

Contents

- Problem 1
- GENERATE TRAJECTORY Problem 2
- Implement the inverse dynamic control Problem 3
- Plotting the result: please plot both the actual trajectory and the desired trajectory for the your states. example code below.
- With different initial condition
- Bonus problem
- With different initial condition

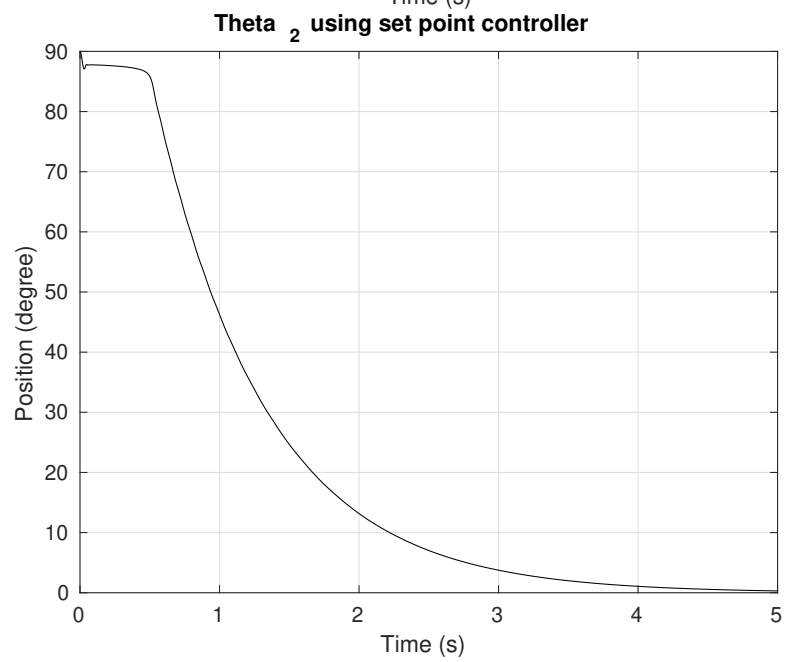
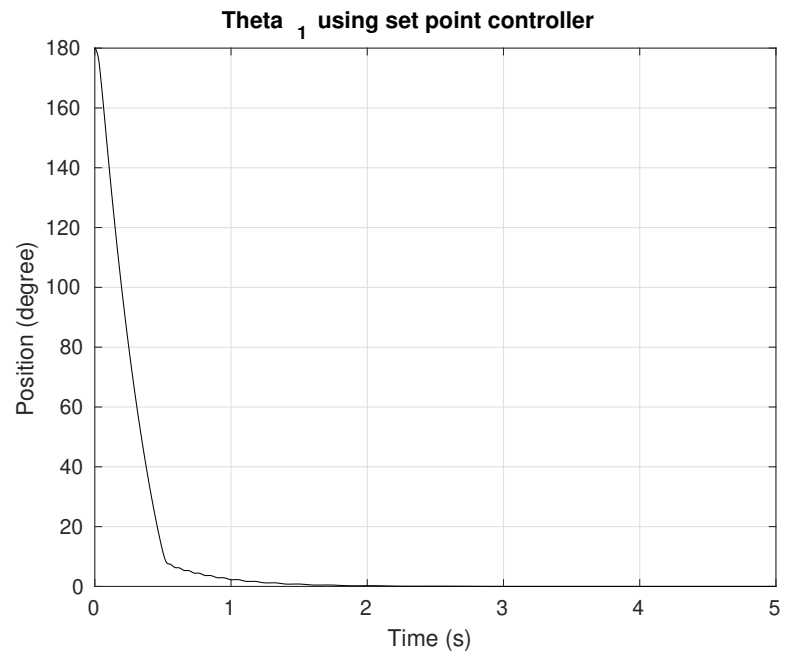
```
%%Farid Tavakkolmoghaddam
clc
clear all;
close all;
% the following parameters for the arm
I1=10; I2 = 10; m1=5; r1=.5; m2=5; r2=.5; l1=1; l2=1;
g=9.8;

% we compute the parameters in the dynamic model
a = I1+I2+m1*r1^2+ m2*(l1^2+ r2^2);
b = m2*l1*r2;
d = I2+ m2*r2^2;
```

