PSI 3442
Projeto de Sistemas Embarcados

Modelagem de Sistemas Dinâmicos

31/08/2020

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Modelagem de Sistemas Dinâmicos

Na aula, vamos rever a modelagem de sistemas dinâmicos

a) Faremos a discussão considerando um helicóptero.

b) Capítulo 2 do Livro Lee and Seshia pags. 18 a 38

Model Based Design

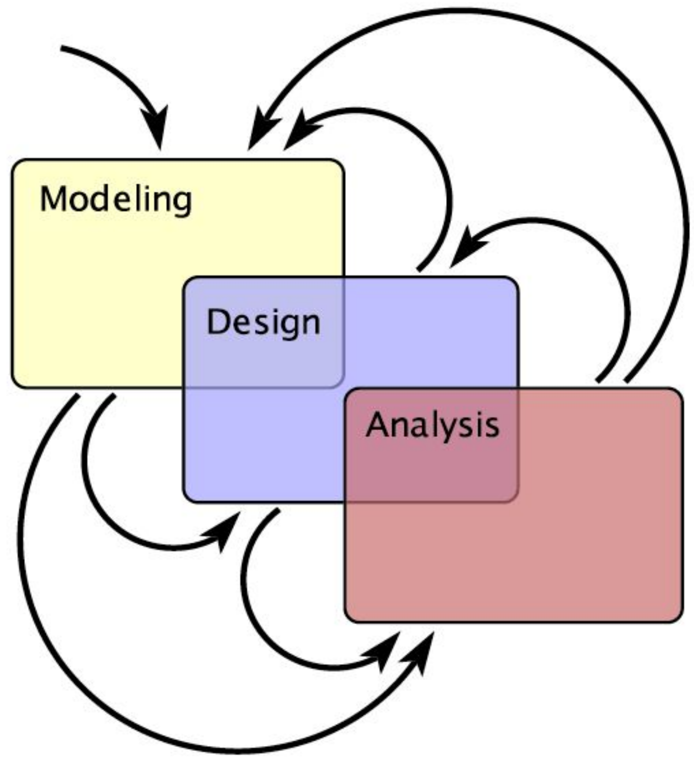


Figure 1.3: Creating embedded systems requires an iterative process of modeling, design, and analysis.

Abordagem Ciberfísica

A cyber-physical system (CPS) is an integration of computation with physical processes whose behavior is defined by both cyber and physical parts of the system.

