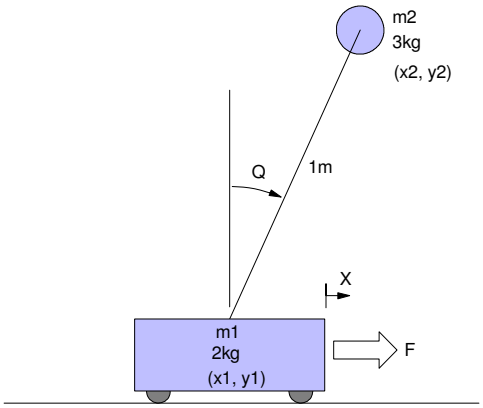
ECE 463/663 - Homework #6

Pole Placement. Due Monday, February 28th

Problem 1) (30pt) Use the dynamics of a Cart and Pendulum System from homework set #4:

$$s\begin{bmatrix} x \\ \theta \\ sx \\ s\theta \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & -14.7 & 0 & 0 \\ 0 & 24.5 & 0 & 0 \end{bmatrix}\begin{bmatrix} x \\ \theta \\ sx \\ s\theta \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0.5 \\ -0.5 \end{bmatrix} F$$



(10pt) Design a feedback control law of the form

U = Kr * R - Kx * X

so that the closed-loop system has

- A 2% settling time of 12 seconds, and
- 10% overshoot for a step input

(10pt) Check the step response of the linear system in Matlab

(10pt) Check the step response of the nonlinear system

Problem 2) (30pt) Use the dynamics for the Ball and Beam system from homework set #4.

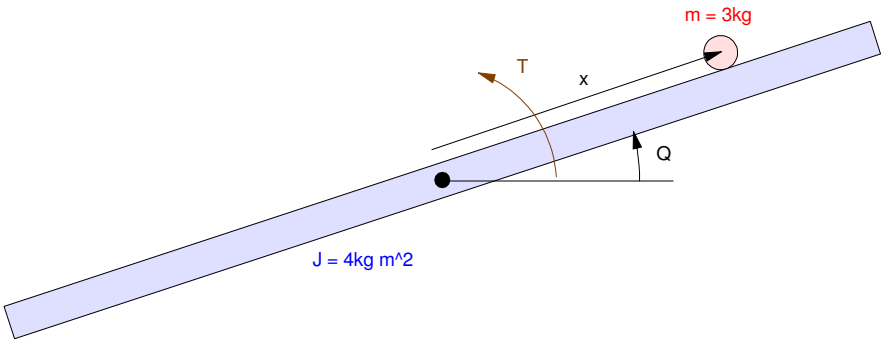
$$s\begin{bmatrix} r \\ \theta \\ sr \\ s\theta \end{bmatrix} = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & -7 & 0 & 0 \\ -4.2 & 0 & 0 & 0 \end{bmatrix}\begin{bmatrix} r \\ \theta \\ sr \\ s\theta \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0 \\ 0.143 \end{bmatrix} T$$

(10pt) Design a feedback control law so that the closed-loop system has

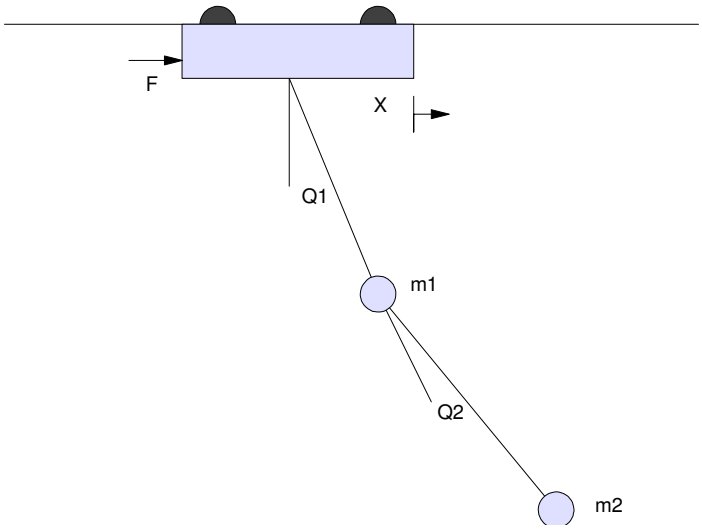
- A 2% settling time of 12 seconds, and
- 10% overshoot for a step input

(10pt) Check the step response of the linear system in Matlab

(10pt) Check the step response of the nonlinear system



Problem #3 (30pt): The dynamics of a double gantry (Gantry2) are



$$s\begin{bmatrix} x \\ \theta_1 \\ \theta_2 \\ \dot{x} \\ \dot{\theta}_1 \\ \dot{\theta}_2 \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 \\ 0 & 2g & 0 & 0 & 0 & 0 \\ 0 & -3g & g & 0 & 0 & 0 \\ 0 & 3g & -3g & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} x \\ \theta_1 \\ \theta_2 \\ \dot{x} \\ \dot{\theta}_1 \\ \dot{\theta}_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \\ -1 \\ 1 \end{bmatrix} F$$

(10pt) Design a feedback control law of the form

U = Kr * R - Kx * X

so that the closed-loop system has

- A 2% settling time of 12 seconds, and
- 10% overshoot for a step input

(10pt) Determine the step response of the linear system in Matlab

(10pt) Determine the step response of the nonlinear system