Problem 1

```
%initial state
tt0=0;
qq0=[pi*180/pi pi/2*180/pi 0 0];
% final state
ttf=5; % time span is 10 seconds
qqf=[0 0 0 0];
options = odeset('RelTol',1e-4,'AbsTol',[1e-4, 1e-4, 1e-4, 1e-4]);
[T0,X0] = ode45(@(t,x) feedback(t,x),[tt0 ttf],qq0, options);
figure('Name','Theta_1 using set point controller');
plot(T0, X0(:,1),'k');
title('Theta_1 using set point controller')
xlabel('Time (s)')
ylabel('Position (degree)')
grid on
hold on
figure('Name','Theta_2 using set point controller');
plot(T0, X0(:,2),'k');
title('Theta_2 using set point controller')
xlabel('Time (s)')
ylabel('Position (degree)')
grid on
```

hold on



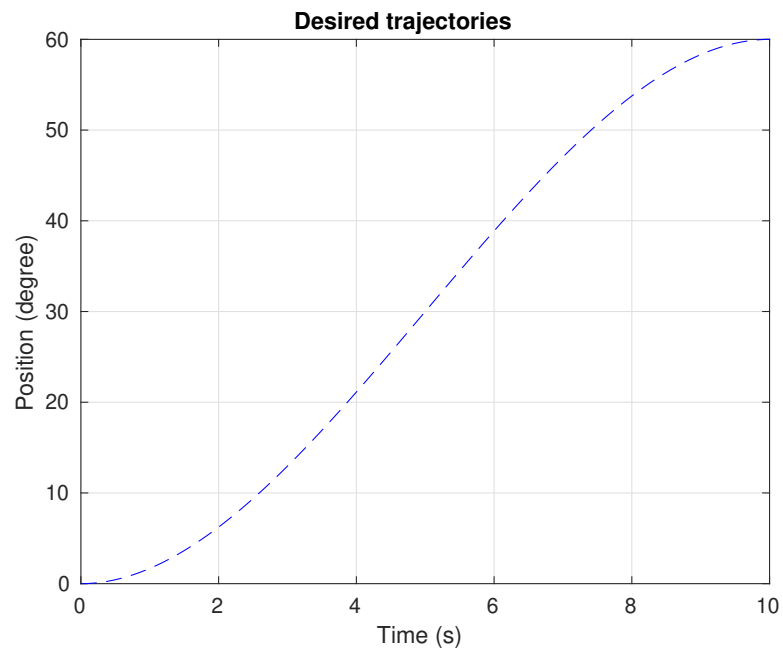
GENERATE TRAJECTORY Problem 2

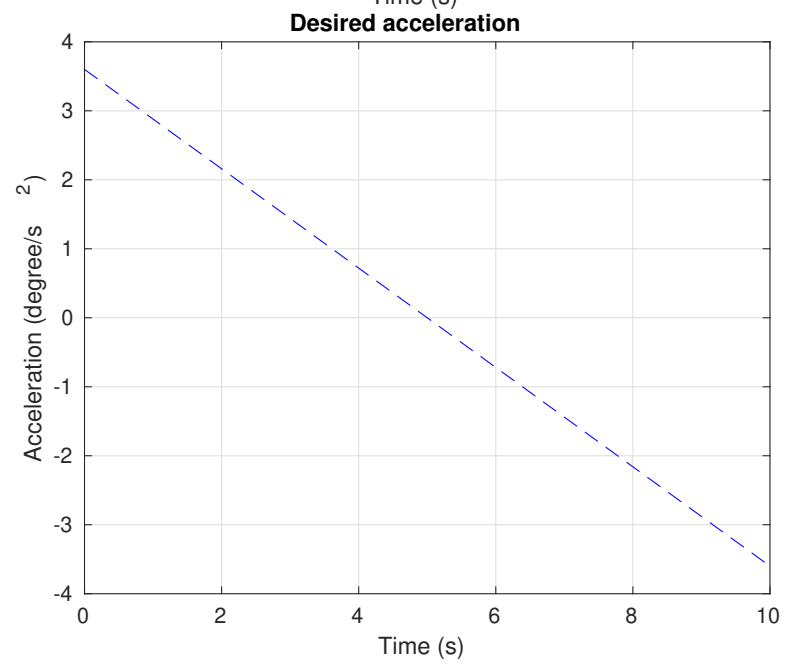
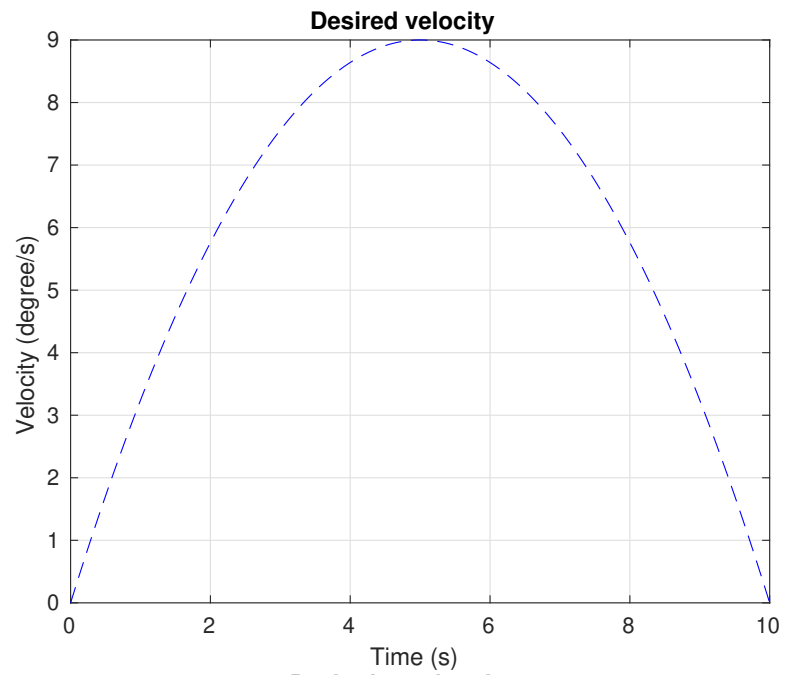
initial state

