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## MAE5803 - HW#4 Part 1 Sliding Controller

Constant mass value, Integrate phi

```
function HW4P1_cd()
```

### Given Values

```
n = 2;
m = 1;
alpha1_lims = [4 6];
alpha2_lims = [1 2];
dlims = [-1 1];
omega_avoid = 4.2;           % (rad/s)
eta = [1 10];
```

### Choose parameters

```
alpha1_hat = mean(alpha1_lims);
alpha2_hat = mean(alpha2_lims);
d_hat = mean(dlims);
lambda = [2*pi*omega_avoid/5 2*pi*omega_avoid/3];
```

### Integrate

```
tspan = [0 6];
X0 = [0.1; 0; 0];
for i1 = 1:length(lambda)
    for i2 = 1:length(eta)

        casenum = 2*(i1-1) + i2;
        [t,X] = ode45(@slidingEOM_ConstMass,tspan,X0,[],...

        m,alpha1_hat,alpha2_hat,d_hat,eta(i2),lambda(i1));
        x1 = X(:,1);
        xd = 2*sin(t);
        x1_tilde = x1 - xd;
        % Calc s and phi again (I haven't found a better way to do
        this yet)
```

---

```

clear s phi u kd
for i3 = 1:length(t)
    [~,s(i3),phi(i3),u(i3),kd(i3)] =
slidingEOM_ConstMass(t(i3),...

X(i3,:),m,alpha1_hat,alpha2_hat,d_hat,eta(i2),lambda(i1));
end
x_tilde_bound = kd/lambda(i1);

