Smart Control Algorithm for 2-DOF Helicopter

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Outline

Introduction

- Helicopter are important for short-distance travel
  - air-sea rescue
  - fire fighting
  - traffic control
  - tourism
- Purpose of control system
  - resistance to turbulence
  - enable use of mobile device
- Which is better?
  - Fundamental (LQR)
  - Noise Filtering (LQG)
  - Machine Learning (ADP)

Introduction

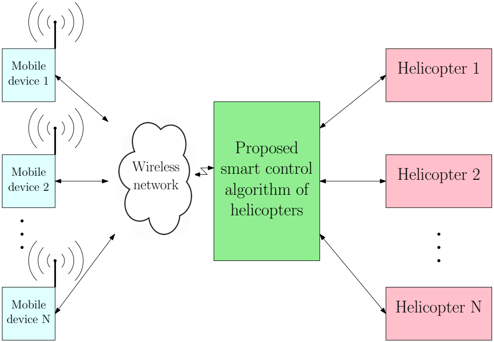

Figure 1: General High-Level System Architecture

Introduction

- This project will:
  - use a pair of 2-DOF (2-degrees-of-freedom) testing platforms
  - implement control algorithms on embedded system
  - use mobile device for user control
  - encourage research
  - serve as an educational tool

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Various control techniques have been proposed for 2-DOF helicopters such as:

- Sliding mode control [?]
- Fuzzy Logic control [?] [?] [?]
- Data-driven Adaptive Optimal Output-feedback control [?]
- Decentralized discrete-time neural control [?]

These control techniques employ advanced mathematics that are difficult to implement on embedded systems.

Outline

Background Study
Modeling a 2-DOF Helicopter

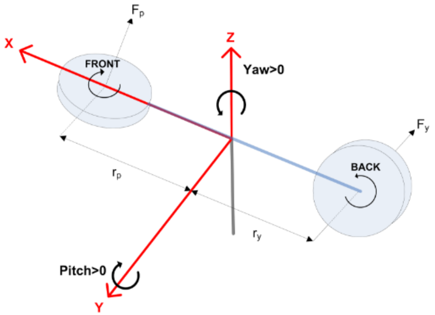

Figure 2: Model of a 2-DOF Helicopter

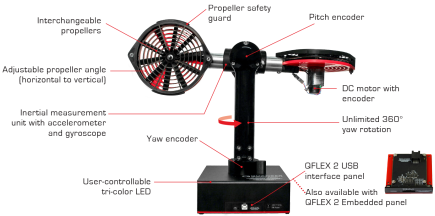

Figure 3: Quanser Aero

- Characterized by fixed base
  - Can change 2 of 3 possible orientations...
    - Pitch (θ)
    - Yaw (ψ)
    - *Not Roll*
  - and cannot change position
    - x direction
    - y direction
    - z direction

- Motors are attached to the propellers to create thrust due to air resistance
  - Main - changes pitch angle
  - Tail - changes yaw angle
- Torque due to rotation also creates a force on opposite axes

$$\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t), \text{ where} \tag{1}$$

$$\mathbf{A} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ -\frac{K_{sp}}{J_p} & 0 & -\frac{D_p}{J_p} & 0 \\ 0 & 0 & 0 & -\frac{D_y}{J_y} \end{bmatrix} \text{ and } \mathbf{B} = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ \frac{K_{pp}}{J_p} & \frac{K_{py}}{J_p} \\ \frac{K_{yp}}{J_y} & \frac{K_{yy}}{J_y} \end{bmatrix},$$

- K_{sp} - being the stiffness of the axes
- K_{pp} - pitch motor thrust constant
- K_{py} - thrust constant acting on the pitch angle from the yaw motor
- K_{yp} - thrust constant acting on the yaw angle from the pitch motor
- K_{yy} - yaw motor thrust constant
- J_p - moment of inertia about pitch axis
- J_y - moment of inertia about yaw axis
- D_p - viscous damping of the pitch axis
- D_y - viscous damping of the yaw axis