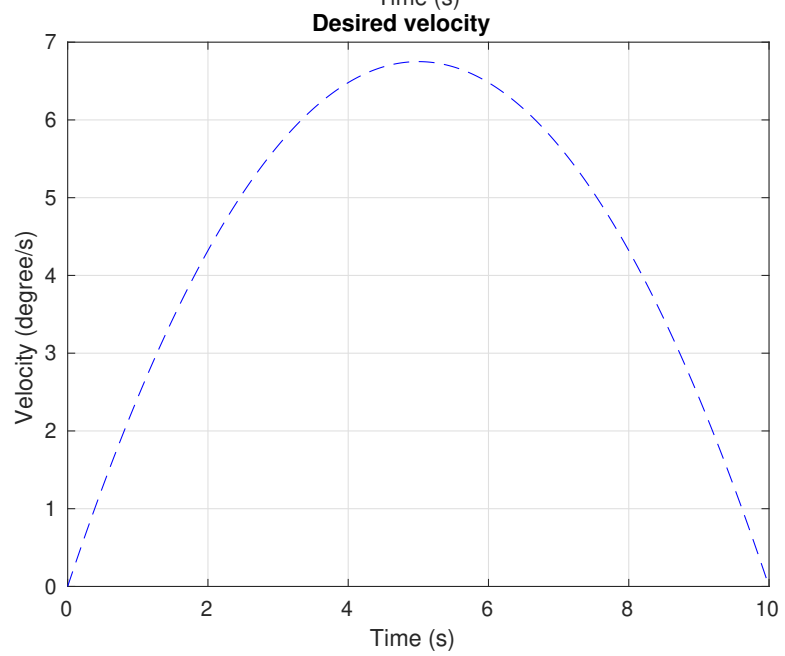
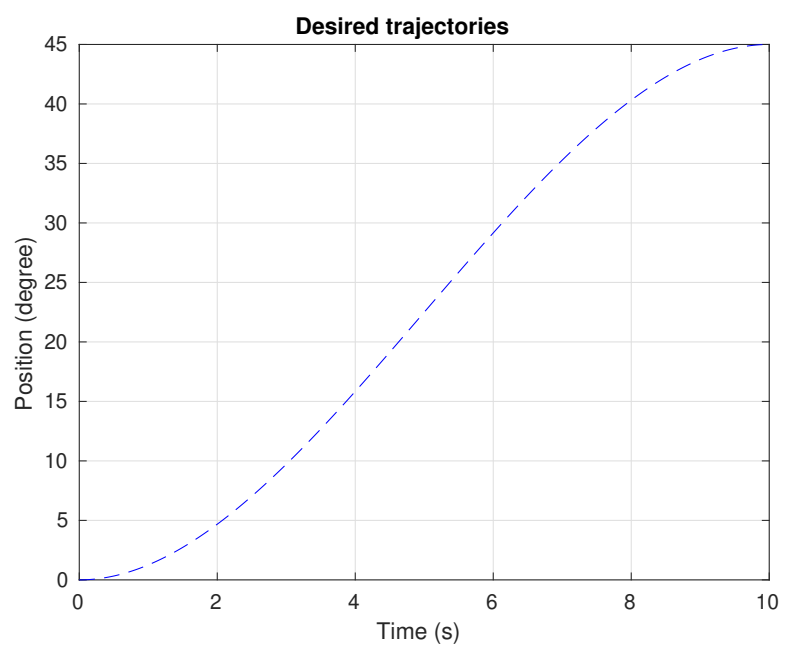
```

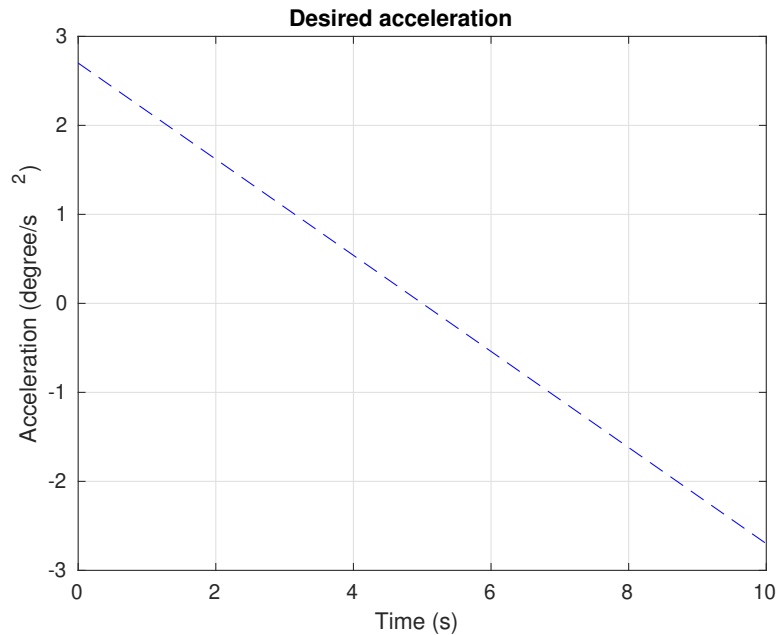
t0=0;
q0=[0 0 0 0];
% final state
tf=10; % time span is 10 seconds
qf=[pi/3*180/pi pi/4*180/pi 0 0];
% generating the desired trajectory based on the initial and terminal
% state conditions
[link1,position1,velocity1,t]= TrajectoryGenerator( q0(1), q0(3), qf(1), qf(3),t0,tf);
[link2,position2,velocity2,t]= TrajectoryGenerator( q0(2), q0(4), qf(2), qf(4),t0,tf);