Lee&Seshia, 2017

Introduction to Embedded Systems

Edward A. Lee
UC Berkeley

EECS 149/249A
Fall 2016

Module *2a*: Modeling Physical Dynamics

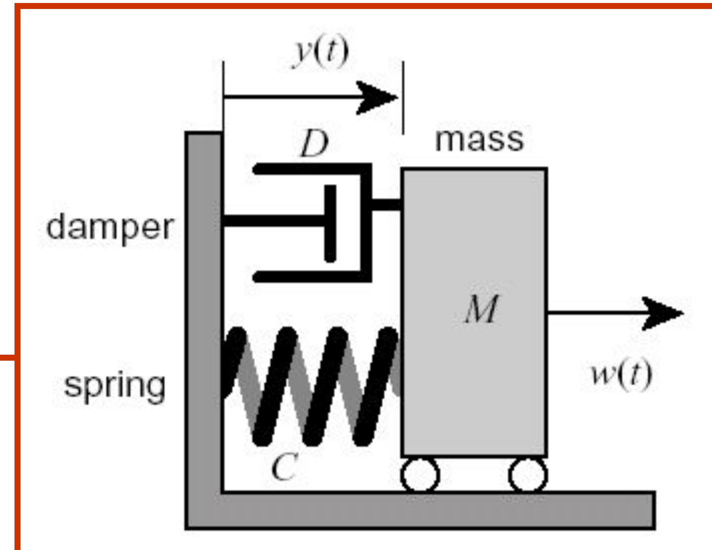
Modeling Techniques in this Course

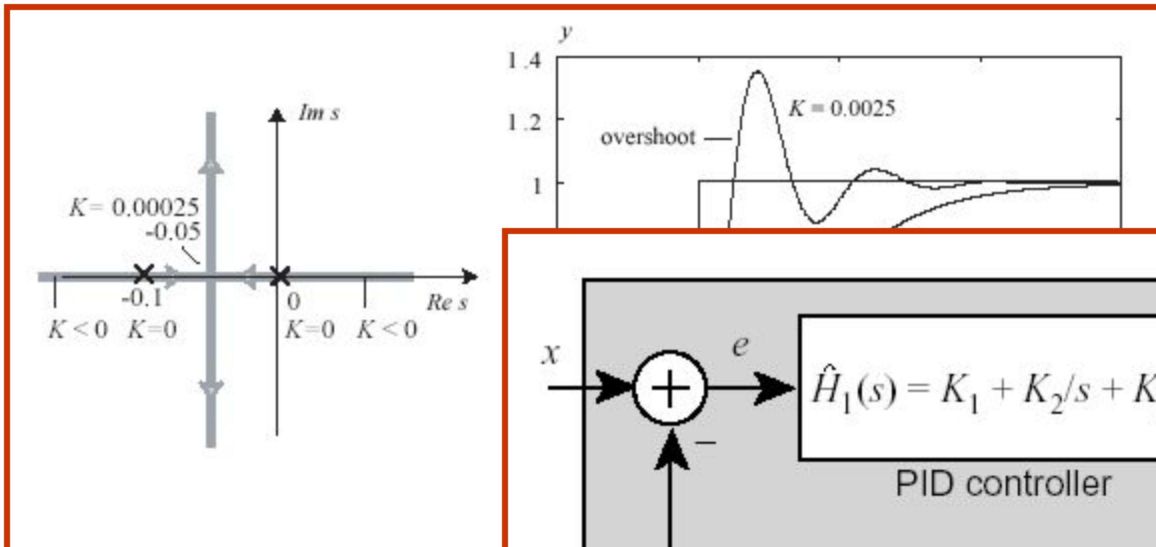
Models that are abstractions of **system dynamics** (how system behavior changes over time)

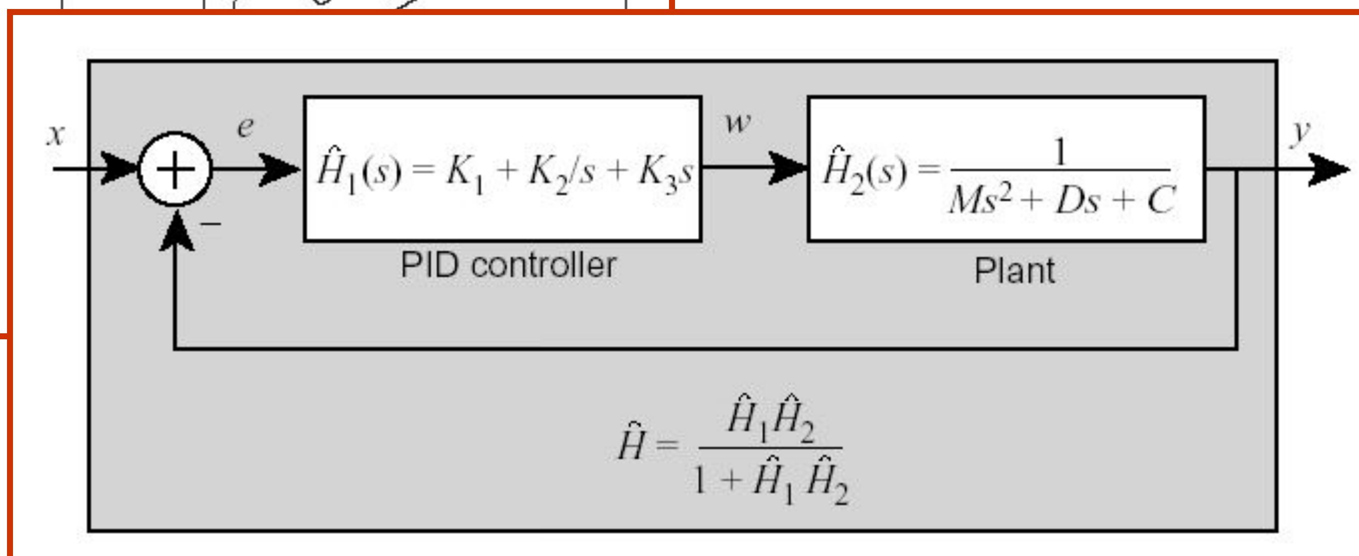
- Modeling physical phenomena – differential equations
- Feedback control systems – time-domain modeling
- Modeling modal behavior – FSMs, hybrid automata, …
- Modeling sensors and actuators –calibration, noise, …
- Hardware and software – concurrency, timing, power, …
- Networks – latencies, error rates, packet losses, …