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- extensive modeling & simulations
- implementation of two motion control algorithms (LQR & ADP)
- one helicopter

Outline

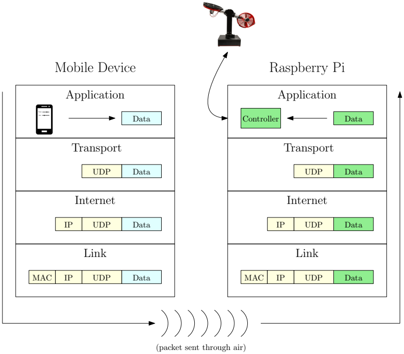


Figure 4: Communication Model

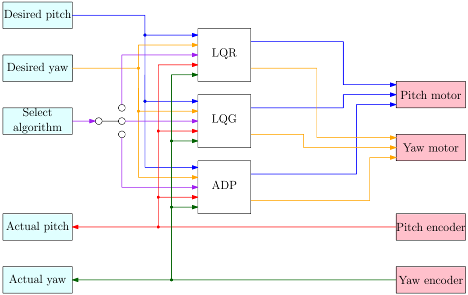
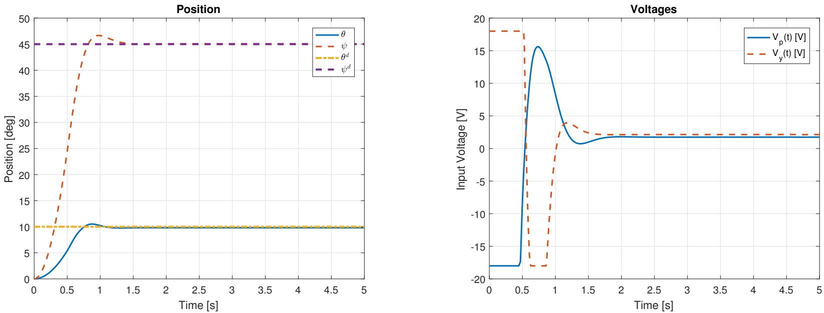


Figure 5: Low Level Smart Control Diagram

Outline



(a) (b)

Figure 6: LQR Simulation (a) Position and (b) Voltage w/ Step Input

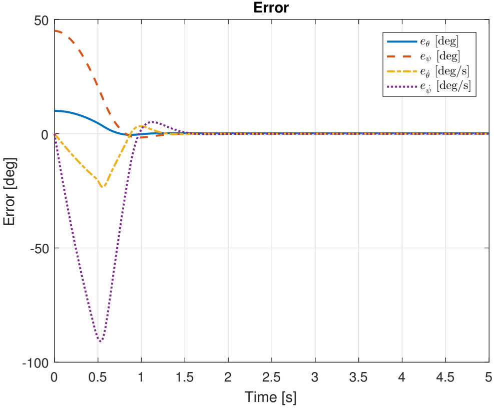


Figure 7: LQR Simulation Error w/ Constant Signal

Simulation
LQR Simulation (PI Controller)

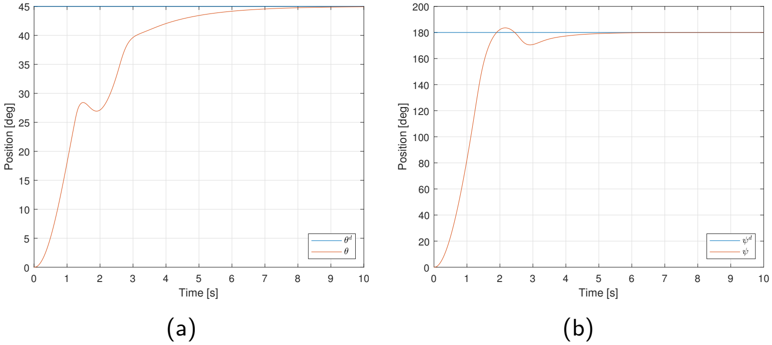


Figure 8: LQR Simulation (PI Controller) (a) Pitch Position and (b) Yaw Position w/ Step Input