```









Implement the inverse dynamic control Problem 3

```
integral_term=false; % this is used for using the integration term for the controller
options = odeset('RelTol',1e-4,'AbsTol',[1e-4, 1e-4, 1e-4, 1e-4]);
[T,X] = ode45(@(t,x) inverseDC(t,x,link1,link2,integral_term),[0 tf],q0, options);
[T1,X1] = ode45(@(t,x) inverseDC(t,x,link1,link2,integral_term),[0 tf],[15 15 2 1.5], options);
```

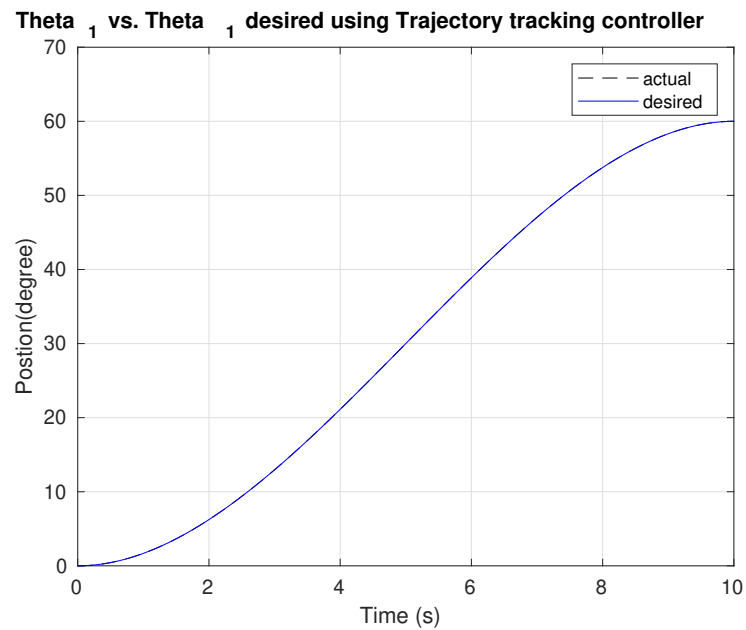
Plotting the result: please plot both the actual trajectory and the desired trajectory for the your states. example code below.

```
figure('Name','Theta_1 under inverse dynamic control');
plot(T, X(:,1),'k--',t,position1,'b');
title('Theta_1 vs. Theta_1 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Postion(degree)')
grid on
legend('actual','desired')
hold on
figure('Name','Theta_2 under inverse dynamic control');
plot(T, X(:,2),'k--',t,position2,'b');
title('Theta_2 vs. Theta_2 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Postion(degree)')
grid on
```