Today's Lecture: Modeling of Continuous Dynamics

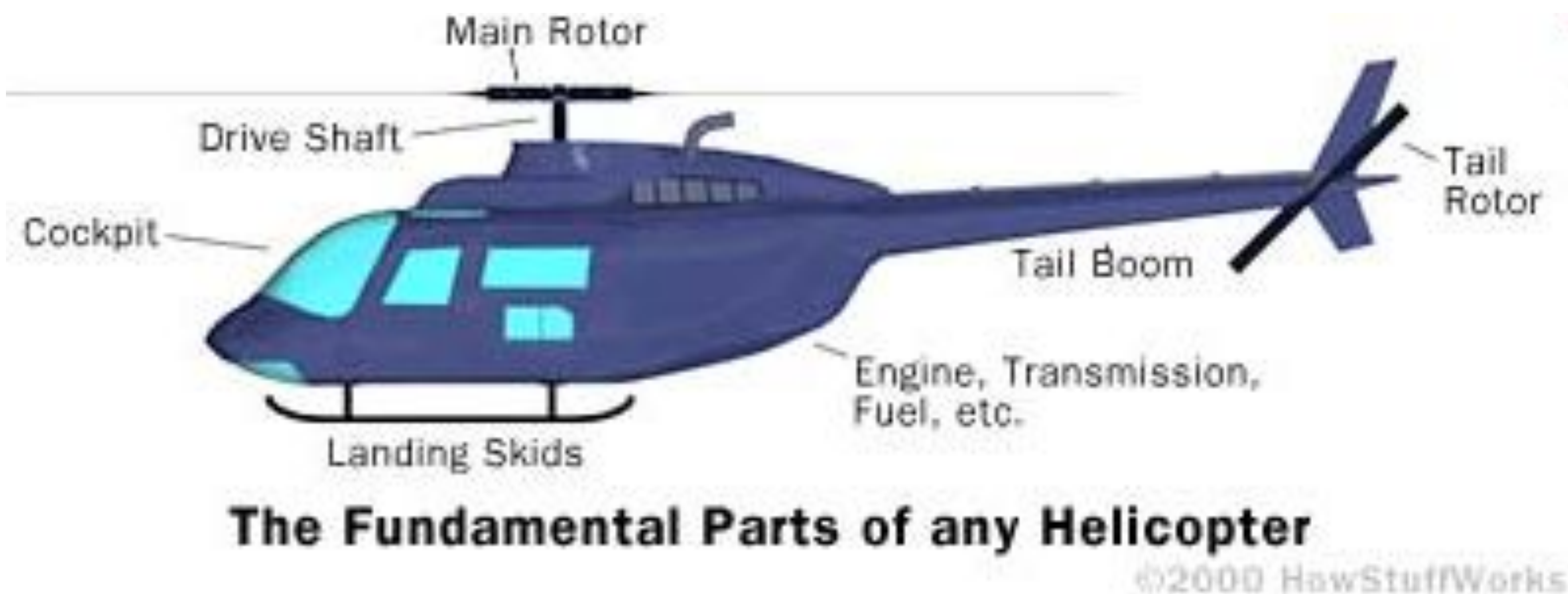
Ordinary differential equations, Laplace transforms, feedback control models, …







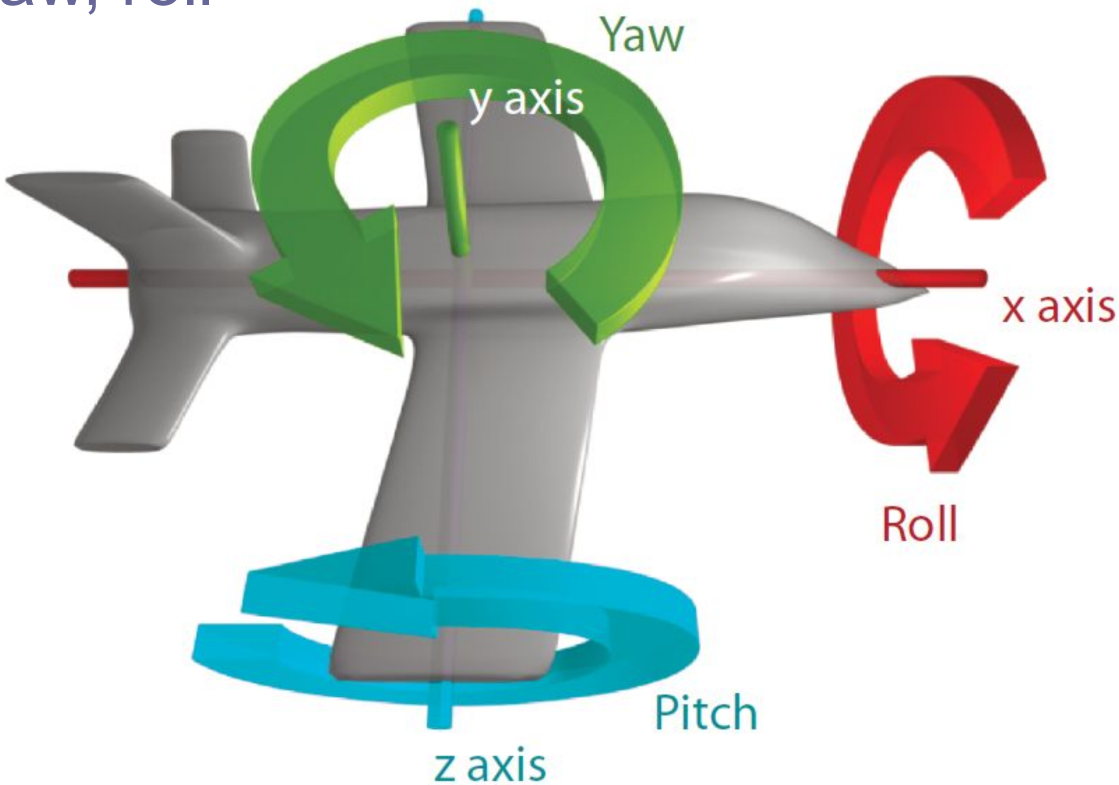
An Example: Helicopter Dynamics



Modeling Physical Motion

Six degrees of freedom:

