Model Documentation of the PVTOL with 2 Forces

1 Nomenclature

1.1 Nomenclature for Model Equations

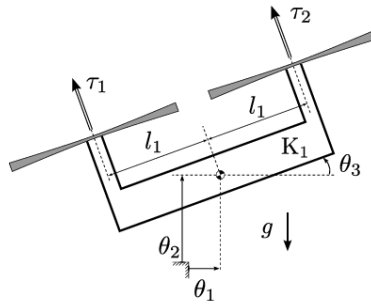|	
x	horizontal displacement
y	vertical displacement
θ	roll angle
F_1, F_2	Forces on the left and right site of the PVTOL
g	acceleration due to gravity
l	distance between mass center of PVTOL and target point of the forces
m	mass of the PVTOL
J	moment of inertia of the PVTOL

1.2 Graphic of the Structure

Figure 1: Structure of the PVTOL Model.
Source: Knoll, Carsten / https://nbviewer.org/github/cknoll/beispiele/
blob/master/senkrechtstarter_pvtol_koordinatentransformation.ipynb

2 Model Equations

State Vector and Input Vector:

$$\underline{x} = (x_1\ x_2\ x_3\ x_4\ x_5\ x_6)^T = (x\ \dot{x}\ y\ \dot{y}\ \theta\ \dot{\theta})^T$$
$$\underline{u} = (u_1\ u_2)^T = (F_1\ F_2)^T$$

Model Equations:

$$\dot{x}_1 = x_2 \tag{1a}$$

$$\dot{x}_2 = -\frac{\sin(x_5)}{m}(u_1 + u_2) \tag{1b}$$

$$\dot{x}_3 = x_4 \tag{1c}$$

$$\dot{x}_4 = \frac{\cos(x_5)}{m}(u_1 + u_2) - g \tag{1d}$$

$$\dot{x}_5 = x_6 \tag{1e}$$

$$\dot{x}_6 = \frac{l}{J}(u_2 - u_1) \tag{1f}$$

Parameters: m, J, l, g
Outputs: x, y, θ

2.1 Assumptions

1. Forces target the body of the PVTOL in a 90° angle.

2.2 Exemplary parameter values

Parametername	Symbol	Value	Unit
acceleration due to gravity	g	9.81	$\frac{m}{s^2}$
distance of forces to mass center	l	0.1	m
mass	m	0.25	kg
moment of inertia	J	0.00076	$kg \cdot m^2$

3 Derivation and Explanation

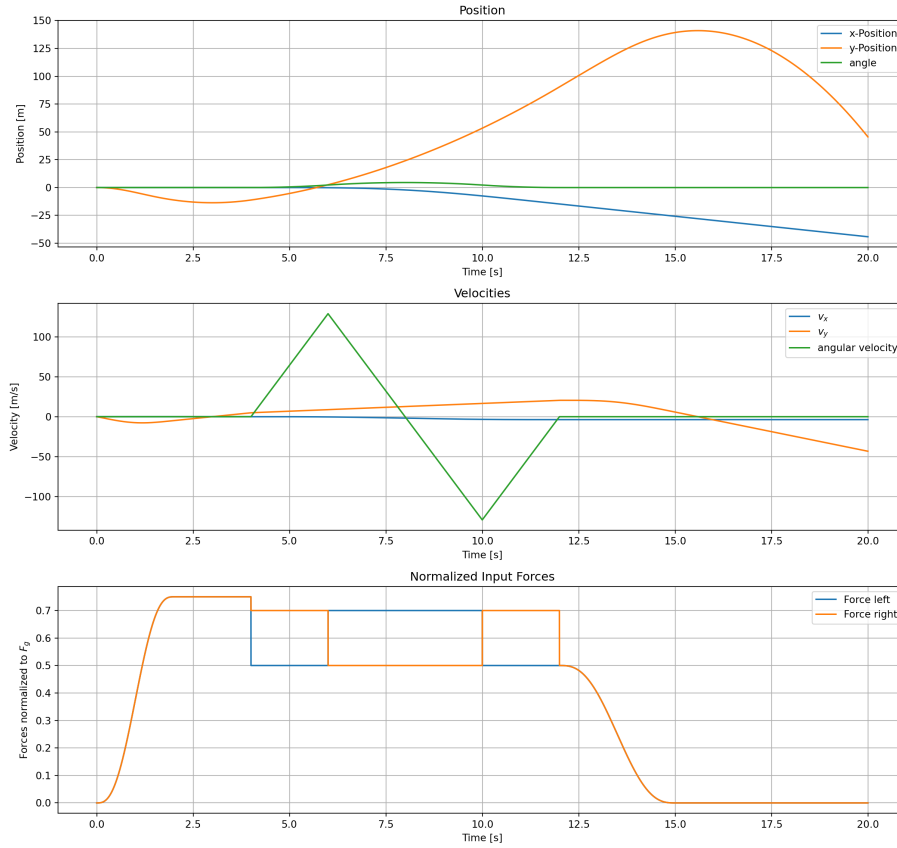The Lagrangian mechanics was used for the solution.

4 Simulation

Figure 2: Simulation of the PVTOL with 2 forces.

References

[1] Knoll, Carsten: *Regelungstheoretische Analyse- und Entwurfsansätze für unteraktuierte mechanische Systeme*, p. 169, TU Dresden, 2016.

[2] Knoll, Carsten: *Senkrechtstarter in der vertikalen Ebene*, Jupyter Notebook published 2016.
https://nbviewer.org/github/cknoll/beispiele/blob/master/senkrechtstarter_pvtol_koordinatentransformation.ipynb