```

## Plots

```

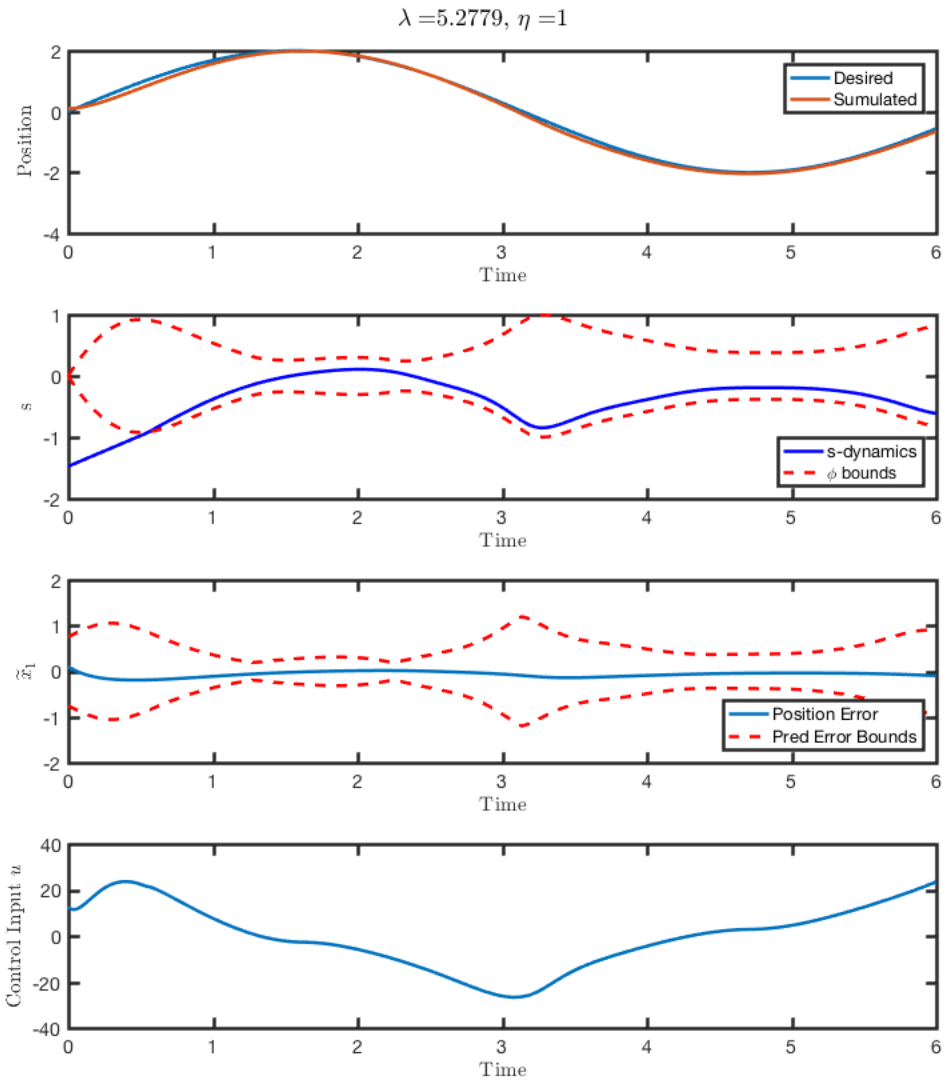
fh = figure(casenum);
set(fh,'Position',[0 0 840 1050])
suptitle(['$\lambda = $' num2str(lambda(i1)) ', $\eta = $'
num2str(eta(i2))]);
% Dynamics
subplot(411)
plot(t,xd,t,xl)
legend('Desired','Sumulated','location','northeast')
xlabel('Time'); ylabel('Position');

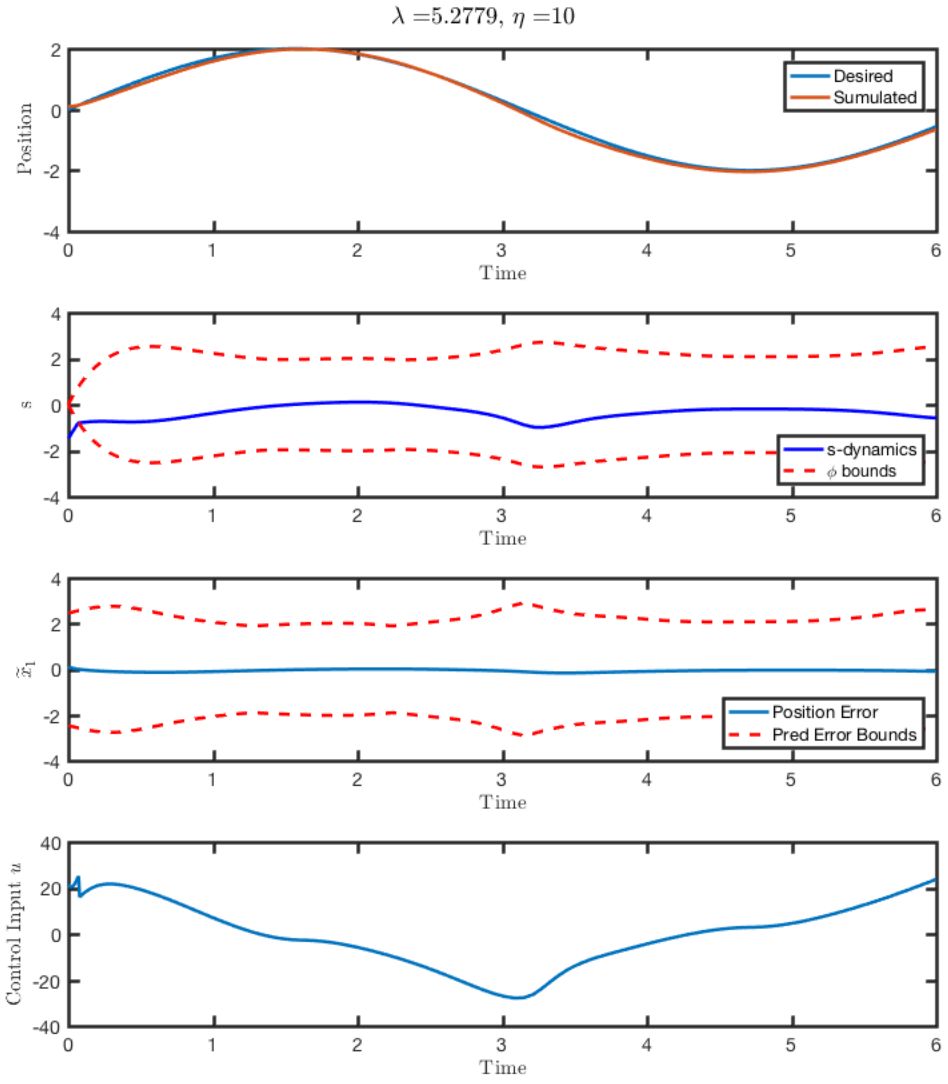
% s-Dynamics
subplot(412)
plot(t,s,'b',t,phi,'r--',t,-phi,'r--')