- Position: x, y, z
- Orientation: pitch, yaw, roll



Notation

Position is given by three functions:

$$x\colon \mathbb{R} \to \mathbb{R}$$
$$y\colon \mathbb{R} \to \mathbb{R}$$
$$z\colon \mathbb{R} \to \mathbb{R}$$

where the domain $\mathbb{R}$ represents time and the co-domain (range) $\mathbb{R}$ represents position along the axis. Collecting into a vector:

$$\mathbf{x}\colon \mathbb{R} \to \mathbb{R}^3$$

Position at time $t \in \mathbb{R}$ is $\mathbf{x}(t) \in \mathbb{R}^3$.

Notation

Velocity

$$\dot{\mathbf{x}} \colon \mathbb{R} \to \mathbb{R}^3$$

is the derivative, $\forall\, t \in \mathbb{R}$,

$$\dot{\mathbf{x}}(t) = \frac{d}{dt}\mathbf{x}(t)$$

Acceleration $\ddot{\mathbf{x}} \colon \mathbb{R} \to \mathbb{R}^3$ is the second derivative,

$$\ddot{\mathbf{x}} = \frac{d^2}{dt^2}\mathbf{x}$$

Force on an object is $\mathbf{F} \colon \mathbb{R} \to \mathbb{R}^3$.

Newton’s Second Law

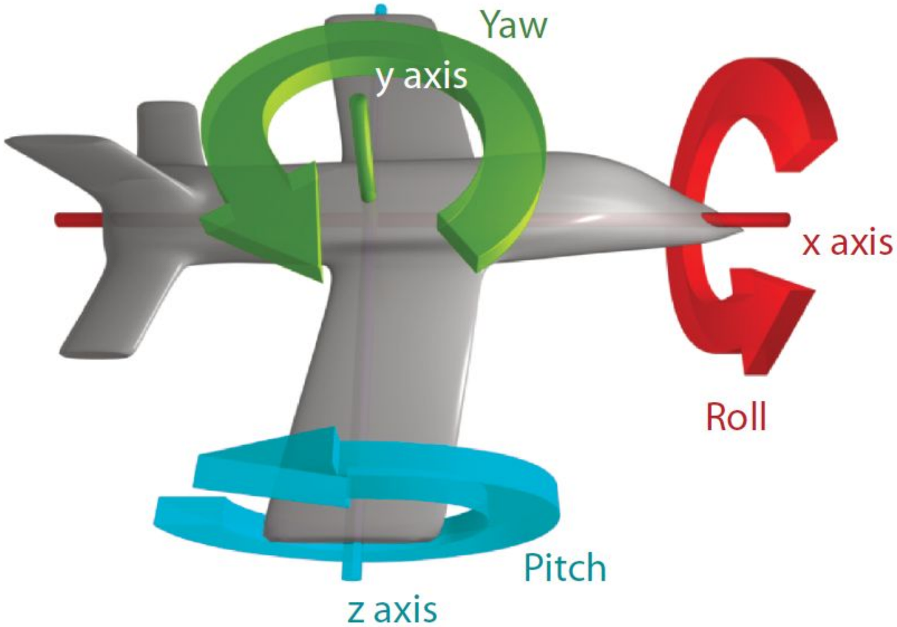
Newton’s second law states $\forall\, t \in \mathbb{R}$,

$$\mathbf{F}(t) = M\ddot{\mathbf{x}}(t)$$

where M is the mass. To account for initial position and velocity, convert this to an integral equation

$$\begin{aligned} \mathbf{x}(t) &= \mathbf{x}(0) + \int_0^t \dot{\mathbf{x}}(\tau) d\tau \\ &= \mathbf{x}(0) + t\dot{\mathbf{x}}(0) + \frac{1}{M}\int_0^t \int_0^\tau \mathbf{F}(\alpha) d\alpha d\tau, \end{aligned}$$

Orientation

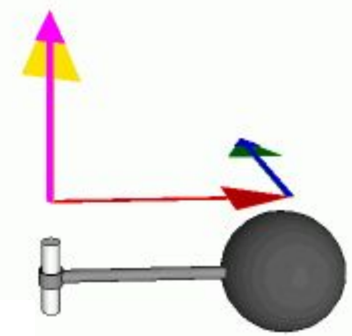


- Orientation: $\theta\colon \mathbb{R} \to \mathbb{R}^3$
- Angular velocity: $\dot{\theta}\colon \mathbb{R} \to \mathbb{R}^3$
- Angular acceleration: $\ddot{\theta}\colon \mathbb{R} \to \mathbb{R}^3$
- Torque: $\mathbf{T}\colon \mathbb{R} \to \mathbb{R}^3$

$$\theta(t) = \begin{bmatrix} \dot{\theta}_x(t) \\ \dot{\theta}_y(t) \\ \dot{\theta}_z(t) \end{bmatrix} = \begin{bmatrix} \text{roll} \\ \text{yaw} \\ \text{pitch} \end{bmatrix}$$

Angular version of force is torque.
For a point mass rotating around a fixed axis:

- radius of the arm: $r \in \mathbb{R}$
- force orthogonal to arm: $f \in \mathbb{R}$
- mass of the object: $m \in \mathbb{R}$



$$T_y(t) = r f(t)$$

angular momentum, momentum

Just as force is a push or a pull, a torque is a twist.

