Deriving equations of motions of a double pendulum on a cart using the Lagrangian

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1 Introduction

This file is made to document the simulation of a double pendulum on a cart using lagrangian mechanics. In this file a double pendulum on a cart will be discussed.

2 The system

Where in figure 1:

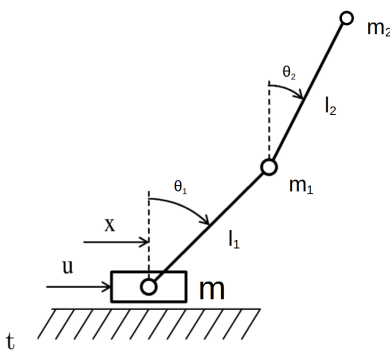|	
M:	Mass of the cart [kg]
m_1:	Mass of the first pendulum [kg]
m_2:	Mass of the second pendulum [kg]
θ_1:	Degrees first pendulum in reference to the cart [rad]
θ_2:	Degrees second pendulum in reference to the cart [rad]
ℓ_1:	Length of the first pendulum [m]
ℓ_2:	Length of the second pendulum [m]
x_c:	Position of the cart [m]

Figure 1: The pendulum

3   Lagrangian

Let the position and velocity of the pendulum be

$$x_1 = \ell_1 \sin(\theta_1) + x_c \qquad\qquad \dot{x}_1 = \ell_1 \dot{\theta}_1 \cos(\theta_1) + \dot{x}$$
$$y_1 = -\ell_1 \cos(\theta_1) \qquad\qquad \dot{y}_1 = \ell_1 \dot{\theta}_1 \sin(\theta_1)$$
$$x_2 = \ell_1 \sin(\theta_1) + \ell_2 \sin(\theta_2) + x_c \qquad\qquad \dot{x}_2 = \ell_1 \dot{\theta}_1 \cos(\theta_1) + \ell_2 \dot{\theta}_2 \cos(\theta_2) + \dot{x}$$
$$y_2 = -\ell_1 \cos(\theta_1) - \ell_2 \cos(\theta_2) \qquad\qquad \dot{y}_2 = \ell_1 \dot{\theta}_1 \sin(\theta_1) + \ell_2 \dot{\theta}_2 \sin(\theta_2)$$

To derive the equations of motion, the Lagrangian (1) will be used. First, T, the kinetic energy of the system will be calculated.

$$\mathcal{L} = T - V \tag{1}$$

$$
\begin{aligned}
T =& \frac{1}{2}M\dot{x}_c^2 + \frac{1}{2}m_1(\dot{x}_1^2 + \dot{y}_1^2) + \frac{1}{2}m_2(\dot{x}_2^2 + \dot{y}_2^2) \\
T =& \frac{1}{2}M\dot{x}_c^2 + \frac{1}{2}m_1 \left((\ell_1\dot{\theta}_1 \cos(\theta_1) + \dot{x}_c)^2 + (\ell_1\dot{\theta}_1 \sin(\theta_1))^2 \right) \\
&+ \frac{1}{2}m_2 \left((\ell_1\dot{\theta}_1 \cos(\theta_1) + \dot{x}_c + \ell_2\dot{\theta}_2 \cos(\theta_2))^2 + (\ell_1\dot{\theta}_2 \sin(\theta_1) + \ell_2\dot{\theta}_2 \sin(\theta_2))^2 \right) \\
T =& \frac{1}{2}M\dot{x}_c^2 + \frac{1}{2}m_1(\ell_1^2\dot{\theta}_1^2 + \dot{x}_c^2 + \dot{\theta}_1^2\ell_1^2 \sin(\theta_1)) + \frac{1}{2}m_2(...) \\
T =& ... + \frac{1}{2}m_2(\ell_1^2\dot{\theta}_1^2 \cos(\theta_1)^2 \\
&+ 2\ell_1\dot{\theta}_1 \cos(\theta_2)\dot{x}_c + 2\ell_1\dot{\theta}_1 \cos(\theta_1)\ell_2\dot{\theta}_2 \cos(\theta_2) \\
&+ \dot{x}_c^2 + 2\dot{x}_c\ell_2\dot{\theta}_2 \cos(\theta_2) + \ell_2^2\dot{\theta}_2^2 \cos(\theta_2)^2 \\
&+ \ell_1^2\dot{\theta}_1^2 \sin(\theta_1)^2 + 2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2 \sin(\theta_1) \sin(\theta_2) + \ell_2^2\dot{\theta}_2^2 \sin(\theta_2)^2) \\
T =& ... + \frac{1}{2}m_2(\ell_1^2\dot{\theta}_1^2 + 2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2 \cos(\theta_1 - \theta_2) + \ell_2^2\dot{\theta}_2^2 + 2\dot{x}_c(\ell_1\dot{\theta}_1 \cos(\theta_1) + \ell_2\dot{\theta}_2 \cos(\theta_2))) \\
T =& \frac{1}{2}(M + m_1)\dot{x}_c^2 + \frac{1}{2}(m_1 + m_2)\ell_1^2\dot{\theta}_1^2 \\
&+ \frac{1}{2}m_2(2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2 \cos(\theta_1 - \theta_2) + \ell_2^2\dot{\theta}_2^2 + 2\dot{x}_c(\ell_1\dot{\theta}_1 \cos(\theta_1) + \ell_2\dot{\theta}_2 \cos(\theta_2)))
\end{aligned}
\tag{2}
$$

