 \\ \left(\frac{\omega_1^2 \omega_{\theta}^2}{g\Delta}\right) & \left(\frac{2\zeta_1 \omega_1 \omega_{\theta}^2}{g\Delta}\right) & -\left(\frac{\omega_{\theta}^2}{\Delta}\right) & 0 \end{bmatrix} \begin{bmatrix} q_1 \\ q_2 \\ q_3 \\ q_4 \end{bmatrix} + \begin{bmatrix} 0 \\ \left(\frac{K_2 \omega_1^2}{\Delta}\right) \\ 0 \\ -\left(\frac{\omega_1^2 \omega_{\theta}^2 K_2}{g\Delta}\right) \end{bmatrix} F$$

j) If we now want to model the inverted pendulum ($l \rightarrow -l$ to go back to the inverted pendulum), which terms change in the matrices above?

k) When we try and fit the frequency response data we see in the lab we will often get an unusual response. To understand this response we will analytically try and show what is happening. If you've not screwed up, you should have obtained values of

$$\begin{aligned}K_1 &= \frac{ml}{k} \\ \omega_1^2 &= \frac{k}{M+m} \\ \omega_{\theta}^2 &= \frac{mgl}{J+ml^2}\end{aligned}$$

If we assume that the mass of the cart and pendulum attachment is much larger than the mass at the center of mass of the pendulum, then we have M is much larger than m . Secondly, J is the moment of inertia about the center of mass of the pendulum, m is the mass at the center of mass of the pendulum, and l is the distance from the pivot to the center of mass of the pendulum. For our systems, the pendulum bars have negligible mass and all of the mass is essentially concentrated at the center of mass. Hence ml^2 is much larger than J . Using these two assumptions, show that $\Delta \approx 1$.

1) Assuming $\Delta \approx 1$, show that

$$\frac{X(s)}{F(s)} \approx \frac{\omega_1^2 K_2}{s^2 + 2\zeta_1 \omega_1 s + \omega_1^2}$$

That is, there is a pole/zero cancellation! This is the effect you will often see in lab.

2) Modify (save under a new filename before modifying) the two degree of freedom Simulink model from Lab 9 and corresponding Matlab code to work with the regular pendulum model. (The state model for the regular pendulum is available on the course website.) Specifically, you need to

- Modify the code to access the correct states. Specifically, set

```
get_desired_states = [1 0 0 0 0 0 0;
                    0 1 0 0 0 0 0;
                    0 0 0 0 0 1 0;
                    0 0 0 0 0 0 1];
```
- Rename the output states to be `m_x1`, `m_x1_dot`, `m_theta`, `m_theta_dot`
- Plot the position of the cart, the velocity of the cart, the position of the pendulum, and the velocity of the pendulum. All plots should be neatly organized on one page.
- Set the input of the system to zero (this is a regulator problem, in that we are just trying to hold the pendulum in place)
- The output of the system is the position of the pendulum, so modify the C vector accordingly.
- Set the initial value of the pendulum to 0.05 radians and all other initial conditions to zero.
- Utilize the linear quadratic regulator or pole placement method to control the position of the pendulum and the cart. The goal is to keep the pendulum pointing straight down and keep the cart from moving more than about 2.5 cm in each direction. The control effort should also be less than 0.4 and the system should come to steady state in less than 1.0 seconds.

You will need to turn in you plot, your Simulink code, and your Matlab code.

3) Utilize the results of problem 2 to model the inverted pendulum. The only thing you should need to change is the state model. (The state model is available on the course website.) Specifically, you need to

- Set the input of the system to zero (this is a regulator problem, in that we are just trying to hold the pendulum in place)
- Set the initial value of the pendulum to 0.05 radians and all other initial conditions to zero.

- Utilize the linear quadratic regulator or pole placement method to control the position of the pendulum and the cart. The goal is to keep the pendulum pointing straight up and keep the cart from moving more than about 2.5 cm in each direction. The control effort should also be less than 0.4. Limiting the cart motion is usually the most difficult part. Often your controller for the regular pendulum will work for this part too, but not always.

You will need to turn in you plot for this part.