Units: newton-meters/radian, Joules/radian

Note that radians are meters/meter (2π meters of circumference per 1 meter of radius), so as units, are optional.

Rotational Version of Newton's Second Law

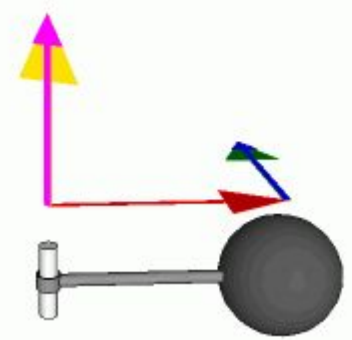
$$\mathbf{T}(t) = \frac{d}{dt}\left(I(t)\dot{\theta}(t)\right),$$

where $I(t)$ is a 3×3 matrix called the moment of inertia tensor.

$$\begin{bmatrix} T_x(t) \\ T_y(t) \\ T_z(t) \end{bmatrix} = \frac{d}{dt}\left(\begin{bmatrix} I_{xx}(t) & I_{xy}(t) & I_{xz}(t) \\ I_{yx}(t) & I_{yy}(t) & I_{yz}(t) \\ I_{zx}(t) & I_{zy}(t) & I_{zz}(t) \end{bmatrix}\begin{bmatrix} \dot{\theta}_x(t) \\ \dot{\theta}_y(t) \\ \dot{\theta}_z(t) \end{bmatrix}\right)$$

Here, for example, $T_y(t)$ is the net torque around the y axis (which would cause changes in yaw), $I_{yx}(t)$ is the inertia that determines how acceleration around the x axis is related to torque around the y axis.

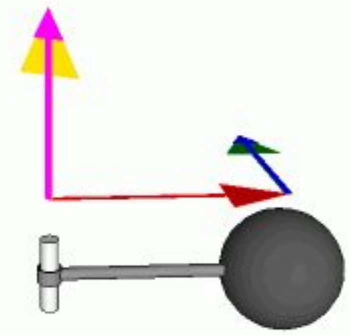
Feedback Control Problem



A helicopter without a tail rotor, like the one below, will spin uncontrollably due to the torque induced by friction in the rotor shaft.

Control system problem: Apply torque using the tail rotor to counterbalance the torque of the top rotor.

Simplified Model



Yaw dynamics:

$$T_y(t) = I_{yy}\ddot{\theta}_y(t)$$

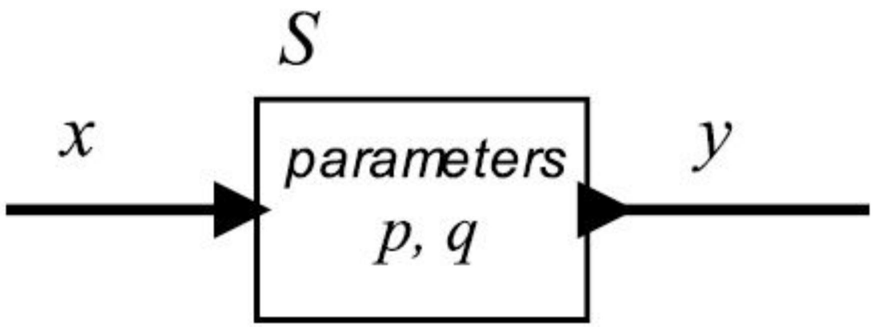
To account for initial angular velocity, write as

$$\dot{\theta}_y(t) = \dot{\theta}_y(0) + \frac{1}{I_{yy}}\int_0^t T_y(\tau)d\tau.$$

“Plant” and Controller

Actor Model of Systems

A *system* is a function that accepts an input *signal* and yields an output signal.



