A Design Study Approach to Classical Control

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Homework C.b

Modify the simulink model created in homework **??**.2 by creating an s-function that implements the equations of motion. The input to the s-function should be a slider for torque. The output should go to the animation developed in homework **??**.2.

Solution

The s-function is listed below.

```
function [sys,x0,str,ts,simStateCompliance]...
                      = satellite_dynamics(t,x,u,flag,AP)
switch flag,

  %%%%%%%%%%%%%%%%%%
  % Initialization %
  %%%%%%%%%%%%%%%%%%
  case 0,
    [sys,x0,str,ts,simStateCompliance]=mdlInitializeSizes(AP);

  %%%%%%%%%%%%%%%
  % Derivatives %
  %%%%%%%%%%%%%%%
  case 1,
    sys=mdlDerivatives(t,x,u,AP);

```

```
  %%%%%%%%%%
  % Update %
  %%%%%%%%%%
  case 2,
    sys=mdlUpdate(t,x,u);

  %%%%%%%%%%%
  % Outputs %
  %%%%%%%%%%%
  case 3,
    sys=mdlOutputs(t,x,u,AP);

  %%%%%%%%%%%%%%%%%%%%%%
  % GetTimeOfNextVarHit %
  %%%%%%%%%%%%%%%%%%%%%%
  case 4,
    sys=mdlGetTimeOfNextVarHit(t,x,u);

  %%%%%%%%%%%%%
  % Terminate %
  %%%%%%%%%%%%%
  case 9,
    sys=mdlTerminate(t,x,u);

  %%%%%%%%%%%%%%%%%%%%
  % Unexpected flags %
  %%%%%%%%%%%%%%%%%%%%
  otherwise
    DAStudio.error('Simulink:blocks:unhandledFlag',...
                     num2str(flag));

end

% end sfuntmpl

%
%=========================================================
% mdlInitializeSizes
% Return the sizes, initial conditions, and sample times
% for the S-function.
%=========================================================
%
function [sys,x0,str,ts,simStateCompliance]...
                                =mdlInitializeSizes(AP)

```

```matlab
sizes = simsizes;

sizes.NumContStates  = 4;
sizes.NumDiscStates  = 0;
sizes.NumOutputs     = 2;
sizes.NumInputs      = 1;
sizes.DirFeedthrough = 0;
sizes.NumSampleTimes = 1;

sys = simsizes(sizes);

%
% initial conditions
%
x0  = [AP.theta0; AP.phi0; AP.thetadot0; AP.phidot0];

%
% str is always an empty matrix
%
str = [];

%
% initialize the array of sample times
%
ts  = [0 0];

simStateCompliance = 'UnknownSimState';

% end mdlInitializeSizes

%
%=============================================================
% mdlDerivatives
% Return the derivatives for the continuous states.
%=============================================================
%
function sys=mdlDerivatives(t,x,u,AP)
  theta    = x(1);
  phi      = x(2);
  thetadot = x(3);
  phidot   = x(4);
  tau      = u(1);

  M = [...
      AP.Js, 0; 0, AP.Jp;...
```

```
        ];
    c = [...
        tau - AP.b*(thetadot-phidot)-AP.k*(theta-phi);...
        -AP.b*(phidot-thetadot);...
        ];

    tmp = inv(M)*c;
    thetaddot = tmp(1);
    phiddot   = tmp(2);

sys = [thetadot; phidot; thetaddot; phiddot];

% end mdlDerivatives


%
%=============================================================
% mdlOutputs
% Return the block outputs.
%=============================================================
%
function sys=mdlOutputs(t,x,u,AP)

sys = x(1:2);

% end mdlOutputs
```

For a complete solution to this problem, see the wiki associated with this book.