# 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

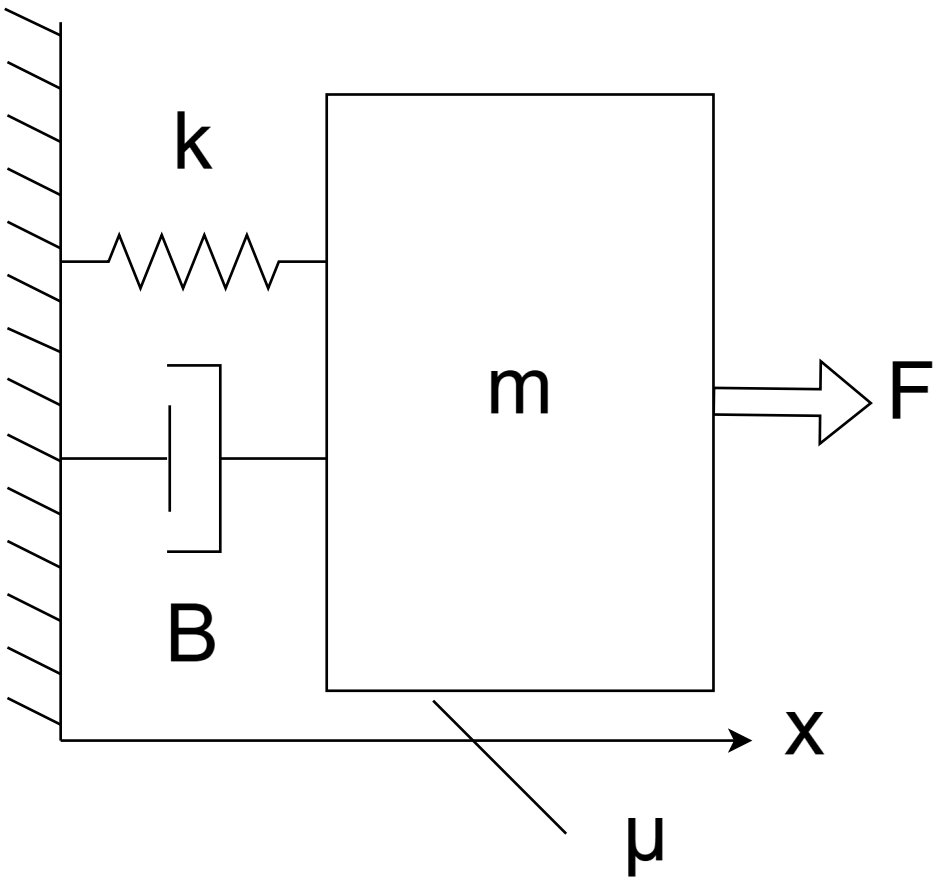


Figure 1: Overview of the 1DoF system

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:

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

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

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

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

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

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.

