RBE 500 Homework #6

Arjan Gupta

Question 1

Consider the following robot joint model

$$J\ddot{\theta}(t) + B\dot{\theta}(t) = u(t) + d(t)$$

where J is the inertia of the link, B is the effective damping on the link, θ is the joint angle, u is the actuator torque (input), and d is the disturbance acting on the system.

First, assume that disturbance is zero and take $J = 2$, $B = 0.5$. Design a PD controller such that the closed loop system is critically damped, and settling time is 2 second. Do not do this by tuning the gains; calculate the K_p and K_d gains using natural frequency and damping ratio.

Solution

Since $d(t) = 0$, $J = 2$, $B = 0.5$, we have

$$2\ddot{\theta}(t) + 0.5\dot{\theta}(t) = u(t)$$

Transform to Laplace domain,

$$2\Theta(s)s^2 + 0.5\Theta(s)s = U(s)$$
$$\Theta(s)[2s^2 + 0.5s] = U(s) \tag{1}$$
$$\frac{\Theta(s)}{U(s)} = \frac{1}{2s^2 + 0.5s}$$

Let our PD controller model be

$$K_p e + K_d \dot{e} = u$$

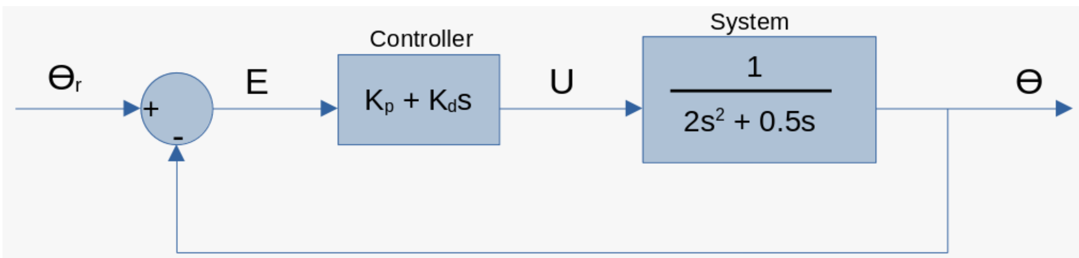
Transform to Laplace domain,

$$K_p E(s) + K_d E(s)s = U(s)$$
$$E(s)[K_p + K_d s] = U(s)$$

Therefore, the transfer function for the PD controller is

$$\frac{U(s)}{E(s)} = K_p + K_d s \tag{2}$$

Now we can draw the block diagram, as shown below.



From the block diagram, we can see that

$$E = \Theta_r - \Theta$$

Using equation 2,

$$\frac{U(s)}{K_p + K_d s} = \Theta_r - \Theta$$

Furthermore, using equation 1,

$$\begin{aligned}
\frac{\Theta(s)[2s^2 + 0.5s]}{K_p + K_d s} &= \Theta_r - \Theta \\
\frac{\Theta[2s^2 + 0.5s]}{K_p + K_d s} + \Theta &= \Theta_r \\
\Theta\left(\frac{2s^2 + 0.5s}{K_p + K_d s} + 1\right) &= \Theta \\
\Theta\left(\frac{2s^2 + 0.5s + K_p + K_d s}{K_p + K_d s}\right) &= \Theta_r
\end{aligned}$$

Therefore,

$$\frac{\Theta}{\Theta_r} = \frac{K_p + K_d s}{2s^2 + s(0.5 + K_d) + K_p}$$

So our charateristic equation is,

$$\begin{aligned}
2s^2 + s(0.5 + K_d) + K_p &= 0 \\
s^2 + s\frac{(0.5 + K_d)}{2} + \frac{K_p}{2} &= 0
\end{aligned}$$

The general form of the charateristic equation is

$$s^2 + (2\xi\omega_n)s + {\omega_n}^2 = 0$$

Where ξ is the damping ratio and ω_n is the natural frequency.

Hence, we have,

$${\omega_n}^2 = \frac{K_p}{2} \tag{3}$$

and

$$2\xi\omega_n = \frac{(0.5 + K_d)}{2} \tag{4}$$

Also, we know that the natural frequency and settling time T_s are related by

$$\xi\omega_n T_s = 4$$

Since we are solving for a critically damped system, we set $\xi = 1$. We also want settling time $T_s = 2$ seconds.

So,

$$\begin{aligned}
\xi\omega_n T_s &= 4 \\
1 \cdot \omega_n \cdot 2 &= 4 \\
\omega_n &= 2
\end{aligned}$$

Plugging this into equation 3, we have

Question 1 continued on next page. . .

$$
\begin{aligned}
(2)^2 &= \frac{K_p}{2} \\
4 &= \frac{K_p}{2} \\
&\boxed{K_p = 8}
\end{aligned}
$$

Also, plugging in values into equation 4, we have

$$
\begin{aligned}
2(1)(2) &= \frac{0.5 + K_d}{2} \\
8 &= 0.5 + K_d \\
&\boxed{K_d = 7.5}
\end{aligned}
$$

Question 2

Follow steps in the assignment PDF file. Explain the process and be sure to include the plot to your report.

