Modeling 1DoF System

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1   Introduction

This document presents the modeling of a simple 1 degree-of-freedom (DoF) system using Lagrangian mechanics and co-energy analysis. It also provides a method for including a friction model. A Simulink block diagram is also provided for simulation purposes.
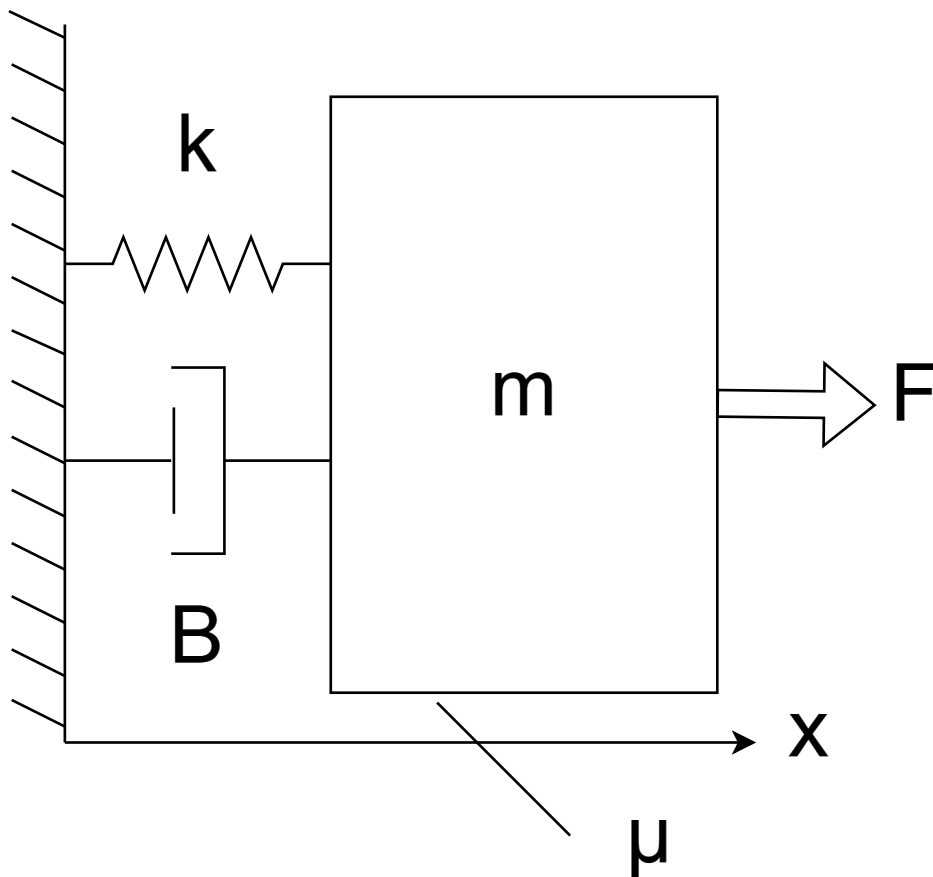
2   1DoF System Description

Figure 1: Overview of the 1DoF system

We consider a 1DoF system in 2 main cases: first, where a plain, frictionless model is presented; second, where friction submodel is included into 1DoF system.

3   Lagrangian Formulation - General Case

The kinetic and potential energies of 1DoF system are defined as:

$$T = \frac{1}{2}m\dot{x}^2$$

$$U = k \int_0^x x\,dx = \frac{1}{2}kx^2$$

The system has a damper, which is a dissipative element:

$$D_B = B \int_0^{\dot{x}} \dot{x}\,dx = \frac{1}{2}B\dot{x}^2$$

Now, we can include the friction model, as it is also a dissipative element:

$$D_\mu = B_\mu \dot{x}$$

In that case, the total dissipation in 1DoF system can be described as:

$$D = \frac{1}{2}B\dot{x}^2 + B_\mu \dot{x}$$

With this approach, we can either define the friction submodel, or equate it to 0.