The domain and range of the system function are sets of signals, which themselves are functions.

$$x : \mathbb{R} \to \mathbb{R}, \quad y : \mathbb{R} \to \mathbb{R}$$

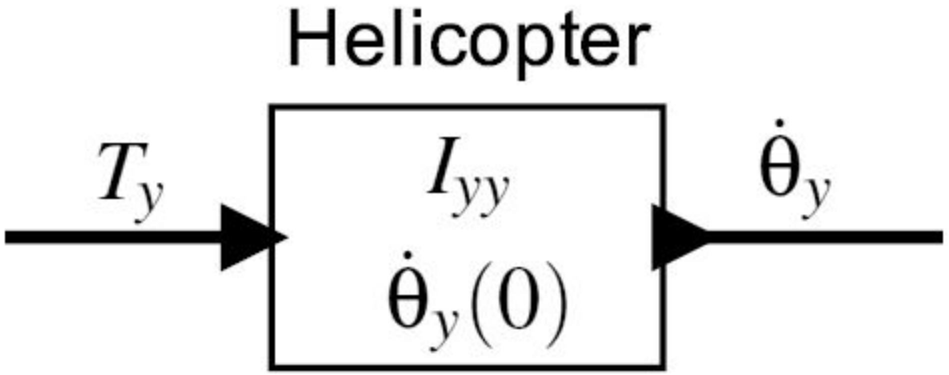
$$S : X \to Y$$

$$X = Y = (\mathbb{R} \to \mathbb{R})$$

Parameters may affect the definition of the function *S*.

Actor Model of the Helicopter

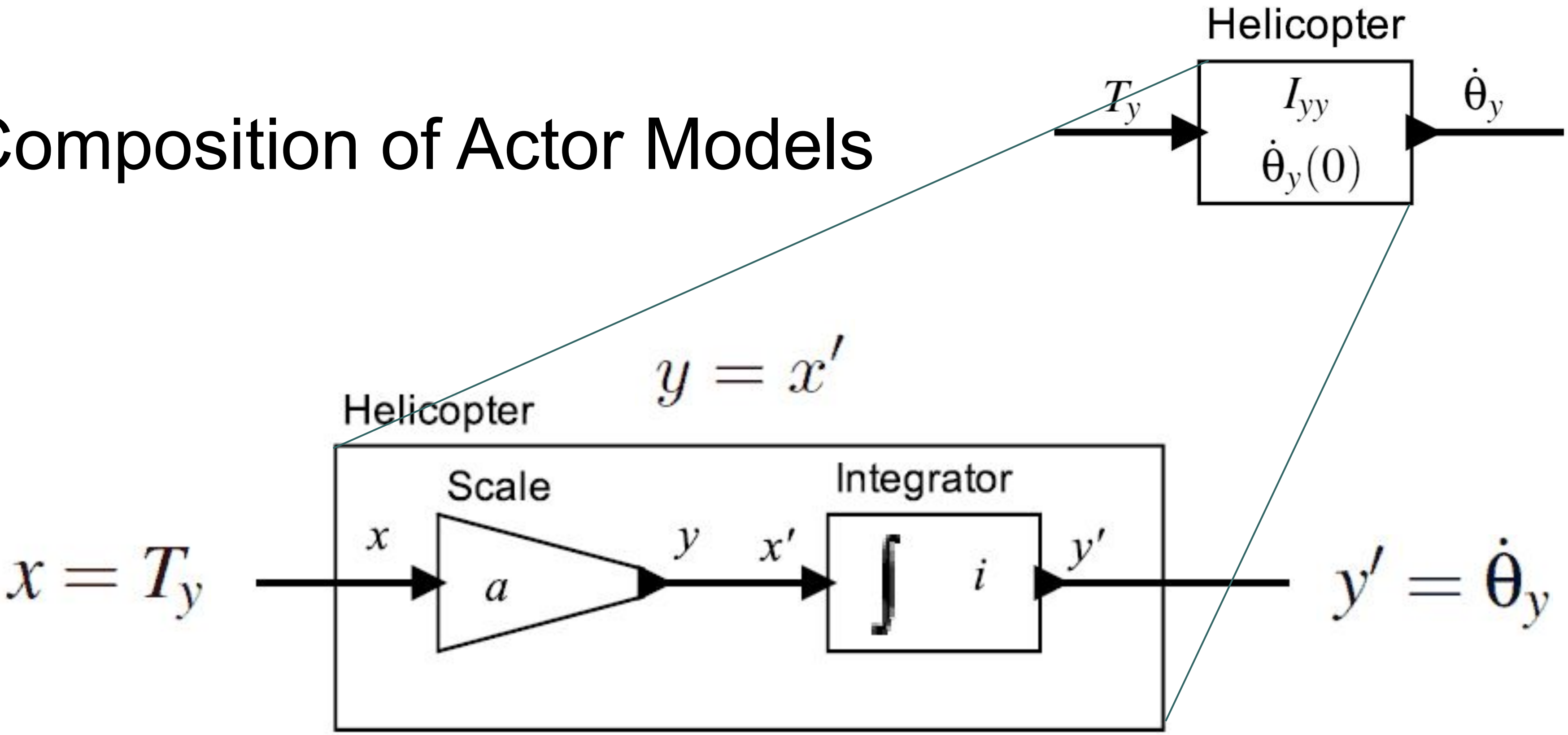
Input is the net torque of the tail rotor and the top rotor. Output is the angular velocity around the *y* axis.