Solution

First we write the following MATLAB script that contains the system and controller values of the closed loop system. Here, J is the intertia of the link in the system model, B is the effective damping on the link in the system model, K_p is the proportional gain for the controller, and K_d is the derivative gain for the controller.

```
% Code for Question 2 of HW6 for RBE500

clear; close all; clc;

% System model
J = 2;
B = 0.5;

% Controller
K_p = 8;
K_d = 7.5;
```

Next, we run our script so that the variables are loaded into our base workspace in MATLAB. We then type `simulink` into the MATLAB command window to launch Simulink. Now we use the Library Browser to begin to construct our closed-loop block diagram. Our process is as follows:

- First, we choose the step function as the input block.
- Then we choose gain blocks to construct our PD controller. By double-clicking on the gain blocks, we are able to indicate the variables `K_p` and `K_d` from our base worksapce. In the case of `K_d`, we also add a derivative block before the gain block.
- Now we add a summation block to add these gains.
- Next, we add a transfer function block and write $[J\ B\ 0]$ in the denominator to accurately represent our transfer function.
- Now we connect the output of the controller summation into our system model.
- We can now add a scope to monitor the output of our controlled system. We connect the transfer function output to the scope.
- Now we add a summation after the input, and edit it by double-clicking the summation and making sure it says $| + -$.
- We can now represent our feedback error. For this, we right-click the connector leading to the scope, and draw a line into the minus part of the summation after the input.
- The input is fed into the plus part of the summation right after the input, so we draw that connector.
- Finally, the output of the summation right after the input feeds into our controller.
- Now our closed loop system is ready to run. We click the play button to run the simulation.

- Our plot is now ready, which can be viewed by double-clicking the scope block.

Figure 1 below shows the end-result of the closed loop system we constructed in Simulink.

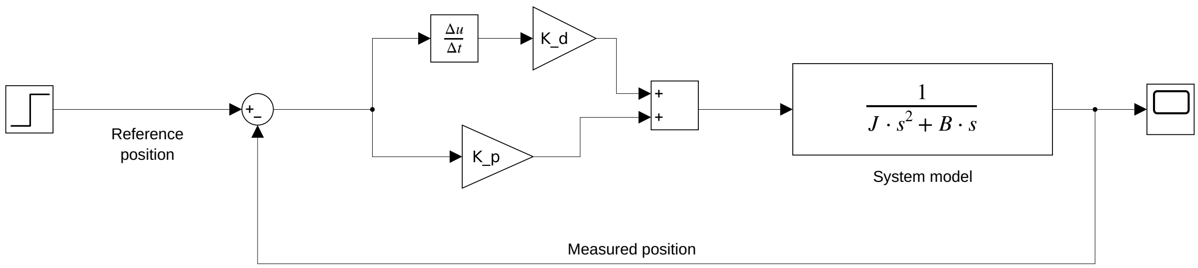


Figure 1: Block diagram for Question 2

After constructing the block diagram, we obtained the following plot (Figure 2).

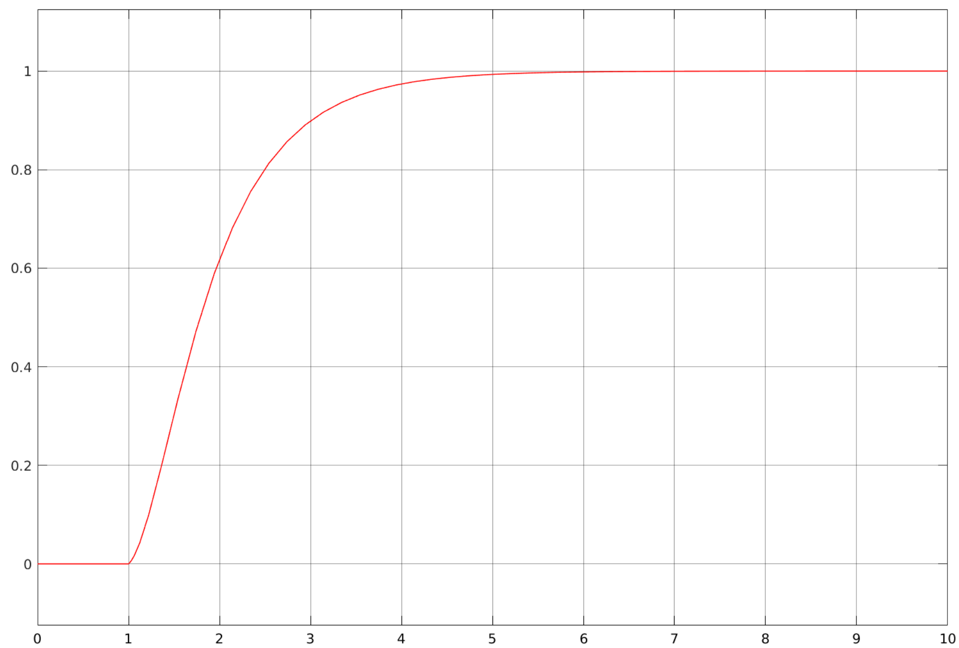


Figure 2: Generated plot for Question 2

Question 3