

# **Zumobot case study**

Control Theory Module

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Homework assignment

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# Chapter 1

## Introduction

One of the most used study cases in Control Theory is the Inverted Pendulum analysis, as it presents an unstable open-loop characteristic but is also possible to stabilize it on a closed-loop configuration.

Here we present the analysis of the Zumobot 32U4, a small robot available in the market. The Zumo 32U4 robot is a complete, versatile robot controlled by an Arduino-compatible ATmega32U4 microcontroller. The Zumo 32U4 robot can be programmed from a computer using any operating system that supports the Arduino environment.

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# Chapter 2

## System Analysis

An inverted pendulum is basically a consistent mass on the ground (usually wheeled), connected through a frictionless joint to a pendulum, so that the pendulum can freely rotate around the joint and fall down by its own weight. The goal in this system is to provide an horizontal force to the mass on the ground with a direction contrary to the inclination of the pendulum with respect to the vertical axis, so that the pendulum holds in its highest position.

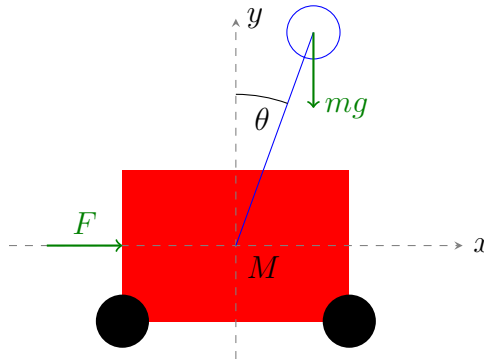


Figure 2.1: Physical representation of the inverted pendulum

The case study in this work is based on a commercial Zumobot 32U4 (See figure 2.2) robot from Pololu manufacturer. It consist on a rigid case that holds 2 brushless DC motors, an Arduino-compatible ATmega32U4 microcontroller and a set of batteries to power up the system. The motors are connected to a belt that rotates between to sets of wheels, sufficiently high to make the Zumobot able to stay in a vertical position without any contact between the case and the ground. The stucture is well suited for an inverted pendulum configuration, considering its physical characteristics and its simple programmability.

The goal position of the Zumobot is a vertical position with respect to the vertical axis. The Zumobot needs to be previously adjusted (frontal sensors holder dismounted), as the frontal part will face the ground, and the posterior part will be held up.

The device includes several helpful sensors and peripherals:

- AVR ATmega 32U4 microcontroller, with 16MHz crystal oscillator.
- Two micrometal gearmotors, driven by on-board TI DRV8838 motor drivers.



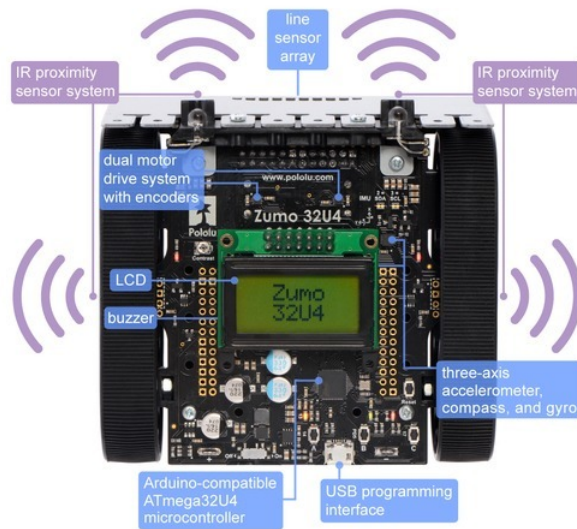


Figure 2.2: Pololu Zumobot

- 3-axis accelerometer + 3-axis gyroscope

To power the motors, the microcontroller generates a PWM digital signal and a direction bit for each wheel (left and right). The Arduino environment provides a library to configure and control the PWM value with low effort. Along with the corresponding firmware, the whole actuator part of the system is complete.

The sensor part of the system uses the accelerometer and gyroscope to provide a value of the angle in the y axis, which is the axis that shows the angle  $\theta$  defined in figure 2.1. The firmware in the Arduino controller gets the value from the



Figure 2.3: Stabilized Zumobot position

# Chapter 3

## Mathematical development

Through the numerous literature is possible to find several approaches to obtain a model for the Inverted Pendulum.

To fully model the dynamic behavior of the zumo robot, we need to consider the equations that govern the movement as rigid body.

TODO: Complete

### 3.1 First approach: Sum of forces

The first approach considered here is described in [Sul03].

