Contents

Introduction 1

1 Optimal control 11
1.1 Statement of the optimal control problem 11
1.2 The maximum principle 16
1.3 Open-loop and feedback control 21
1.4 Examples 23

2 Method of decomposition (the first approach) 31
2.1 Problem statement and game approach 31
2.1.1 Controlled mechanical system 31
2.1.2 Simplifying assumptions 32
2.1.3 Decomposition 35
2.1.4 Game problem 36
2.2 Control of the subsystem and feedback control design 37
2.2.1 Optimal control for the subsystem 37
2.2.2 Simplified control for the subsystem 42
2.2.3 Comparative analysis of the results 45
2.2.4 Control for the initial system 52
2.3 Weak coupling between degrees of freedom 54
2.3.1 Modification of the decomposition method 54
2.3.2 Analysis of the controlled motions 56
2.3.3 Determination of the parameters 59
2.3.4 Case of zero initial velocities 61
2.4 Nonlinear damping 67
2.4.1 Subsystem with nonlinear damping 67
2.4.2 Control for the nonlinear subsystem 69
2.4.3 Simplified control for the subsystem and comparative analysis 74
2.5 Applications and numerical examples 82
2.5.1 Application to robotics 82

2.5.2 Feedback control design and modelling of motions for two-link manipulator with direct drives 86
2.5.3 Modelling of motions of three-link manipulator 92

3 Method of decomposition (the second approach) 103
3.1 Problem statement and game approach 103
3.1.1 Controlled mechanical system 103
3.1.2 Statement of the problem 105
3.1.3 Control in the absence of external forces 106
3.1.4 Decomposition 108
3.2 Feedback control design and its generalizations 112
3.2.1 Feedback control design 112
3.2.2 Control in the general case 114
3.2.3 Extension to the case of nonzero terminal velocity 117
3.2.4 Tracking control for mechanical system 124
3.3 Applications to robots 131
3.3.1 Symbolic generation of equations for multibody systems . . . 131
3.3.2 Modelling of control for a two-link mechanism (with three degrees of freedom) 136
3.3.3 Modelling of tracking control for a two-link mechanism (with two degrees of freedom) 144

4 Stability based control for Lagrangian mechanical systems 147
4.1 Scleronomic and rheonomic mechanical systems 147
4.2 Lyapunov stability of equilibrium 151
4.3 Lyapunov's direct method for autonomous systems 151
4.4 Lyapunov's direct method for nonautonomous systems 153
4.5 Stabilization of mechanical systems 153
4.6 Modification of Lyapunov's direct method 155

5 Piecewise linear control for mechanical systems under uncertainty . . . 157
5.1 Piecewise linear control for scleronomic systems 157
5.1.1 Problem statement 157
5.1.2 Description of the control algorithm 159
5.1.3 Justification of the algorithm 161
5.1.4 Estimation of the time of motion 166
5.1.5 Sufficient condition for steering the system to the prescribed state 168
5.2 Applications to mechanical systems 170
5.2.1 Control of a two-link manipulator 170
5.2.2 Control of a two-mass system with unknown parameters . . . 173
5.2.3 The first stage of the motion 178
5.2.4 The second stage of the motion 182
5.2.5 System "a load on a cart" 186
5.2.6 System "a pendulum on a cart" 187

5.2.7 Computer simulation results . . . 197
5.3 Piecewise linear control for rheonomic systems . . . 199
5.3.1 Problem statement . . . 199
5.3.2 Control algorithm for rheonomic systems . . . 200
5.3.3 Justification of the control . . . 201
5.3.4 Results of simulation . . . 210

6 Continuous feedback control for mechanical systems under uncertainty . . . 213
6.1 Feedback control for scleronomic system with a given matrix of inertia . . . 213
6.1.1 Problem statement . . . 213
6.1.2 Control function . . . 214
6.1.3 Justification of the control . . . 217
6.1.4 Sufficient condition for controllability . . . 222
6.1.5 Computer simulation results . . . 223
6.2 Control of a scleronomic system with an unknown matrix of inertia 229
6.2.1 Problem statement . . . 229
6.2.2 Computer simulation of the motion of a two-link manipulator 234
6.3 Control of rheonomic systems under uncertainty . . . 237
6.3.1 Problem statement . . . 237
6.3.2 Computer simulation results . . . 241

7 Control in distributed-parameter systems . . . 245
7.1 System of linear oscillators . . . 245
7.1.1 Equations of motion . . . 245
7.1.2 Decomposition . . . 246
7.1.3 Time-optimal control problem . . . 248
7.1.4 Upper bound for the optimal time . . . 249
7.2 Distributed-parameter systems . . . 252
7.2.1 Statement of the control problem for a distributed-parameter system . . . 252
7.2.2 Decomposition . . . 254
7.2.3 First-order equation in time . . . 257
7.2.4 Second-order equation in time . . . 258
7.2.5 Analysis of the constraints and construction of the control . . 259
7.3 Solvability conditions . . . 263
7.3.1 The one-dimensional problems . . . 263
7.3.2 Control of beam oscillations . . . 266
7.3.3 The two-dimensional and three-dimensional problems . . . 267
7.3.4 Solvability conditions in the general case . . . 270

8 Control system under complex constraints 275
8.1 Control design in linear systems under complex constraints 275
8.1.1 Problem statement 275
8.1.2 Kalman's approach 277
8.2 Application to oscillating systems 281
8.2.1 Control for the system of oscillators 281
8.2.2 Pendulum with a suspension point controlled by acceleration 286
8.2.3 Pendulum with a suspension point controlled by acceleration (continuation) 290
8.2.4 Pendulum with a suspension point controlled by velocity . . . 296
8.3 Application to electro-mechanical systems 303
8.3.1 Model of the electro-mechanical system 303
8.3.2 Analysis of the simplified model 306
8.3.3 Control of the electro-mechanical system of the fourth order 310
8.3.4 Active dynamical damper 317

9 Optimal control problems under complex constraints 327
9.1 Time-optimal control problem under mixed and phase constraints . . 328
9.1.1 Problem statement 328
9.1.2 Time-optimal control under constraints imposed on the velocity and acceleration 329
9.1.3 Problem of control of an electric motor 335
9.2 Time-optimal control under constraints imposed on the rate of change of the acceleration 340
9.2.1 Statement of the problem 340
9.2.2 Open-loop optimal control 342
9.2.3 Feedback optimal control 345
9.3 Time-optimal control under constraints imposed on the acceleration and its rate 354
9.3.1 Problem statement 354
9.3.2 Possible modes of control 357
9.3.3 Construction of the trajectories 359

10 Time-optimal swing-up and damping feedback controls of a nonlinear pendulum 367
10.1 Optimal control structure 368
10.1.1 Statement of the problem 368
10.1.2 Phase cylinder 369
10.1.3 Maximum principle 370
10.1.4 Numerical algorithm 371
10.2 Swing-up control 372
10.2.1 Literature overview 372
10.2.2 Special trajectories 373
10.2.3 Numerical results 375
10.3 Damping control 380

10.3.1 Literature overview 380
10.3.2 Special trajectories 382
10.3.3 Numerical results 383
References 389

Index 395