Chapter Three
Examples

... Don't apply any model until you understand the simplifying assumptions on which it is based, and you can test their validity. Catch phrase: use only as directed. Don't limit yourself to a single model: More than one model may be useful for understanding different aspects of the same phenomenon. Catch phrase: legalize polygamy."

Saul Golomb, "Mathematical Models—Uses and Limitations," 1970 [Gol70].

In this chapter we present a collection of examples spanning many different fields of science and engineering. These examples will be used throughout the text and in exercises to illustrate different concepts. First-time readers may wish to focus on only a few examples with which they have had the most prior experience or insight to understand the concepts of state, input, output and dynamics in a familiar setting.

3.1 Cruise Control

The cruise control system of a car is a common feedback system encountered in everyday life. The system attempts to maintain a constant velocity in the presence of disturbances primarily caused by changes in the slope of a road. The controller compensates for these unknowns by measuring the speed of the car and adjusting the throttle appropriately.

To model the system we start with the block diagram in Figure 3.1. Let v be the speed of the car and v_r the desired (reference) speed. The controller, which typically is of the proportional-integral (PI) type described briefly in Chapter 1, receives the signals v and v_r and generates a control signal u that is sent to an actuator that controls the throttle position. The throttle in turn controls the torque T delivered by the engine, which is transmitted through the gears and the wheels, generating a force F that moves the car. There are disturbance forces F_d due to variations in the slope of the road, the rolling resistance and aerodynamic forces. The cruise controller also has a human–machine interface that allows the driver to set and modify the desired speed. There are also functions that disconnect the cruise control when the brake is touched.

The system has many individual components—actuator, engine, transmission, wheels and car body—and a detailed model can be very complicated. In spite of this, the model required to design the cruise controller can be quite simple.

To develop a mathematical model we start with a force balance for the car body. Let v be the speed of the car, m the total mass (including passengers), F the force generated by the contact of the wheels with the road, and F_d the disturbance force

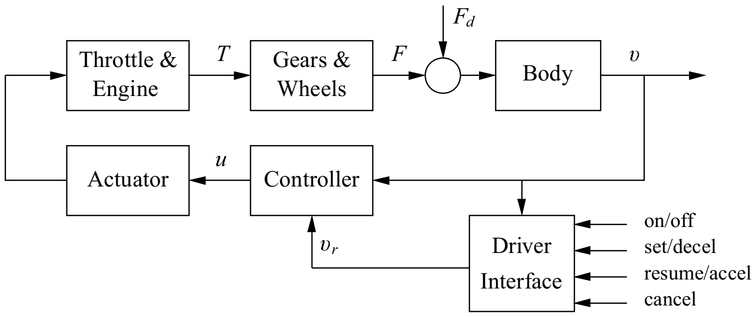

Figure 3.1: Block diagram of a cruise control system for an automobile. The throttle-controlled engine generates a torque T that is transmitted to the ground through the gearbox and wheels. Combined with the external forces from the environment, such as aerodynamic drag and gravitational forces on hills, the net force causes the car to move. The velocity of the car v is measured by a control system that adjusts the throttle through an actuation mechanism. A driver interface allows the system to be turned on and off and the reference speed v_r to be established.

due to gravity, friction and aerodynamic drag. The equation of motion of the car is simply

$$m\frac{dv}{dt} = F - F_d. \tag{3.1}$$

The force F is generated by the engine, whose torque is proportional to the rate of fuel injection, which is itself proportional to a control signal $0 \le u \le 1$ that controls the throttle position. The torque also depends on engine speed ω. A simple representation of the torque at full throttle is given by the torque curve

$$T(\omega) = T_m\left(1 - \beta\left(\frac{\omega}{\omega_m} - 1\right)^2\right), \tag{3.2}$$