legend('s-dynamics','\phi bounds','location','southeast')
xlabel('Time'); ylabel('s');

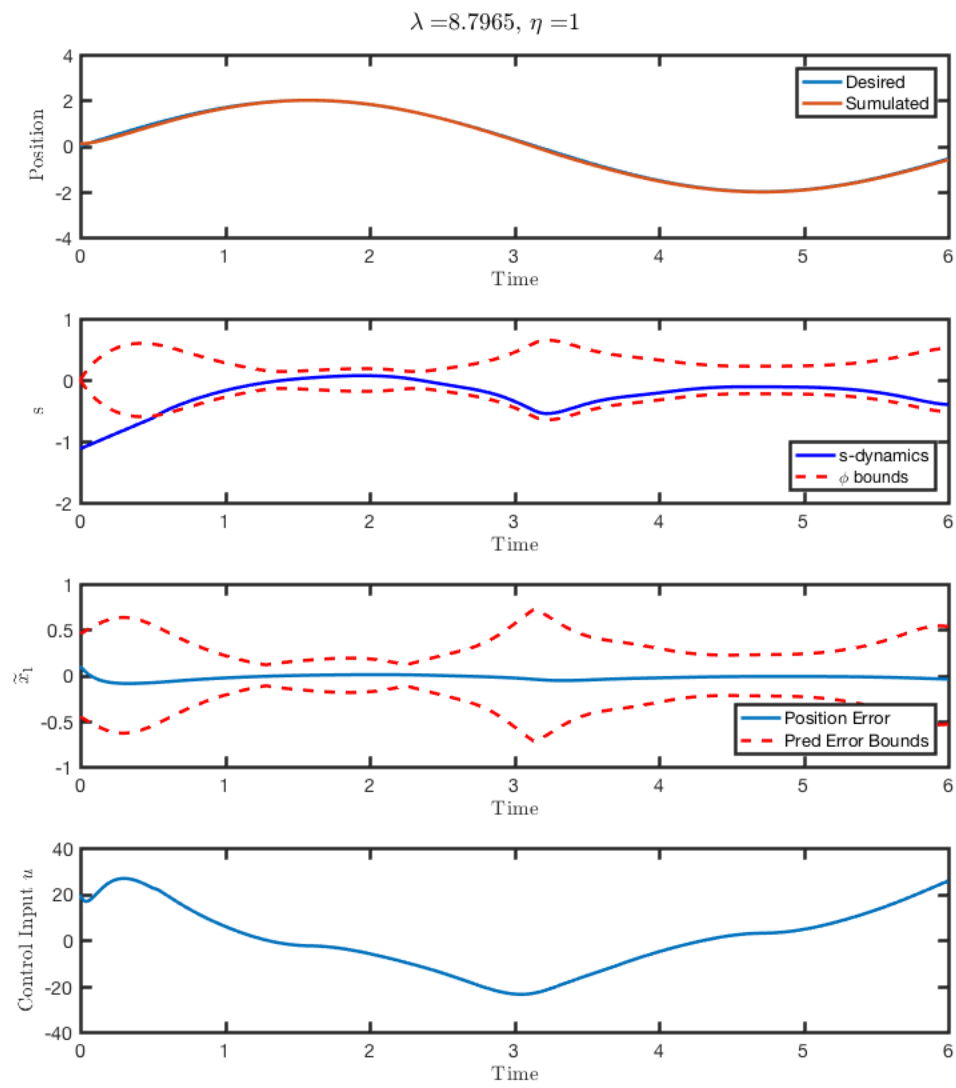
% Error Plot
subplot(413)
plot(t,xl_tilde,t,x_tilde_bound,'r--',t,-x_tilde_bound,'r--');
legend('Position Error','Pred Error
Bounds','location','southeast')
xlabel('Time'); ylabel('$\widetilde{x}_1$');

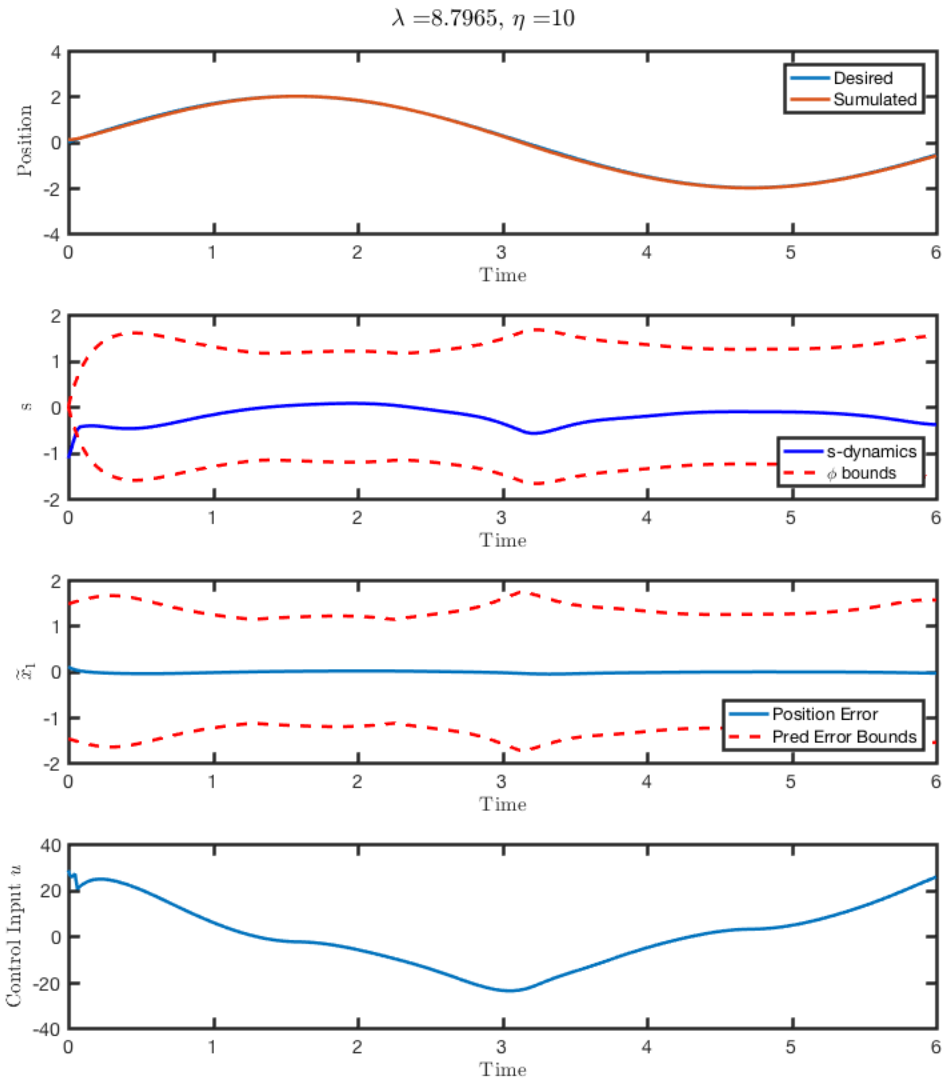
% Control Input
subplot(414)
plot(t,u);
xlabel('Time'); ylabel('Control Input $u$');