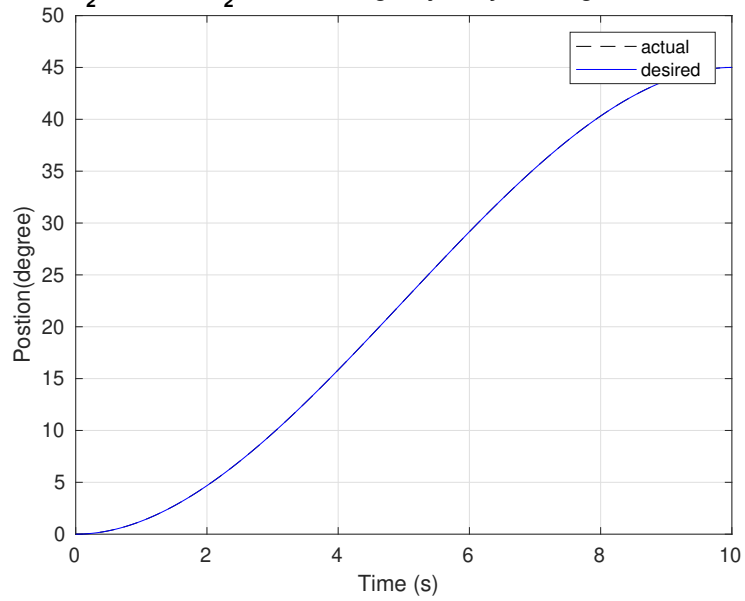
```

legend('actual','desired')
hold on
% Plotting the Deired velocity Vs. Actual velocity
figure('Name','dTheta_1 vs. dTheta_1 desired under inverse dynamic control');
plot(T, X(:,3),'k--',t,velocity1,'b');
title('dTheta_1 vs. dTheta_1 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Velocity(degree/s)')
legend('actual','desired')
grid on
hold on
figure('Name','Theta_2 under inverse dynamic control');
plot(T, X(:,4),'k--',t,velocity2,'b');
title('dTheta_2 vs. dTheta_2 desired using Trajectory tracking controller')
xlabel('Time (s)')
legend('actual','desired')
ylabel('Velocity(degree/s)')
grid on
hold on

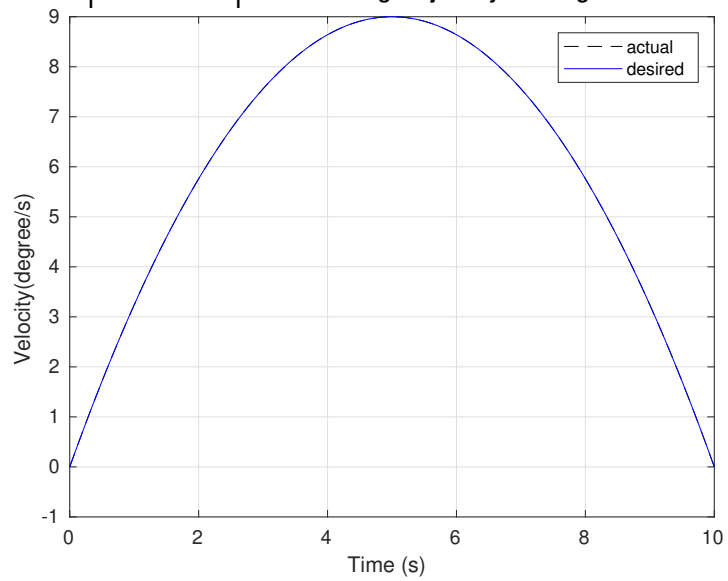
```