Then, for V, the potential energy of the system

$$
\begin{aligned}
V &= m_1 g(y_1) + m_2 g(y_2) \\
V &= -m_1 g\ell_1 \cos(\theta_1) - m_2 g(\ell_1 \cos(\theta_1) + \ell_2 \cos(\theta_2)) \\
V &= -(m_1 + m_2)g\ell_1 \cos(\theta_1) - m_2 g\ell_2 \cos(\theta_2)
\end{aligned}
\tag{3}
$$

Lastly, using (2) and (3) the Lagrangian, $\mathcal{L}$, can be formulated

$$
\begin{aligned}
\mathcal{L} =& \frac{1}{2}(M + m_1)\dot{x}_c^2 \\
&+ \frac{1}{2}(m_1 + m_2)\ell_1^2\dot{\theta}_1^2 \\
&+ \frac{1}{2}m_2 \left(2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2 \cos(\theta_1 - \theta_2) + \ell_2^2\dot{\theta}_2^2 + 2\dot{x}_c(\ell_1\dot{\theta}_1 \cos(\theta_1) + \ell_2\dot{\theta}_2 \cos(\theta_2)) \right) \\
&+ (m_1 + m_2)g\ell_1 \cos(\theta_1) + m_2 g\ell_2 \cos(\theta_2)
\end{aligned}
\tag{4}
$$

4 Solve for $\ddot{\theta}_1$

Using the Lagrangian equation (19)

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right) = \frac{\partial \mathcal{L}}{\partial q} \tag{5}$$

Substituting (4) in equation (19) and solving for θ_1 gives:

$$\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1} = (m_1 + m_2)\ell_1^2\dot{\theta}_1 + m_2\ell_1\ell_2\dot{\theta}_2\cos(\theta_1 - \theta_2) + m_2\dot{x}_c\ell_1\cos(\theta_1) \tag{6}$$

$$\begin{aligned}
\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1}\right) =& (m_1 + m_2)\ell_1^2\ddot{\theta}_1 + m_2\ell_1\ell_2\ddot{\theta}_2\cos(\theta_1 - \theta_2) - m_2\ell_1\ell_2\dot{\theta}_2\sin(\theta_1 - \theta_2)(\dot{\theta}_1 - \dot{\theta}_2) \\
&+ m_2\ddot{x}_c\ell_1\cos(\theta_1) - m_2\dot{x}_c\ell_1\sin(\theta_1)\dot{\theta}_1
\end{aligned} \tag{7}$$

$$\frac{\partial \mathcal{L}}{\partial \theta_1} = -m_2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2\sin(\theta_1 - \theta_2) - (m_1 + m_2)g\ell_1\sin(\theta_1) - m_2\dot{x}_c\ell_1\dot{\theta}_1\sin(\theta_1) \tag{8}$$

Which give the following differential equation:

$$\begin{aligned}
&(m_1 + m_2)\ell_1^2\ddot{\theta}_1 + m_2\ell_1\ell_2\ddot{\theta}_2\cos(\theta_1 - \theta_2) - m_2\ell_1\ell_2\dot{\theta}_2\sin(\theta_1 - \theta_2)(\dot{\theta}_1 - \dot{\theta}_2) \\
&+ m_2\ddot{x}_c\ell_1\cos(\theta_1) - m_2\dot{x}_c\ell_1\sin(\theta_1)\dot{\theta}_1 + m_2\ell_1\ell_2\dot{\theta}_1\dot{\theta}_2\sin(\theta_1 - \theta_2) \\
&+ (m_1 + m_2)g\ell_1\sin(\theta_1) + m_2\dot{x}_c\ell_1\dot{\theta}_1\sin(\theta_1) = 0
\end{aligned} \tag{9}$$

Which simplifies to:

$$\begin{aligned}
&(m_1 + m_2)\ell_1\ddot{\theta}_1 + m_2\ell_2\ddot{\theta}_2\cos(\theta_1 - \theta_2) + m_2\ell_2\dot{\theta}_2^2\sin(\theta_1 - \theta_2) \\
&+ m_2\ddot{x}_c\cos(\theta_1) + (m_1 + m_2)g\sin(\theta_1) = 0
\end{aligned} \tag{10}$$

With the differential equation solved for $\ddot{\theta}_1$:

$$\frac{m_2\ell_2\ddot{\theta}_2\cos(\theta_1 - \theta_2) + m_2\ell_2\dot{\theta}_2^2\sin(\theta_1 - \theta_2) + m_2\ddot{x}_c\cos(\theta_1) + (m_1 + m_2)g\sin(\theta_1)}{-(m_1 + m_2)\ell_1} = \ddot{\theta}_1 \tag{11}$$

5   Solve for $\ddot{\theta}_2$

Using the Lagrangian equation (19)

