

# Assignment 3, TTK4190

Shiv Jeet Rai  
Arne Selle  
Erik Liland

17. November 2015

## Contents

<b>1</b>	<b>Autopilot design</b>	<b>2</b>
1.1	Heading autopilot . . . . .	2
1.2	Speed autopilot . . . . .	7
<b>2</b>	<b>Path following and Path tracking</b>	<b>8</b>
2.1	Path Generation . . . . .	8
2.2	Path following . . . . .	8
2.3	Path Tracking . . . . .	8

# 1 Autopilot design

## 1.1 Heading autopilot

### Analysis of ship characteristics

To be able to model the ship in a good way we ran many simulations with different rudder angle and measured the steady-state yaw rate. We then made a  $\delta - r$  plot of the result. Since the ship was turning port while giving a positive rudder command, this plot the rest of the assignment is made with a fixed gain of -1 on  $\delta_c$ .

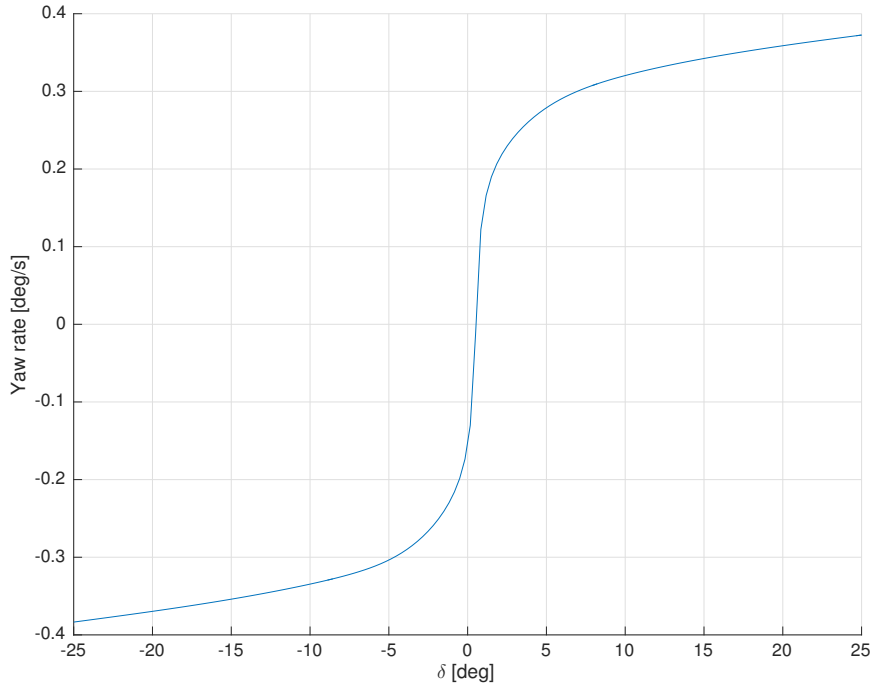


Figure 1:  $\delta - r$  plot

From figure 1 we clearly see the non-linear behavior of the ship. This motivates a 1-DOF heading model i.e. first- or second order Monoto model with non-linear extensions. To further investigate the effect of the non-linear characteristics of this ship, we compare the actual response with different models at different rudder angles. It should also be noticed that the ship has a constant drift to starboard with  $\delta_c = 0$ , as seen by the curve not passing through the origin. We compensate for this through the rest of the modeling part by adding a fixed rudder angle of  $0.52^\circ$  to the rudder input. We only need this correction while estimating the model parameters. In a closed loop, the integral effect will cancel both this drift and drift caused by wind, current and waves.

## 2. order linear Nomoto

$$\frac{r}{\delta}(s) = \frac{K_\nu(1 + T_3s)}{(1 + T_1s)(1 + T_2s)} \quad (1)$$

$$T_1T_2\ddot{\psi} + (T_1 + T_2)\dot{\psi} + \psi = K(\delta + T_3\dot{\delta})$$

The second order Nomoto model follows the ships overshoot some, but not enough.