The Lagrangian of 1DoF system is:

$$\mathcal{L}(x, \dot{x}) = T - U = \frac{1}{2}m\dot{x}^2 - \frac{1}{2}kx^2$$

The Rayleigh dissipation function can be written as:

$$\mathcal{D} = D - P = \left(\frac{1}{2}B\dot{x}^2 + B_\mu \dot{x}\right) - F\dot{x}$$

Using Lagrange's equation with a non-conservative force (damper), the equation expands into the following form:

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right) - \frac{\partial \mathcal{L}}{\partial q} + \frac{\partial \mathcal{D}}{\partial \dot{q}} = 0$$

This leads to the following differential equation:

$$\frac{d}{dt}\left(\frac{\partial\left(\frac{1}{2}m\dot{x}^2 - \frac{1}{2}kx^2\right)}{\dot{x}}\right) - \frac{\partial\left(\frac{1}{2}m\dot{x}^2 - \frac{1}{2}kx^2\right)}{x} + \frac{\partial\left(\left(\frac{1}{2}B\dot{x}^2 + B_\mu \dot{x}\right) - F\dot{x}\right)}{\dot{y}} = 0$$

$$\frac{d}{dt}\left(\frac{\partial\left(\frac{1}{2}m\dot{x}^2 - 0\right)}{\dot{x}}\right) - \frac{\partial\left(0 - \frac{1}{2}kx^2\right)}{x} + \frac{\partial\left(\left(\frac{1}{2}B\dot{x}^2 + B_\mu \dot{x}\right) - F\dot{x}\right)}{\dot{y}} = 0$$

$$\frac{d}{dt}\left(2 \cdot \frac{1}{2}m\dot{x}^{2-1}\right) - \left(-\left(2 \cdot \frac{1}{2}kx^{2-1}\right)\right) + \left(\left(2 \cdot \frac{1}{2}B\dot{x}^{2-1} + \cdot B_\mu \dot{x}^{1-1}\right) - F\dot{x}^{1-1}\right) = 0$$

$$\frac{d}{dt}(m\dot{x}) - (-(kx)) + ((B\dot{x} + B_\mu) - F) = 0$$

$$m\ddot{x} + kx + B\dot{x} + B_\mu - F = 0$$

Sorting yields the equation's final form:

$$m\ddot{x} + B\dot{x} + kx = F - B_\mu$$

4 Co-energy and Energy Expressions

Mass

The general inertia co-energy for mass is:

$$W_m' = W_m = \int_0^v mv'\, dv' = \frac{1}{2}mv^2 = \frac{1}{2}m\dot{x}^2$$

In linear systems, energy and co-energy are equal.

Spring

The general energy stored in the spring k_1 is:

$$W_s' = W_s = \int_0^x kx'\, dx' = \frac{1}{2}kx^2$$

Since the spring is conservative (no energy loss), co-energy equals energy.

Damper and Friction

The general damper dissipates energy as friction:

$$W_d = \int_0^t Bv^2(\tau)\, d\tau = \frac{1}{2}Bv^2 = \frac{1}{2}B\dot{x}^2$$

The general friction dissipates energy in the following manner:

$$W_f = \frac{d}{d\dot{x}}\left[\int_0^{\dot{x}} B_\mu(v)v\, dv\right] = B_\mu(\dot{x})\dot{x} = B_\mu\dot{x}$$

Dampers, as friction, do not store energy, so they do not have co-energy.