Parameters of the model are shown in the box. The input and output relation is given by the equation to the right.

$$\dot{\theta}_y(t) = \dot{\theta}_y(0) + \frac{1}{I_{yy}} \int_0^t T_y(\tau) d\tau$$

Composition of Actor Models



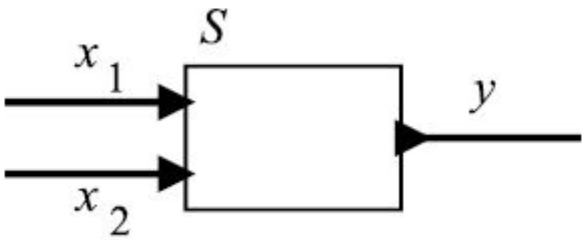
$$\forall\, t \in \mathbb{R}, \quad y(t) = ax(t) \qquad y'(t) = i + \int_0^t x'(\tau)d\tau$$

$$y = ax$$

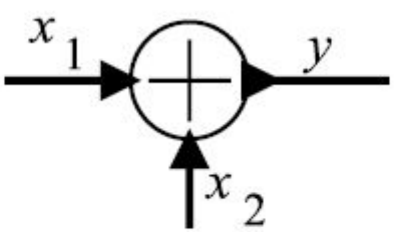
$$a = 1/I_{yy}$$

$$i = \dot{\theta}_y(0)$$

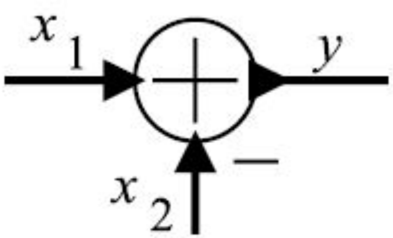
Actor Models with Multiple Inputs



$$S\colon (\mathbb{R} \to \mathbb{R})^2 \to (\mathbb{R} \to \mathbb{R})$$

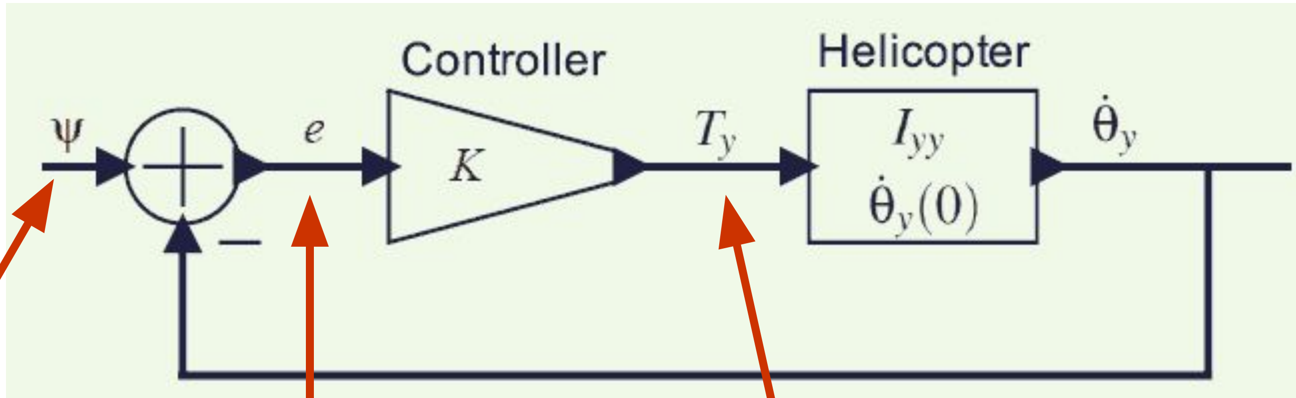


$$\forall\, t \in \mathbb{R}, \quad y(t) = x_1(t) + x_2(t)$$



$$(S(x_1, x_2))(t) = y(t) = x_1(t) - x_2(t)$$

Proportional controller



desired angular velocity

error signal

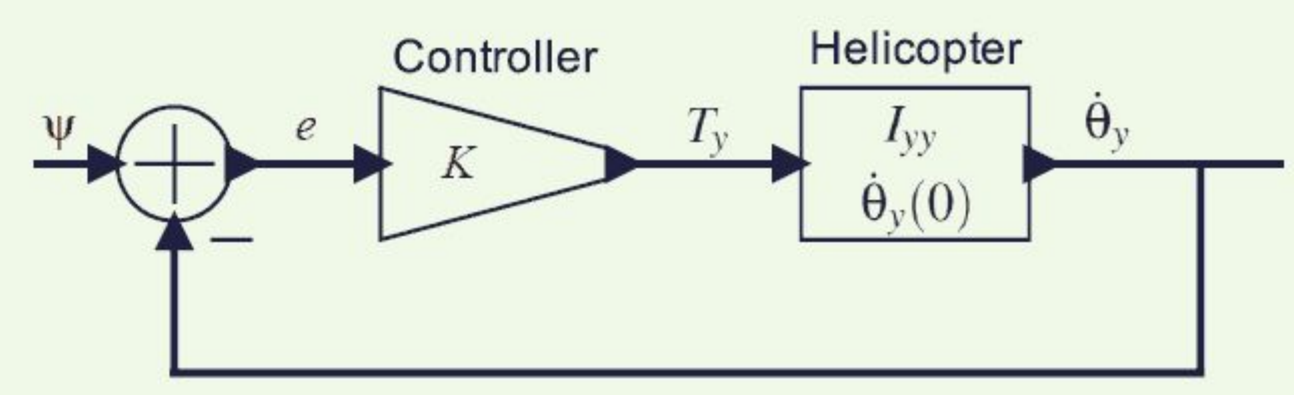
net torque

$$e(t) = \psi(t) - \dot{\theta}_y(t) \qquad T_y(t) = Ke(t)$$

$$\begin{aligned}
\dot{\theta}_y(t) &= \dot{\theta}_y(0) + \frac{1}{I_{yy}} \int_0^t T_y(\tau)\,d\tau \\
&= \dot{\theta}_y(0) + \frac{K}{I_{yy}} \int_0^t (\psi(\tau) - \dot{\theta}_y(\tau))\,d\tau
\end{aligned}$$

Note that the angular velocity appears on both sides, so this equation is not trivial to solve.

Behavior of the controller



$$\dot{\theta}_y(t) = \dot{\theta}_y(0) + \frac{K}{I_{yy}} \int_0^t (\psi(\tau) - \dot{\theta}_y(\tau)) d\tau$$

Desired angular velocity: $\psi(t) = 0$