```









```

end
end
end

```

## Equation of Motion

```

function [dx, s, phi, u, kd] =
    slidingEOM_ConstMass(t,x,m,a1_hat,a2_hat,d_hat,eta,lambda)
dx = zeros(size(x));
x1 = x(1);
x2 = x(2);
phi = x(3);
xd = 2*sin(t);

```

---

```

xd_dot = 2*cos(t);
xd_dd = -2*sin(t);

a1 = 5 + cos(t);
a2 = 1 + abs(sin(2*t));
d = cos(1.3*t);
f = (-1/m)*((a1 + a2*cos(x1)^2)*abs(x2)*x2 + d);
fd = (-1/m)*((a1 + a2*cos(xd)^2)*abs(xd_dot)*xd_dot + d);
b = 1/m;
f_hat = (-1/m)*((a1_hat + a2_hat*cos(x1)^2)*abs(x2)*x2 + d_hat);
fd_hat = (-1/m)*((a1_hat + a2_hat*cos(xd)^2)*abs(xd_dot)*xd_dot +
    d_hat);
F = abs(f-f_hat);
Fd = abs(fd-fd_hat);
k = F + eta;
kd = Fd + eta;
% phi = 0.1;
% phi = kd/lambda;
% phi_dot = 0;
phi_dot = kd - lambda*phi;
s = x2 - xd_dot + lambda*(x1-xd);
u_hat = -f_hat + xd_dd - lambda*(x2-xd_dot);

if abs(s) >= phi
    u = u_hat - k*sign(s);
else
    u = u_hat - (k-phi_dot)*(s/phi);
end

dx(1) = x2;
dx(2) = f + b*u;
dx(3) = phi_dot;

end

```

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