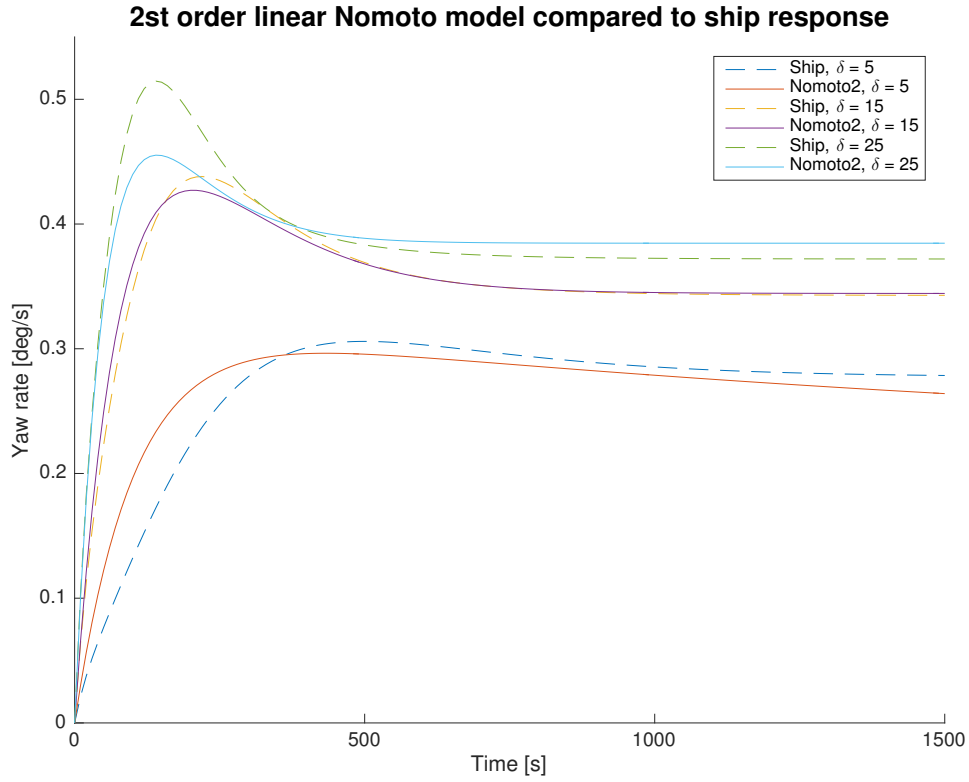


Figure 2: 2.order linear Nomoto model

## 1. order linear Nomoto

$$\frac{r}{\delta}(s) = \frac{K}{(1 + Ts)} \quad (2)$$

$$T\ddot{\psi} + \dot{\psi} = K\delta$$

We also tried the first order version Nomoto, and as expected the model will only be accurate for small rudder angles, and is therefore not very good for modeling the non-linearities.