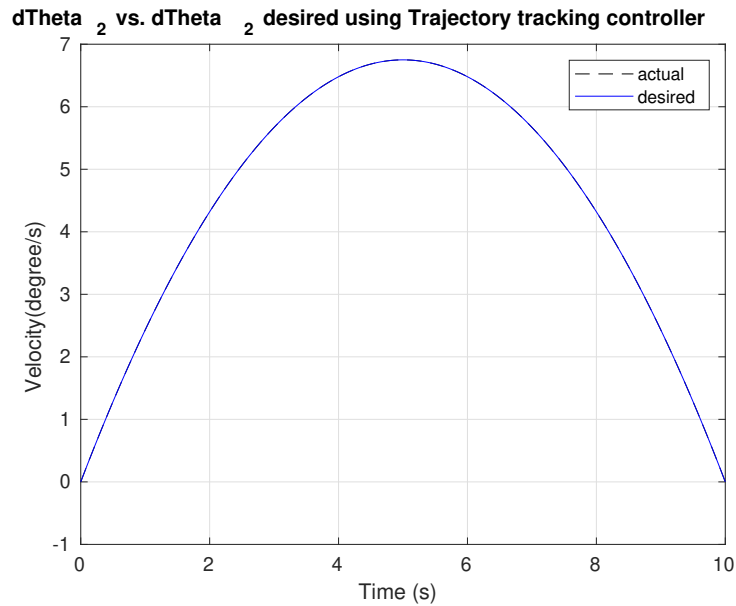


Theta₂ vs. Theta₂ desired using Trajectory tracking controller



dTheta₁ vs. dTheta₁ desired using Trajectory tracking controller





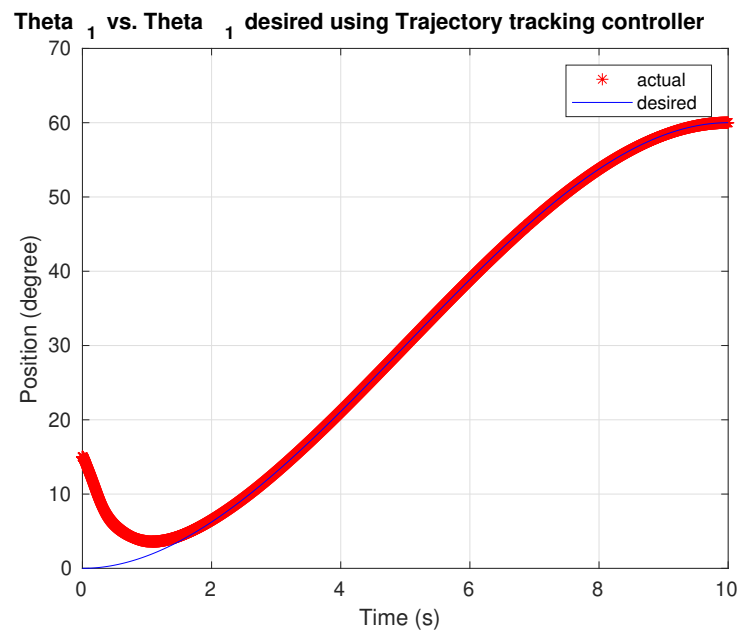
With different initial condition

```
figure('Name','Theta_1 under inverse dynamic control');
plot(T1, X1(:,1),'r*',t,position1,'b');
title('Theta_1 vs. Theta_1 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Position (degree)')
legend('actual','desired')
grid on
hold on
figure('Name','Theta_2 under inverse dynamic control');
plot(T1, X1(:,2),'r*',t,position2,'b');
title('Theta_2 vs. Theta_2 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Position (degree)')
grid on
legend('actual','desired')
hold on
%
% Plotting the Deired velocity Vs. Actual velocity
figure('Name','Theta_1 under inverse dynamic control');
plot(T1, X1(:,3),'k--',t,velocity1,'b');
title('dTheta_1 vs. dTheta_1 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Velocity(degree/s)')
legend('actual','desired')
```