Using the co-energy equation with a non-conservative force, we can write:

$$\frac{d}{dt}\left[\frac{\partial T}{\dot{y}}\right] - \frac{\partial T}{y} + \frac{\partial U}{y} + \frac{\partial D}{\dot{y}} = f_i$$

Adjusting the general co-energy expressions to 1DoF systems speciffic configuration gives:

$$W_m = \frac{1}{2}m\dot{x}^2$$

$$W_s = \frac{1}{2}kx^2$$

$$W_d + W_f = \frac{1}{2}B\dot{x}^2 + B_\mu\dot{x}$$

Finally, we can assign the following assumptions:

$$T = W_m$$
$$U = W_s$$
$$D = W_d + W_f$$
$$f_i = F$$

By substituting the coefficients into the equation, we obtain the following:

$$\frac{d}{dt}\left[\frac{\partial\left(\frac{1}{2}m\dot{x}^2\right)}{\dot{x}}\right] - \frac{\partial\left(\frac{1}{2}m\dot{x}^2\right)}{x} + \frac{\partial\left(\frac{1}{2}kx^2\right)}{x} + \frac{\partial\left(\frac{1}{2}B\dot{x}^2 + B_\mu\dot{x}\right)}{\dot{x}} = F$$

$$\frac{d}{dt}\left[\frac{\partial\left(\frac{1}{2}m\dot{x}^2\right)}{\dot{x}}\right] - 0 + \frac{\partial\left(\frac{1}{2}kx^2\right)}{x} + \frac{\partial\left(\frac{1}{2}B\dot{x}^2 + B_\mu\dot{x}\right)}{\dot{x}} = F$$

$$\frac{d}{dt}\left[m\dot{x}\right] + kx + B\dot{x} + B_\mu = F$$

$$m\ddot{x} + B\dot{x} + kx = F - B_\mu$$

5   Simulink Model for Lagrangian and Co-energy Expression

In order to model the equation properly, we must translate the dynamic equation into a form understandable for Simulink:

$$m\ddot{x} + B\dot{x} + kx = F - B_\mu$$

$$\ddot{x} = \frac{1}{m}\left(F - B\dot{x} - kx - B_\mu\right)$$

Before coding the solution in Simulink, we should consider the friction submodel. The most versatile friction model is the Coulomb function:

$$B_\mu = \mu mg \cdot sign\left(\dot{x}\right) + c\dot{x}$$

where:

$$\mu - \text{dry friction coefficient;}$$
$$c - \text{viscous friction coefficient;}$$
$$g - \text{gravitational force;}$$

In the following, the Simulink model is presented.

Figure 2: Simulink model of 1DoF system - general form

Figure 3: Simulink model of 1DoF system - explicitly frictionless

At $\dot{x} = 0$, the sign function has a discontinuity (jump from -1 to +1), and Simulink's solver repeatedly attempts to find the exact zero-crossing time, failing to progress. This causes the 1000 consecutive zero-crossings error. In order to solve the issue, use either:

- smoothing approximation $sign(\dot{x}) \approx \tanh\left(\frac{\dot{x}}{\epsilon}\right)$

- switch function instead of sign.

5

6 Matlab and Python script

For script-based system modeling, we must take a slightly different approach to translating mathematical equations into code. Let $x(t) = x(1)$, $\dot{x}(t) = x(2)$, in that case the matrix of the 1DoF equation will be written as:

$$\frac{d}{dt}\begin{bmatrix} x(1) \\ x(2) \end{bmatrix} = \begin{bmatrix} x(2) \\ \left(F - B \cdot x(2) - k \cdot x(1) - friction\right)/m \end{bmatrix}$$

Now, the equation can be coded into Matlab:

```
Dx = [x(2); (F-B * x(2) - k * x(1) - friction) / m];
```