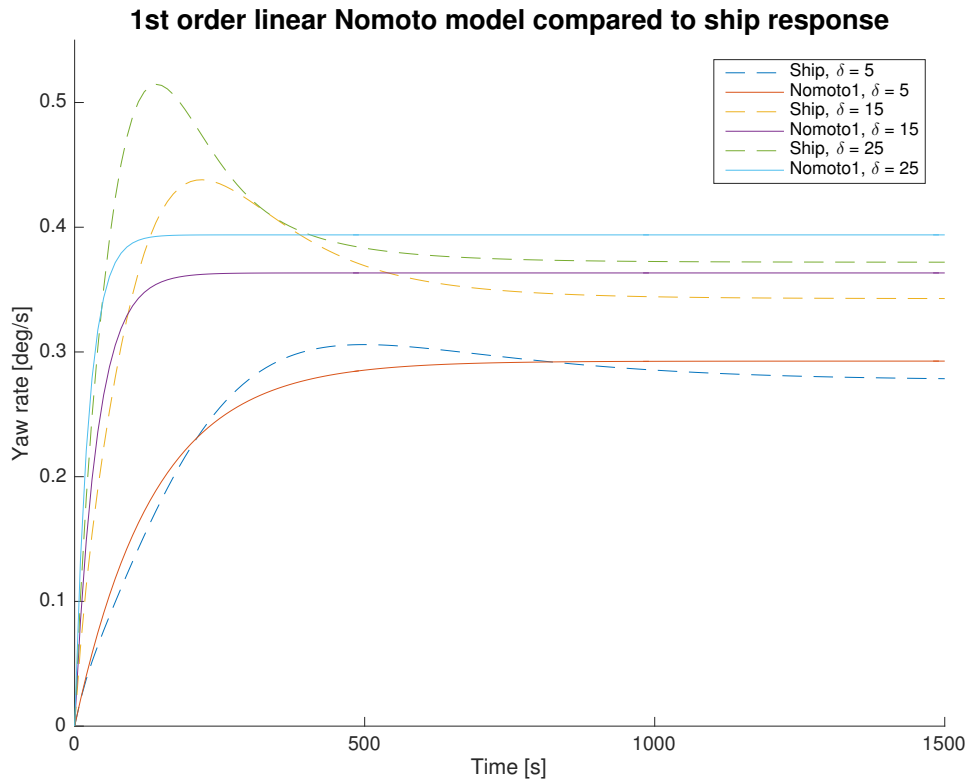


Figure 3: 1.order linear Nomoto model

## 2. order non-linear Nomoto

$$\begin{aligned} T_1 T_2 \ddot{r} + (T_1 + T_2) \dot{r} + K H_B(r) &= K(\delta + T_3 \dot{\delta}) \\ H_B(r) &= b_3 r^3 + b_2 r^2 + b_1 r + b_0 \end{aligned} \tag{3}$$

Where the steady state of  $H_B(r) = \delta$ .  $b_0$  have already been taken care of in the fixed rudder offset, and by symmetry in the hull leads to  $b_2 = 0$ . We then only need the first- and third-order term to describe the maneuvering characteristics. By curve fitting  $H_B(r) = b_3 r^3 + b_1 r = \delta$  to the obtained delta-r curve, we estimate the parameters  $b_3$  and  $b_1$ .

### 1. order non-linear Nomoto

Norbins' extension of the linear first order model:

$$\begin{aligned} T\dot{r} + H_N(r) &= K\delta \\ H_N(r) &= n_3 r^3 + n_2 r^2 + n_1 r + n_0 \end{aligned} \tag{4}$$

Where the steady state of  $H_N(r) = K\delta$ . We know that  $n_i = \frac{b_i}{|b_1|}$ , and since our ship is stable we know that  $n_1 = 1$ , and  $n_3 = \text{sign}(b_3) = 1$  thus resulting in following model.

$$T\dot{r} + r^3 + r = K\delta \tag{5}$$

## 1.2 Speed autopilot

To control the surge speed of MS Fartøystyring we suggest using a linearized model, where the surge speed is decoupled from the rest of the system. We are assuming

$$u \gg v$$

which leads to

$$U = u$$

. We then use a quadratic speed model

$$(m - X_{\dot{u}})\dot{u} - X_u u_r - X_{|u|u}|u_r|u_r = \tau \quad (6)$$

which leads to

$$\dot{u} = \frac{\tau + X_{|u|u}|u_r|u_r + X_u u_r}{m - X_{\dot{u}}} = \frac{X_{|u|u}|u_r|u_r + X_u u_r}{m - X_{\dot{u}}} + \tau_{nl} \quad (7)$$

where

$$\tau_{nl} = \frac{\tau}{m - X_{\dot{u}}} \Rightarrow \tau = \tau_{nl}(m - X_{\dot{u}}) \quad (8)$$

