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

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December 6, 2023

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]

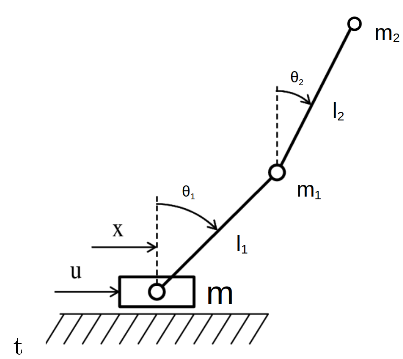

Figure 1: The pendulum

3 Lagrangian

Let the position and velocity of the pendulum be

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

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

Then, for V, the potential energy of the system

$$V = m_1 g(y_1) + m_2 g(y_2) \tag{3}$$

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

$$
\begin{aligned}
\mathcal{L} =& \frac{1}{2} (M + m_1) \dot{x}_c^2 + \frac{1}{2} (m_1 + m_2)(\ell_1^2 \theta_1^2 \cos(\theta_1)^2 + 2 \ell_1 \dot{\theta}_1 \cos(\theta_1) \dot{x}_c) \\
& + \frac{1}{2} m_1 \dot{y}_1^2 + m_2 \left((2 \ell_1 \ell_2 \dot{\theta}_1 \dot{\theta}_2 \cos(\theta_1) \cos(\theta_2) \dot{x}_c^2 + 2 \dot{x}_c \ell_2 \dot{\theta}_2 \cos(\theta_2) + \ell_2^2 \dot{\theta}_2^2 \cos(\theta_2)^2) + \dot{y}_2^2 \right) \\
& - m_1 g y_1 - m_2 g y_2
\end{aligned}
\tag{4}
$$

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:

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

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

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

Which give the following differential equation:

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

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 $\ddot{\theta}_1$:

$$fracm_2\ell_1\ddot{\theta}_1\cos(\theta_1) - m_2\ell_1\dot{\theta}_1^2\sin(\theta_1) + m_2\ell_2\ddot{\theta}_2\cos(\theta_2) - m_2\ell_2\dot{\theta}_2^2\cos(\theta_2) - M + m_1 = \ddot{x}_c \tag{24}$$