#### 3.1.1 Dynamic behavior

The equations of motion are obtained from the sum of forces in the cart for the horizontal direction.

$$F - b \cdot \dot{x} - N = M \cdot \ddot{x} \quad (3.1)$$

Now considering the pendulum itself, the force applied in the horizontal direction due to the momentum of the pendulum is determined as:

$$\tau = r \cdot F = I \cdot \ddot{\theta} \quad (3.2)$$

Given the fact that the moment of inertia of a pendulum of mass  $m$  is defined as  $I = m \cdot L^2$ , the previous equation can be rewritten as:

$$F = \frac{I \cdot \ddot{\theta}}{r} = \frac{m \cdot l^2 \cdot \ddot{\theta}}{l} = m \cdot l \cdot \ddot{\theta} \quad (3.3)$$

Obtaining the component of the force defined in 3.3 in the horizontal direction:

$$F = m \cdot l \cdot \ddot{\theta} \cdot \cos \theta \quad (3.4)$$

Now, the component of the centripetal force acting on the pendulum is similar to the one in 3.3, but the horizontal component of this force is:

$$F = m \cdot l \cdot \dot{\theta}^2 \cdot \sin \theta \quad (3.5)$$

Summing the defined forces present in the horizontal direction of the pendulum in 3.4 and 3.5, we obtain the following expression:

$$N = m \cdot \ddot{x} + m \cdot l \cdot \ddot{\theta} \cdot \cos \theta - m \cdot l \cdot \dot{\theta}^2 \cdot \sin \theta \quad (3.6)$$

Now we can substitute 3.6 into 3.1, we obtain the first equation of motion:

$$F = (M + m)\ddot{x} + b \cdot \dot{x} + m \cdot l \cdot \ddot{\theta} \cdot \cos \theta - m \cdot l \cdot \dot{\theta}^2 \cdot \sin \theta \quad (3.7)$$

To get the second equation of motion, we sum the forces perpendicular to the pendulum. The vertical components of this forces are considered here to get:

$$P \cdot \sin \theta + N \cdot \cos \theta - m \cdot g \cdot \sin \theta = m \cdot l \cdot \ddot{\theta} + m \cdot \ddot{x} \cdot \cos \theta \quad (3.8)$$

To get rid of the  $P$  and  $N$  terms, sum the moments around the center of gravity of the pendulum:

$$-P \cdot l \cdot \sin \theta - N \cdot l \cdot \cos \theta = I \cdot \ddot{\theta} \quad (3.9)$$

Summing up the equations 3.8 and 3.9, we obtain the second equation of movement:

$$(I + m \cdot l^2)\ddot{\theta} + m \cdot g \cdot l \cdot \sin \theta = -m \cdot l \cdot \ddot{x} \cdot \cos \theta \quad (3.10)$$

The obtained equations are non-linear, so they are linearized around the operating point, defined as the top vertical position or  $\pi rad$  from the stable equilibrium position. We need also to define a small angle deviation from the top vertical position, so that  $\theta = \pi + \phi$ .

Under this circumstances, we can deduce that  $\cos \theta \approx -1$ ,  $\sin \theta \approx -\phi$ , and  $\dot{\theta}^2 \approx 0$ . Applying this relations into our movement equations, we obtain:

$$F = (M + m)\ddot{x} + b \cdot \dot{x} - m \cdot l \cdot \ddot{\phi} \quad (3.11)$$

$$(I + m \cdot l^2)\ddot{\phi} - m \cdot g \cdot l \cdot \phi = m \cdot l \cdot \ddot{x} \quad (3.12)$$

To obtain the transfer function of the linearized system of equations analytically, we perform the Laplace transform of the system equations:

$$F(s) = (M + m)s^2 \cdot X(s) + b \cdot s \cdot X(s) - m \cdot l \cdot s^2 \cdot \Phi(s) \quad (3.13)$$

$$(I + m \cdot l^2)s^2 \cdot \Phi(s) - m \cdot g \cdot l \cdot \Phi(s) = m \cdot l \cdot s^2 \cdot X(s) \quad (3.14)$$

To unify the equations, we solve 3.13 for  $X(s)$  and then replace it into 3.14, obtaining:

$$\frac{\Phi(s)}{F(s)} = \frac{m \cdot l \cdot s}{q \cdot s^3 + b(l + m \cdot l^2)s^2 - m \cdot g \cdot l(M + m)s - b \cdot m \cdot g \cdot l} \quad (3.15)$$

Where:

$$q = (M + m)(l + m \cdot l^2) - (m \cdot l)^2 \quad (3.16)$$

Assuming a coefficient of friction as zero, we can represent the equation as:

$$\frac{\Phi(s)}{F(s)} = \frac{K_p}{\frac{s^2}{A_p^2} - 1} \quad (3.17)$$

With:

$$K_p = \frac{1}{(M+m)g}; A_p = \pm \sqrt{\frac{(M+m)m \cdot g \cdot l}{(M+m)(l+m \cdot l^2) - (m \cdot l)^2}} \quad (3.18)$$

### 3.1.2 Actuator system

The actuation mechanism consist on a DC motor that drives a belt sytem around two wheels. The overall transfer function of the actuation mechanism will depend upon the motor and the belt system.