## **2 Path following and Path tracking**

### **2.1 Path Generation**

Her skriver vi om Path generation

### **2.2 Path following**

Her skriver vi om Path following

### **2.3 Path Tracking**

Her skriver vi om Path tracking



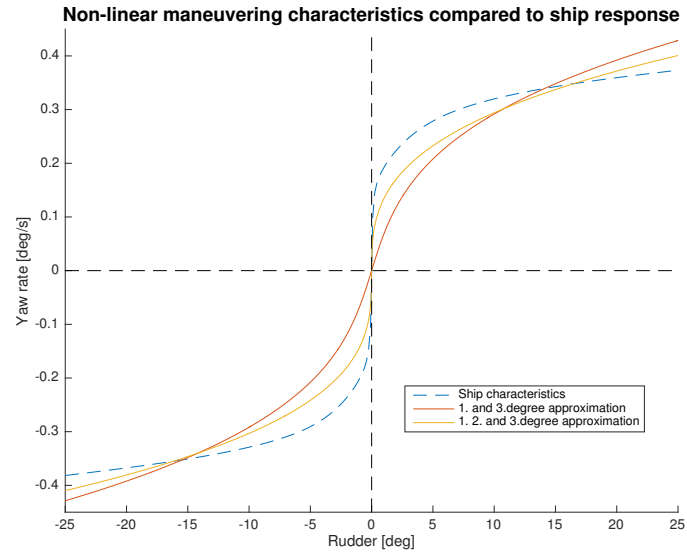


Figure 4: Third degree approximation of ship characteristics

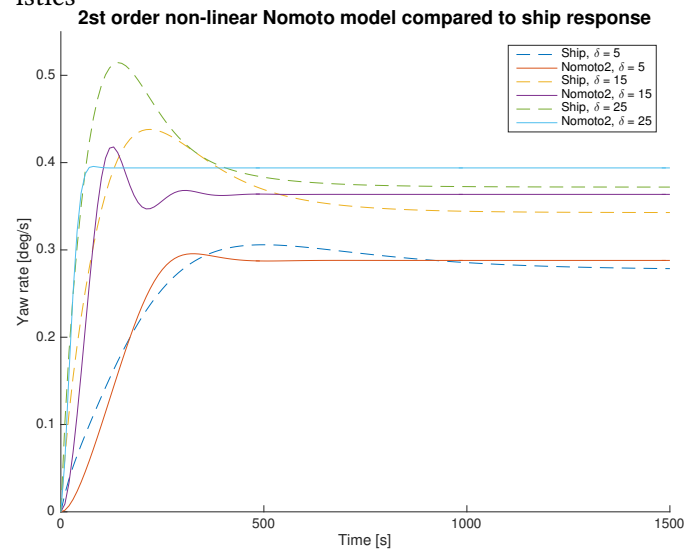


Figure 5: 2.order non-linear Nomoto model

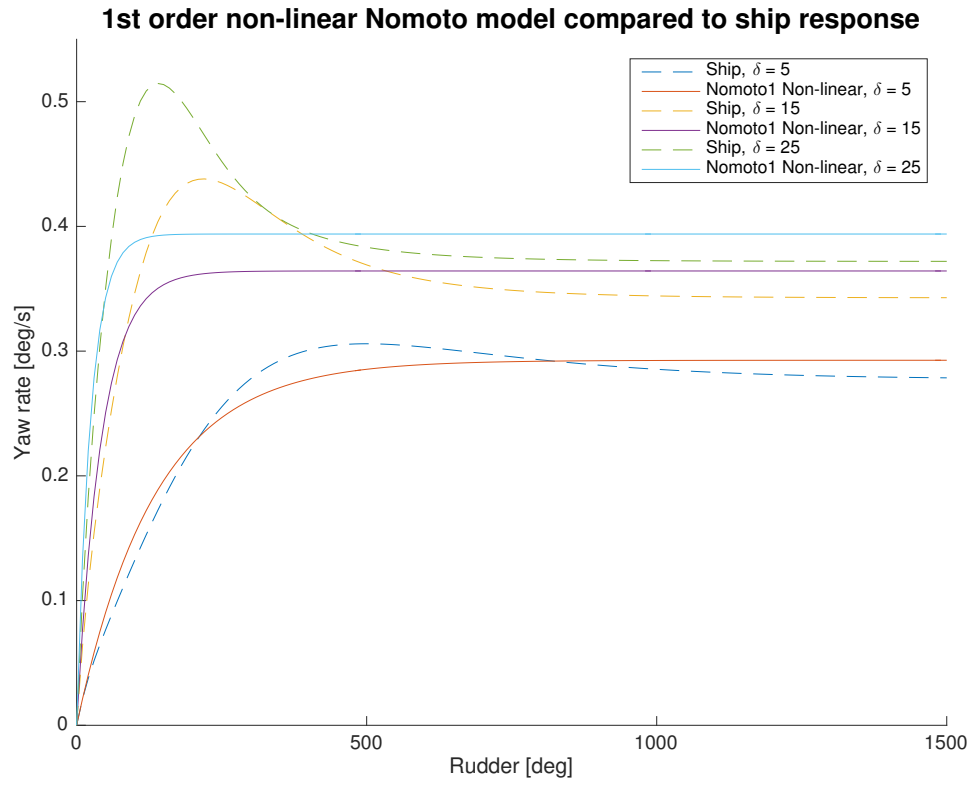


Figure 6: 1.order non-linear Nomoto model

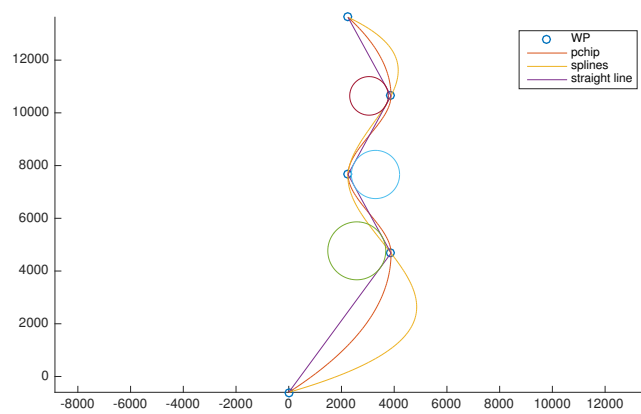


Figure 7: Different trajectories