Python counts matrix elements from 0, so the equivalent Python code can be written as:

```python
def sindle_dof(x, t):
    friction = Mu * m * g * np.sign(x[1]) + c * x[1]
    return x[1], (F - B * x[1] - k * x[0] - friction) / m
```
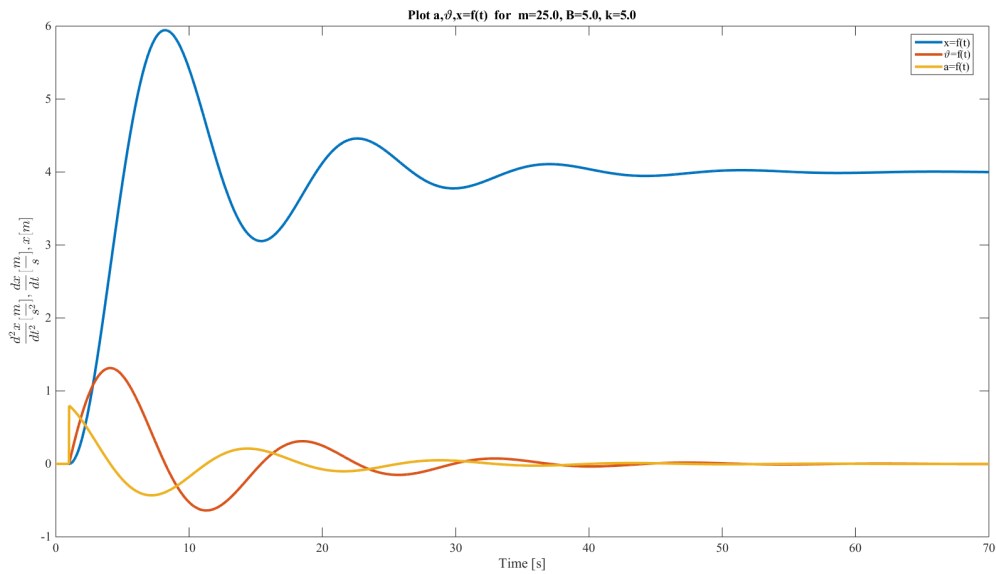
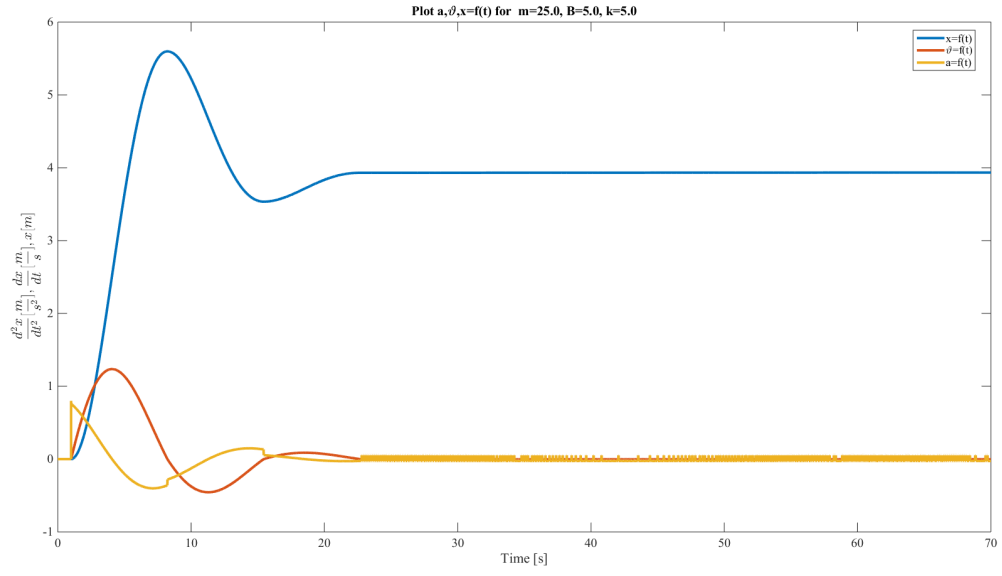# 7 Simulation Results