The torque to be delivered by the motor is:

$$T_L = (M+m)r^2\dot{\omega} \quad (3.19)$$

The relation between Torque and Force can be expressed as:

$$T_L \propto r^2; F \propto r \quad (3.20)$$

The motor dynamics can be represented with the well known tansfer function:

$$\omega(s) = K_m \frac{V(s)}{\tau s + 1} \quad (3.21)$$

Where  $\tau$  is the time constant and depends on the load, and  $K_m$  is the steady-state gain of the motor.

$$\frac{F(s)}{E(s)} = K_m \frac{(M+m)r \cdot s}{\tau s + 1} \quad (3.22)$$

## 3.2 Second approach - Euler-Lagrange

To represent the dynamics of the system as in [Jer12] and [Lun02], the initial definition is the natural form of the Lagrangian in classical mechanics:

$$\mathcal{L} = E_k - E_p \quad (3.23)$$

Where  $E_k = \frac{1}{2}mv^2$  and  $E_p = mgh$ . Equation 3.23 can then be rewritten as:

$$\mathcal{L} = \frac{1}{2}mv^2 - mgh \quad (3.24)$$

The Euler-Lagrange equation states that:

$$\frac{d}{dt} \left( \frac{\partial \mathcal{L}}{\partial \dot{\theta}} \right) = \frac{\partial \mathcal{L}}{\partial \theta} \quad (3.25)$$

The pendulum is a stiff bar of lenght L which is supported at one end by a frictionless pin.

TODO: Insert image

From the figure we can state that:

$$\begin{aligned} x &= L \sin \theta & \dot{x} &= L \cos \theta \dot{\theta} \\ y &= L \cos \theta & \dot{y} &= -L \sin \theta \dot{\theta} \end{aligned} \quad (3.26)$$

Velocity is a vector representing the change in the position in the coordinates  $x$  and  $y$ . Hence:

$$v^2 = \dot{x}^2 + \dot{y}^2 \quad (3.27)$$

With the coordinates found in 3.26, we can substitute in 3.27 to obtain:

$$\begin{aligned} v^2 &= L^2 \cos^2 \theta \dot{\theta}^2 + L^2 \sin^2 \theta \dot{\theta}^2 \\ v^2 &= L^2 \dot{\theta}^2 \end{aligned} \quad (3.28)$$

Substituting 3.26 and 3.28 into 3.24, we obtain:

$$\mathcal{L} = \frac{1}{2} m L^2 \dot{\theta}^2 - m g L \cos \theta \quad (3.29)$$

To perform the Euler-Lagrange equation presented in 3.25, we need to compute the partial derivatives. First we compute the left part:

$$\frac{\partial \mathcal{L}}{\partial \theta} = m g L \sin \theta \quad (3.30)$$

Now we compute the inner part of the right element:

$$\frac{\partial \mathcal{L}}{\partial \dot{\theta}} = m L^2 \dot{\theta} \quad (3.31)$$

And now we can compute the outer derivative of 3.31:

$$\frac{d}{dt} \left( \frac{\partial \mathcal{L}}{\partial \dot{\theta}} \right) = m L^2 \ddot{\theta} \quad (3.32)$$

Now that we have all the terms, we can write the equation:

$$\begin{aligned} \frac{d}{dt} \left( \frac{\partial \mathcal{L}}{\partial \dot{\theta}} \right) &= \frac{\partial \mathcal{L}}{\partial \theta} \\ m L^2 \ddot{\theta} &= m g L \sin \theta \\ \ddot{\theta} &= \frac{g}{l} \sin \theta \end{aligned} \quad (3.33)$$

TODO: Insert development of second part of angular acceleration

The total accelerations present on the pendulum can then be stated as:

$$\ddot{\theta} = \ddot{\theta}_g + \ddot{\theta}_x = \left( \frac{g}{l} \right) \sin \theta - \left( \frac{\dot{x}}{l} \right) \cos \theta \quad (3.34)$$

The obtained equation is non-linear, so we apply an approximation based on the fact that the operation point implies an angle  $\theta \approx 0$ . It means that  $\sin \theta \approx \theta$  and  $\cos \theta \approx 1$ . Applying this on 3.34, we obtain:

$$l \ddot{\theta} - g \theta = -\ddot{x} \quad (3.35)$$

To obtain the transfer function, we perform the Laplace transform on 3.35:

$$ls^2\Theta(s) - g\Theta(s) = -s^2X(s) \quad (3.36)$$

Now we solve for the variables  $\Theta$  and  $X$ :

$$ls^2\Theta(s) - g\Theta(s) = -s^2X(s) \quad (3.37)$$

TODO: Complete

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