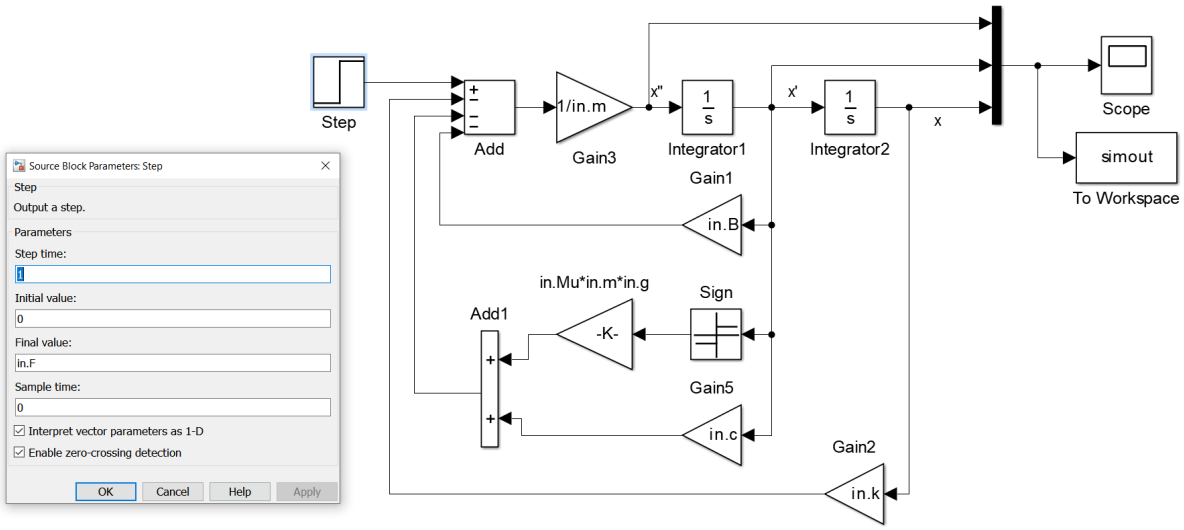


Figure 2: Simulink model of 1DoF system - general form

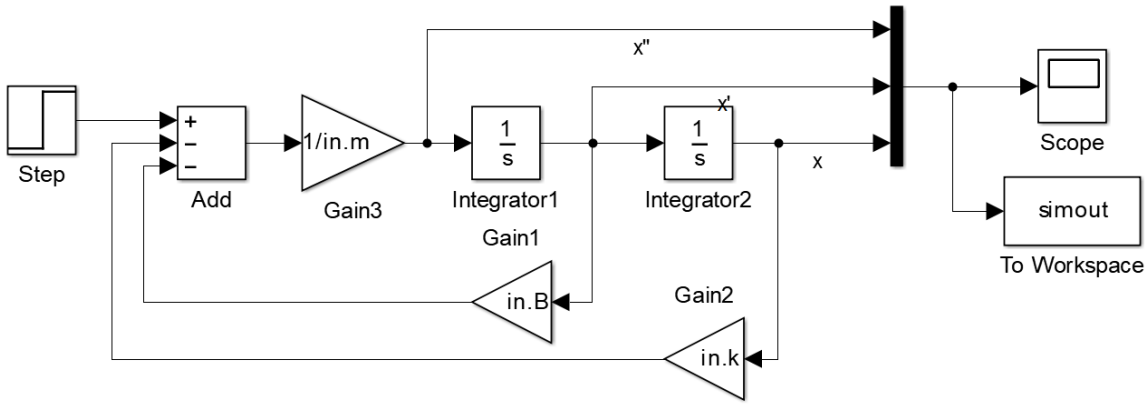


Figure 3: Simulink model of 1DoF system - explicitly frictionless

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.