where the maximum torque T_m is obtained at engine speed ω_m. Typical parameters are $T_m = 190$ Nm, $\omega_m = 420$ rad/s (about 4000 RPM) and $\beta = 0.4$. Let n be the gear ratio and r the wheel radius. The engine speed is related to the velocity through the expression

$$\omega = \frac{n}{r}v =: \alpha_n v,$$

and the driving force can be written as

$$F = \frac{nu}{r}T(\omega) = \alpha_n u T(\alpha_n v).$$

Typical values of α_n for gears 1 through 5 are $\alpha_1 = 40$, $\alpha_2 = 25$, $\alpha_3 = 16$, $\alpha_4 = 12$ and $\alpha_5 = 10$. The inverse of α_n has a physical interpretation as the *effective wheel radius*. Figure 3.2 shows the torque as a function of engine speed and vehicle speed. The figure shows that the effect of the gear is to "flatten" the torque curve so that an almost full torque can be obtained almost over the whole speed range.

The disturbance force F_d has three major components: F_g, the forces due to

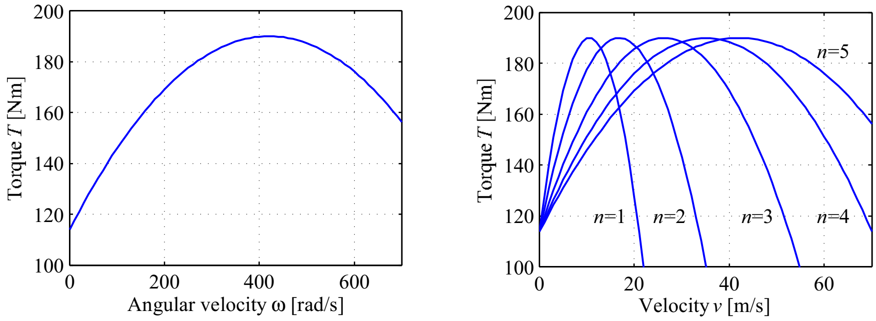

Figure 3.2: Torque curves for typical car engine. The graph on the left shows the torque generated by the engine as a function of the angular velocity of the engine, while the curve on the right shows torque as a function of car speed for different gears.

gravity; F_r, the forces due to rolling friction; and F_a, the aerodynamic drag. Letting the slope of the road be θ, gravity gives the force $F_g = mg \sin\theta$, as illustrated in Figure 3.3a, where $g = 9.8$ m/s^2 is the gravitational constant. A simple model of rolling friction is

$$F_r = mgC_r \operatorname{sgn}(v),$$

where C_r is the coefficient of rolling friction and $\operatorname{sgn}(v)$ is the sign of v (± 1) or zero if $v = 0$. A typical value for the coefficient of rolling friction is $C_r = 0.01$. Finally, the aerodynamic drag is proportional to the square of the speed:

$$F_a = \frac{1}{2}\rho C_d A v^2,$$

where ρ is the density of air, C_d is the shape-dependent aerodynamic drag coefficient and A is the frontal area of the car. Typical parameters are $\rho = 1.3$ kg/m^3, $C_d = 0.32$ and $A = 2.4$ m^2.

Summarizing, we find that the car can be modeled by

$$m\frac{dv}{dt} = \alpha_n u T(\alpha_n v) - mgC_r \operatorname{sgn}(v) - \frac{1}{2}\rho C_d A v^2 - mg\sin\theta, \tag{3.3}$$

where the function T is given by equation (3.2). The model (3.3) is a dynamical system of first order. The state is the car velocity v, which is also the output. The input is the signal u that controls the throttle position, and the disturbance is the force F_d, which depends on the slope of the road. The system is nonlinear because of the torque curve, the gravity term and the nonlinear character of rolling friction and aerodynamic drag. There can also be variations in the parameters; e.g., the mass of the car depends on the number of passengers and the load being carried in the car.

We add to this model a feedback controller that attempts to regulate the speed of the car in the presence of disturbances. We shall use a proportional-integral