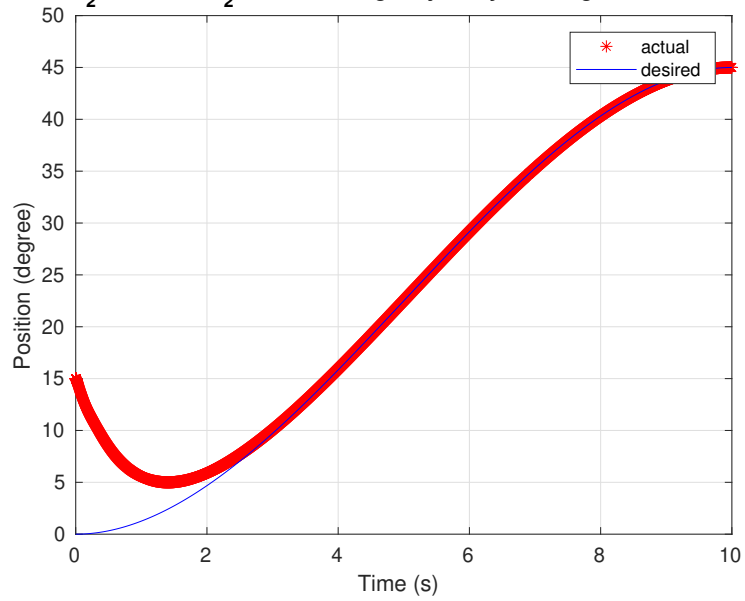
```

grid on
hold on
figure('Name','Theta_2 under inverse dynamic control');
plot(T1, X1(:,4),'k--',t,velocity2,'b');
title('dTheta_2 vs. dTheta_2 desired using Trajectory tracking controller')
xlabel('Time (s)')
ylabel('Velocity(degree/s)')
legend('actual','desired')
grid on
hold on

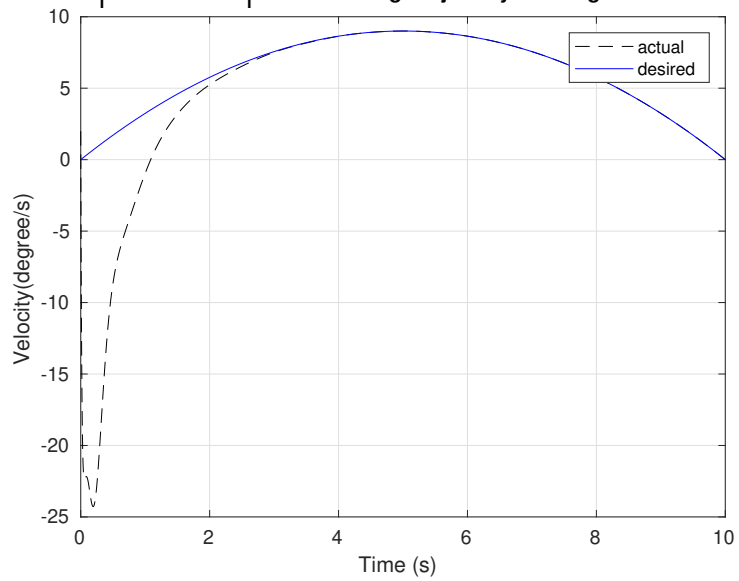
```