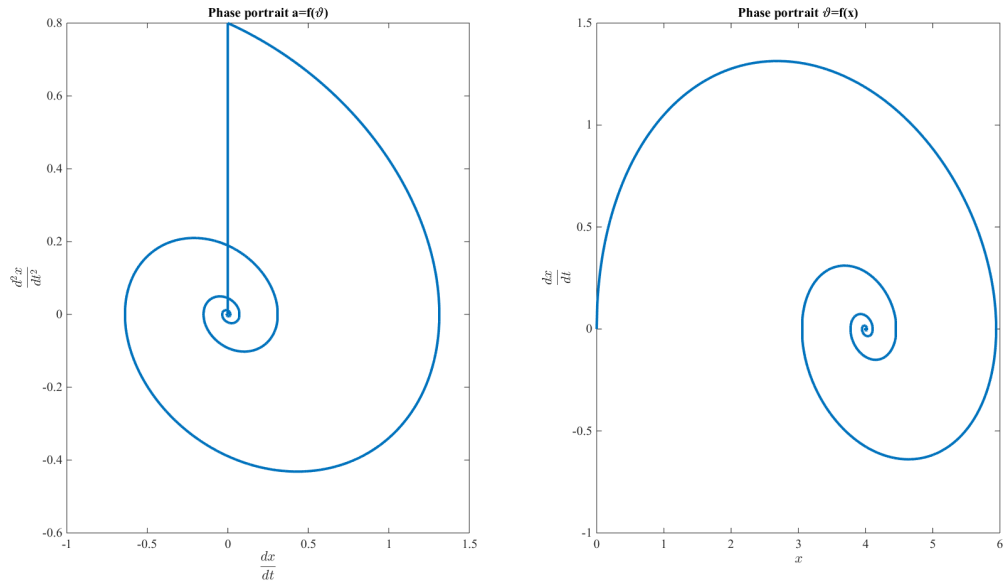Figure 4: Result without friction

Figure 5: Result with friction
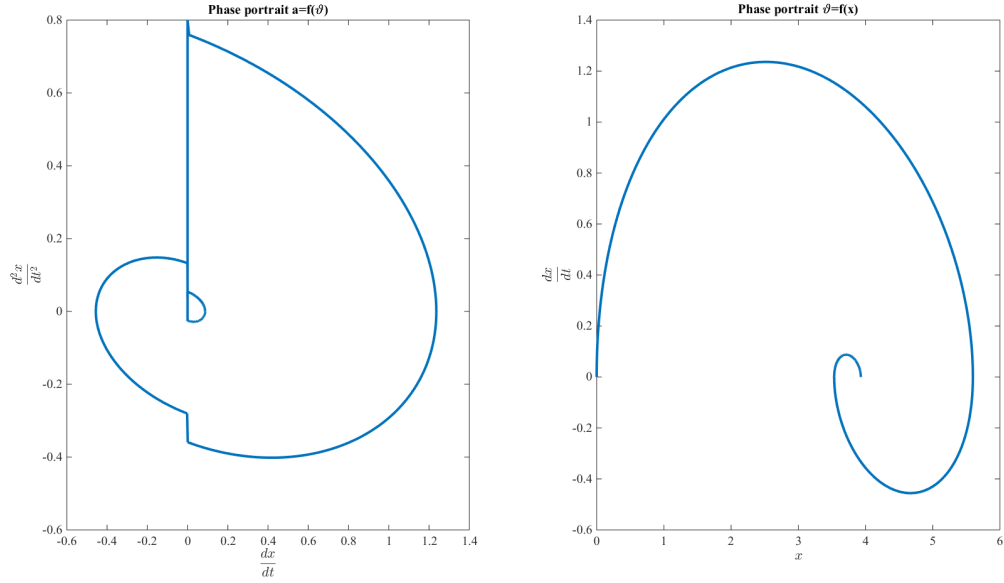

Figure 6: Phase portrait without friction

Figure 7: Phase portrait with friction

8 Conclusion

This document demonstrates the Lagrangian and co-energy approach to modeling a 2DoF system. It also provides a visual block diagram suitable for simulation in Simulink and basic code for scripting.