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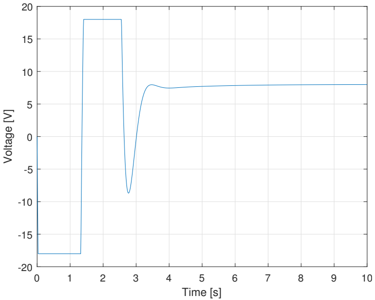
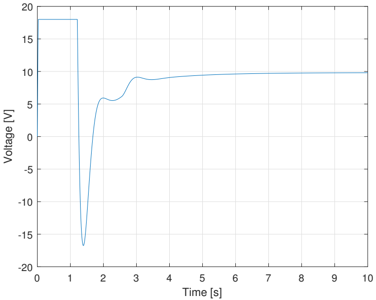


(a)



(b)

Figure 9: LQR Simulation (PI Controller) (a) Pitch Voltage and (b) Yaw Voltage w/ Step Input

Outline

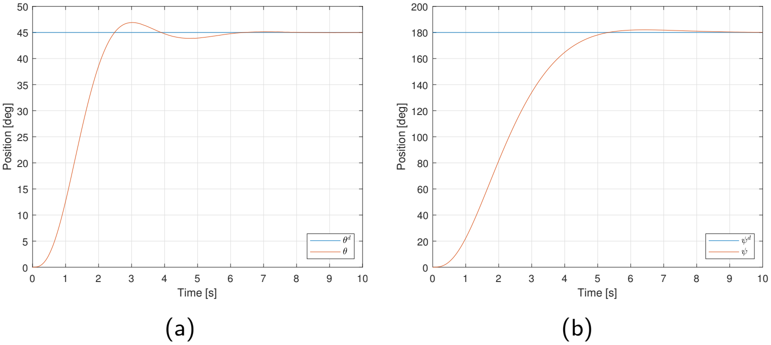
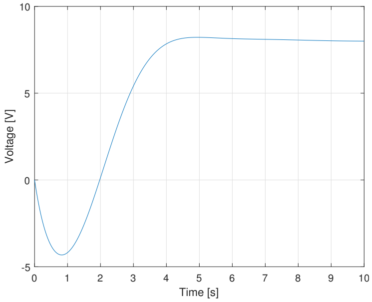
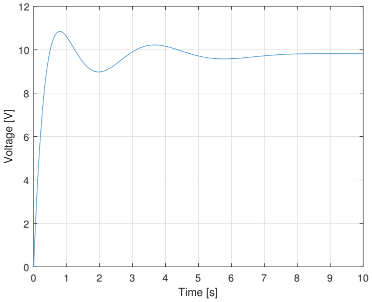


Figure 10: LQG Simulation (PI Controller) (a) Pitch Position and (b) Yaw Position w/ Step Input



(a)



(b)

Figure 11: LQR Simulation (PI Controller) (a) Pitch Voltage and (b) Yaw Voltage w/ Step Input

Outline

Demonstration

Parts List

- Hardware
  - Two Quanser Aeros
    - Q-flex2 Embedded Panel
  - Two Single Board Computers (Raspberry Pi 3 Model B)
  - Android Smart-phone or Tablet
    (Note that Apple devices could also be used, however modifications are needed)
- Software
  - MATLAB & Simulink
    - Raspberry Pi Support Package
    - Android Support Package
  - Quanser Real-Time Control (QUARC)

Future Directions

- Digital Compass
- Enhanced Smart Control
- Implmentation on 6-DOF Helicopter

Summary

- Embedded implementation of control algorithms
- Mobile interface
- PI control improves steady-state error
- ADP is best when system parameters are unknown or time-varient

For Further Reading I