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

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: $x,\ y,\ \theta$

2.1 Assumptions

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

2.2 Exemplary parameter values

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

3 Derivation and Explanation

Not available

References

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