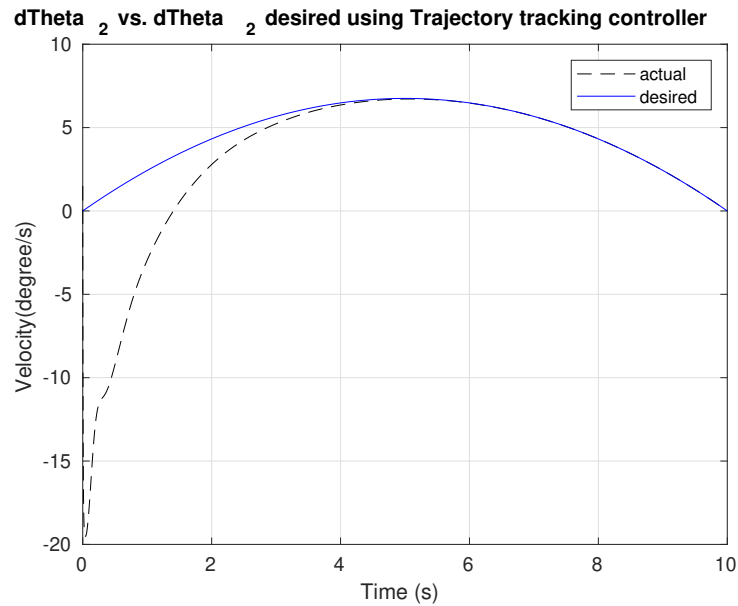


Theta₂ vs. Theta₂ desired using Trajectory tracking controller



dTheta₁ vs. dTheta₁ desired using Trajectory tracking controller

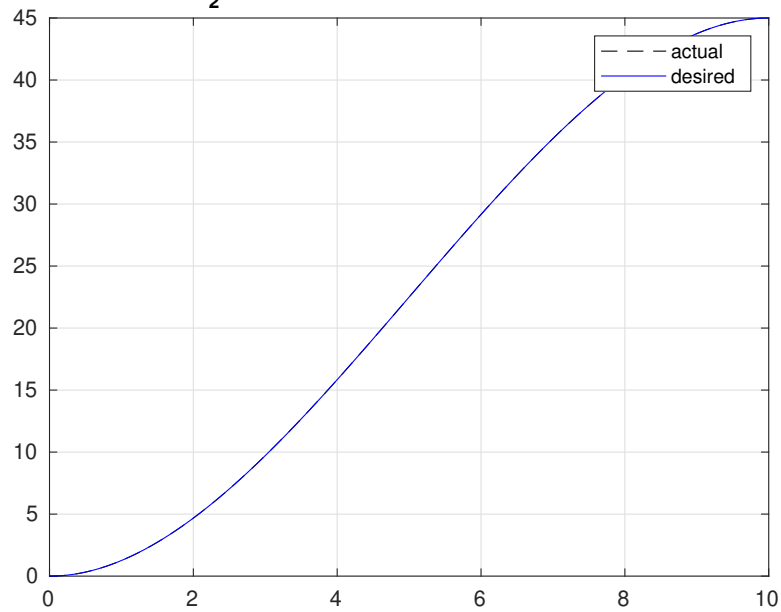
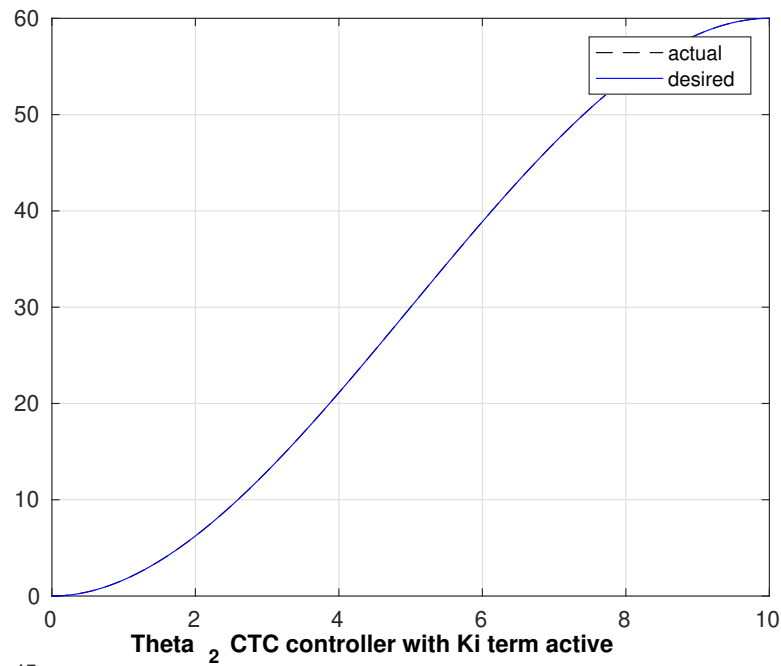




Bonus problem

setting the integration term to true so that we could enable the integration in the controller feedback.

```
integral_term=true;
options = odeset('RelTol',1e-4,'AbsTol',[1e-4, 1e-4, 1e-4, 1e-4]);
[T2,X2] = ode45(@(t,x) inverseDC(t,x,link1,link2,integral_term),[0 tf],q0, options);
figure('Name','Theta_1 under inverse dynamic control');
title('Theta_1 CTC controller with Ki term active')
plot(T2, X2(:,1),'k--',t,position1,'b');
legend('actual','desired')
grid on
hold on
figure('Name','Theta_2 under inverse dynamic control');
plot(T2, X2(:,2),'k--',t,position2,'b');
title('Theta_2 CTC controller with Ki term active')
legend('actual','desired')
grid on
hold on
```



With different initial condition

```
options = odeset('RelTol',1e-4,'AbsTol',[1e-4, 1e-4, 1e-4, 1e-4]);
[T3,X3] = ode45(@(t,x) inverseDC(t,x,link1,link2,integral_term),[0 tf],[20 15 1 5], options);
figure('Name','Theta_1 CTC controller with Ki term active');
```

```

plot(T3, X3(:,1),'r*',t,position1,'b');
title('Theta_1 CTC controller with Ki term active')
legend('actual','desired')
xlabel('Time (s)')
ylabel('Position (degree)')
grid on
hold on
figure('Name','Theta_2 CTC controller with Ki term active');
plot(T3, X3(:,2),'r*',t,position2,'b');
title('Theta_2 CTC controller with Ki term active')
legend('actual','desired')
xlabel('Time (s)')
ylabel('Position (degree)')
grid on
legend('actual','desired')
hold on

```