# 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:

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

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:

```
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

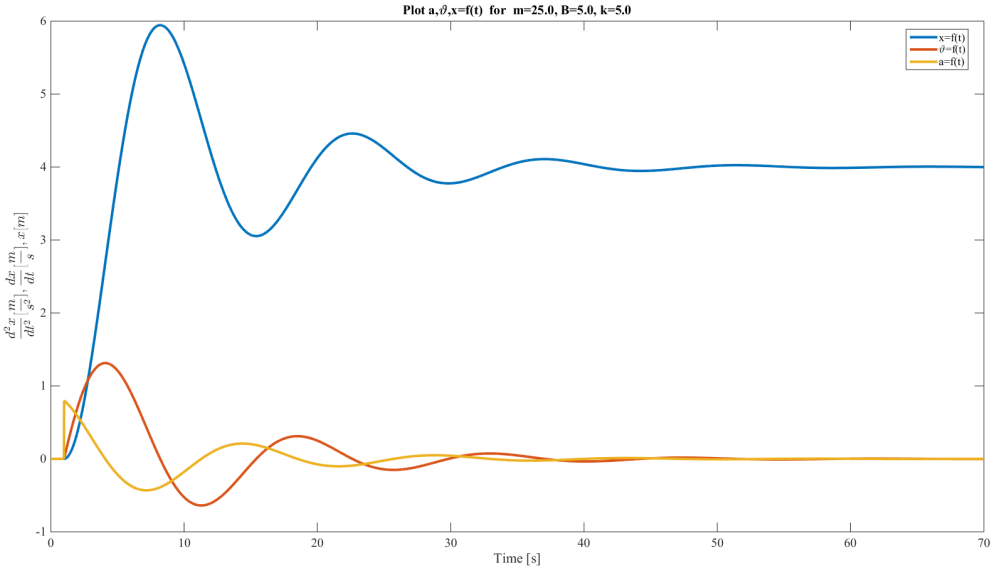


Figure 4: Result without friction

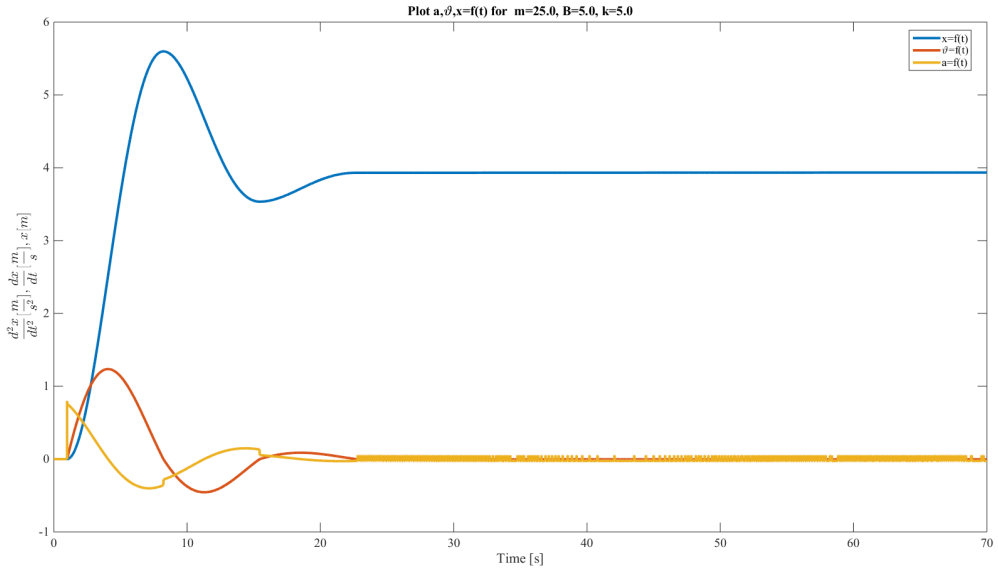


Figure 5: Result with friction

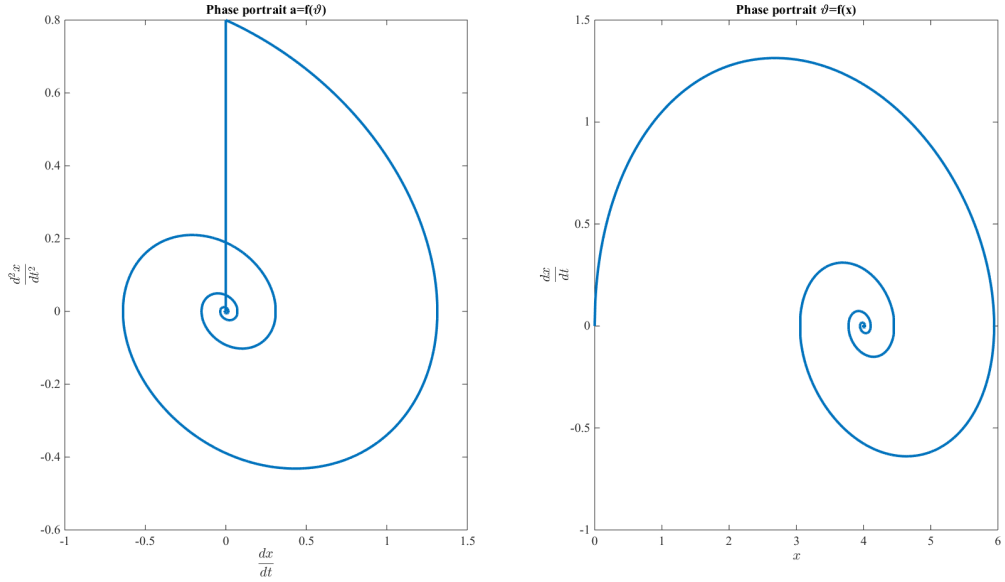


Figure 6: Phase portrait without friction

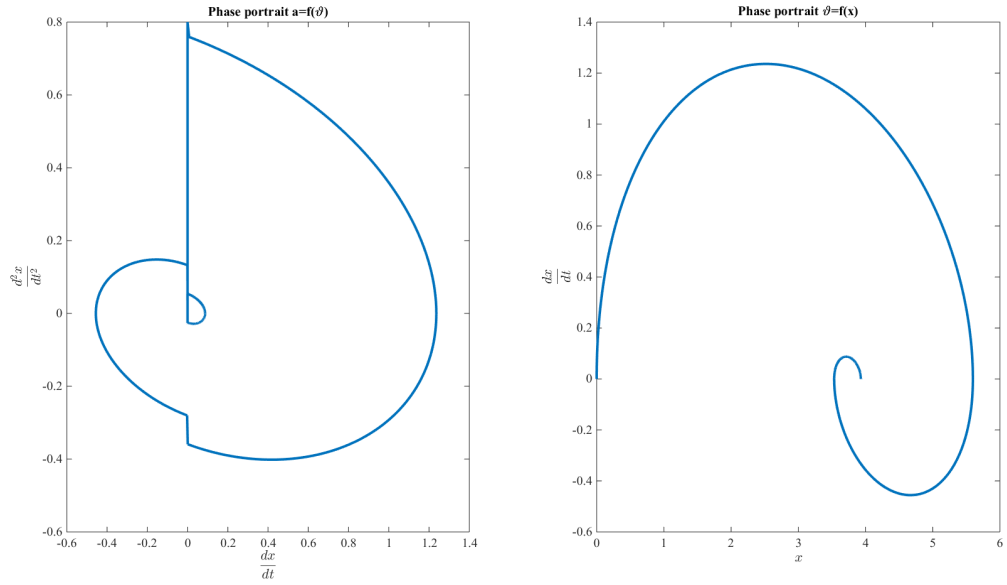


Figure 7: Phase portrait with friction

# 8 Conclusion

This document demonstrates the Lagrangian and co-energy approach to modeling a 1DoF system. It also provides a visual block diagram suitable for simulation in Simulink and basic code for scripting.