Simplifies differential equation to:

$$\dot{\theta}_y(t) = \dot{\theta}_y(0) - \frac{K}{I_{yy}} \int_0^t \dot{\theta}_y(\tau) d\tau$$

Which can be solved as follows (see textbook):

$$\dot{\theta}_y(t) = \dot{\theta}_y(0) e^{-Kt/I_{yy}} u(t)$$

Exercise

Reformulate the helicopter considering now a quad-rotor or a drone

Can we do a MathLab Simulator of a Drone?

https://www.mathworks.com/help/aeroblks/examples/quadcopter-project.html?requestedDomain=www.mathworks.com

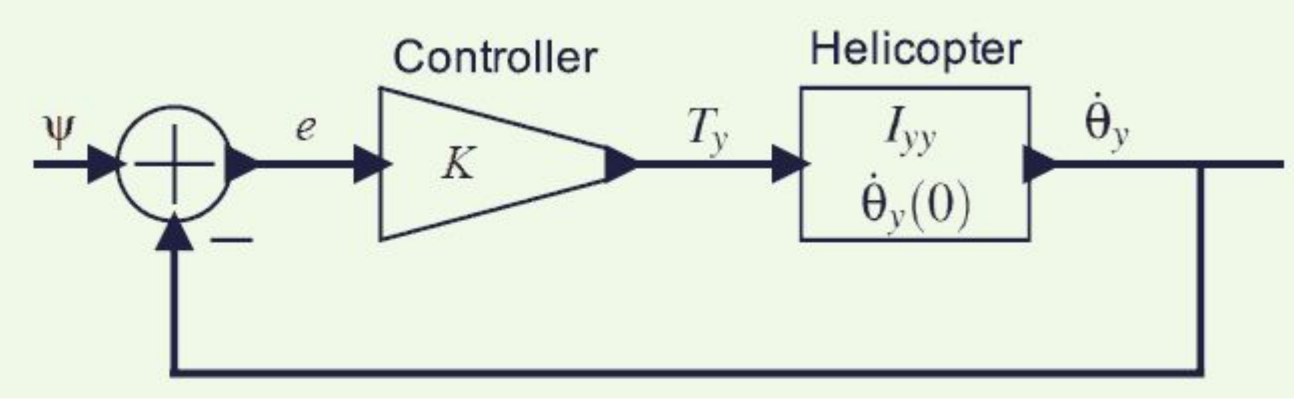
Refences:

[1] Prouty, R. Helicopter Performance, Stability, an Control. PWS Publishers, 2005.
[2] Ponds, P., Mahony, R., Corke, P. Modelling and control of a large quadrotor robot. Control Engineering Practice. 2010.

Questions

- Can the behavior of this controller change when it is implemented in software?
- How do we measure the angular velocity in practice? How do we incorporate noise into this model?
- What happens when you have failures (sensors, actuators, software, computers, or networks) https://www.youtube.com/watch?v=MhEXXgiIVuY

Behavior of the controller



$$\dot{\theta}_y(t) = \dot{\theta}_y(0) + \frac{K}{I_{yy}} \int_0^t (\psi(\tau) - \dot{\theta}_y(\tau)) d\tau$$

Assume that helicopter is initially at rest,

$$\dot{\theta}(0) = 0,$$

and that the desired signal is

$$\psi(t) = au(t)$$

for some constant a.
By calculus (see notes), the solution is

$$\dot{\theta}_y(t) = au(t)(1 - e^{-Kt/I_{yy}})$$