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right) = \frac{\partial \mathcal{L}}{\partial q} \tag{12}$$

Substituting (4) in equation (19) and solving for θ_1 gives:

$$\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1} = m_2 \ell_1 \ell_2 \dot{\theta}_1 \cos(\theta_1 - \theta_2) + m_2 \ell_2^2 \dot{\theta}_2 + m_2 \dot{x}_c \ell_2 \cos(\theta_2) \tag{13}$$

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1}\right) = m_2 \ell_1 \ell_2 \ddot{\theta}_1 \cos(\theta_1 - \theta_2) - m_2 \ell_1 \ell_2 \dot{\theta}_1 \sin(\theta_1 - \theta_2)(\dot{\theta}_1 - \dot{\theta}_2)$$
$$+ m_2 \ell_2^2 \ddot{\theta}_2 + m_2 \ddot{x}_c \ell_2 \cos(\theta_2) - m_2 \dot{x}_c \ell_2 \sin(\theta_2)\dot{\theta}_2 \tag{14}$$

$$\frac{\partial \mathcal{L}}{\partial \theta_1} = -m_2 \ell_1 \ell_2 \dot{\theta}_1 \dot{\theta}_2 \sin(\theta_1 - \theta_2) - m_2 \dot{x}_c \dot{\theta}_2 \ell_2 \sin(\theta_2) - m_2 g \ell_2 \sin(\theta_2) \tag{15}$$

Which give the following differential equation:

$$m_2 \ell_1 \ell_2 \ddot{\theta}_1 \cos(\theta_1 - \theta_2) - m_2 \ell_1 \ell_2 \dot{\theta}_1 \sin(\theta_1 - \theta_2)(\dot{\theta}_1 - \dot{\theta}_2)$$
$$+ m_2 \ell_2^2 \ddot{\theta}_2 + m_2 \ddot{x}_c \ell_2 \cos(\theta_2) - m_2 \dot{x}_c \ell_2 \sin(\theta_2)\dot{\theta}_2 + m_2 \ell_1 \ell_2 \dot{\theta}_1 \dot{\theta}_2 \sin(\theta_1 - \theta_2)$$
$$+ m_2 \dot{x}_c \dot{\theta}_2 \ell_2 \sin(\theta_2) + m_2 g \ell_2 \sin(\theta_2) = 0 \tag{16}$$

Which simplifies to:

$$m_2 \ell_2 \ddot{\theta}_2 + m_2 \ell_1 \ddot{\theta}_1 \cos(\theta_1 - \theta_2) - m_2 \ell_1 \dot{\theta}_1^2 \sin(\theta_1 - \theta_2) + m_2 \ddot{x}_c \cos(\theta_2) + m_2 g \sin(\theta_2) = 0 \tag{17}$$

With the differential equation solved for $\ddot{\theta}_1$:

$$\frac{m_2 \ell_1 \ddot{\theta}_1 \cos(\theta_1 - \theta_2) - m_2 \ell_1 \dot{\theta}_1^2 \sin(\theta_1 - \theta_2) + m_2 \ddot{x}_c \cos(\theta_2) + m_2 g \sin(\theta_2)}{-m_2 \ell_2} = \ddot{\theta}_2 \tag{18}$$

6 Solve for $\ddot{x}_c$

Using the Lagrangian equation (19)

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{q}}\right) = \frac{\partial \mathcal{L}}{\partial q} \tag{19}$$

Substituting (4) in equation (19) and solving for θ_1 gives:

$$\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1} = (M + m_1)\dot{x}_c + m_2\ell_1\dot{\theta}_1\cos(\theta_1) + m_2\ell_2\dot{\theta}_2\cos(\theta_2) \tag{20}$$

$$\frac{d}{dt}\left(\frac{\partial \mathcal{L}}{\partial \dot{\theta}_1}\right) = (M + m_1)\ddot{x}_c + m_2\ell_1\ddot{\theta}_1\cos(\theta_1) - m_2\ell_1\dot{\theta}_1^2\sin(\theta_1) + m_2\ell_2\ddot{\theta}_2\cos(\theta_2) - m_2\ell_2\dot{\theta}_2^2\cos(\theta_2) \tag{21}$$

$$\frac{\partial \mathcal{L}}{\partial \theta_1} = 0 \tag{22}$$

Which give the following differential equation:

$$(M + m_1)\ddot{x}_c + m_2\ell_1\ddot{\theta}_1\cos(\theta_1) - m_2\ell_1\dot{\theta}_1^2\sin(\theta_1) + m_2\ell_2\ddot{\theta}_2\cos(\theta_2) - m_2\ell_2\dot{\theta}_2^2\cos(\theta_2) = 0 \tag{23}$$

With the differential equation solved for $\ddot{\theta}_1$:

$$frac{m_2\ell_1\ddot{\theta}_1\cos(\theta_1) - m_2\ell_1\dot{\theta}_1^2\sin(\theta_1) + m_2\ell_2\ddot{\theta}_2\cos(\theta_2) - m_2\ell_2\dot{\theta}_2^2\cos(\theta_2)}{-M + m_1} = \ddot{x}_c \tag{24}$$