



Faculty of Manufacturing Engineering

**DESIGN OF LINEAR QUADRATIC REGULATOR CONTROLLER
WITH ADJUSTABLE GAIN FUNCTION FOR ROTARY INVERTED
PENDULUM SYSTEM**

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Master of Science in Manufacturing Engineering

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**DESIGN OF LINEAR QUADRATIC REGULATOR CONTROLLER WITH
ADJUSTABLE GAIN FUNCTION FOR ROTARY INVERTED PENDULUM
SYSTEM**

TANG TENG FONG

**A thesis submitted
in fulfilment of the requirements for the degree of Master of Science
in Manufacturing Engineering**

Faculty of Manufacturing Engineering

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2015

DECLARATION

I declare that this thesis entitled “Design of linear quadratic regulator controller with adjustable gain function for rotary inverted pendulum system” is the result of my own research except as cited in the references. The thesis has not been accepted for any degree and is not concurrently submitted in candidature of any other degree.

Signature :

Name : Tang Teng Fong

Date :

APPROVAL

I hereby declare that I have read this thesis and in my opinion this thesis is sufficient in terms of scope and quality for the award of Master of Science in Manufacturing Engineering.

Signature :

Supervisor's Name : Associate Prof. Dr. Zamberi bin Jamaludin

Date :

DEDICATION

To my beloved parents, Tang Chin Siang and Ong Geok Ee,
For taking good care and giving guidance in life and academic.

To my concerned sister, Tang Hoay Sean,

For giving moral support.

And also for those I love very much.

ABSTRACT

Design of controllers for non-linear systems has long drawn the attention of researchers especially in the fields of robotics, aerospace engineering and marine engineering. A classic example of a non-linear under-actuated control system is the balance control for a rotary inverted pendulum. Basically, the control approach for such system focusses on torque control of the servo-motor for the purpose of rotating the arm and stabilising the pendulum in its upright position at the shortest possible time. The aim of this research is to supplement and further enhance the control performance of a linear quadratic regulator (LQR) controller with focus on reduced response time and degree of oscillation of the pendulum with added robustness against input disturbance applied to the pendulum position and voltage to the motor. Initially, this thesis comprehensively analysed the LQR controller parameters based on minimal balance time of the pendulum. The LQR controller by itself produced high degree of oscillations, long balance time and poor robustness against input disturbance. As an enhancement over this approach, an adjustable gain was added to the existing LQR control structure. The results showed that for a 30° balancing control, the LQR controller with adjustable gain managed to reduce as much as 70% in the balance time and 98% in the degree of oscillation, while improved its robustness by producing faster balance time and lower oscillation upon excitation by input disturbance forces. In conclusion, the LQR controller with adjustable gain has significantly improved the control performance of the rotary inverted pendulum system.

ABSTRAK

Reka bentuk pengawal untuk sistem tidak linear telah sekian lama menarik perhatian penyelidik-penyelidik terutamanya dalam bidang robotik, kejuruteraan aeroangkasa dan kejuruteraan marin. Satu contoh klasik sistem kawalan tak lurus yang kurang pacu gerak, ialah kawalanimbangan untuk bandul terbalik berputar. Pada asasnya, kaedah kawalan sistem sebegini berfokus kepada kawalan tork pada motor servo bagi tujuan memutar lengan dan menstabilkan bandul dalam kedudukan tegak pada masa paling singkat yang mungkin. Tujuan penyelidikan ini ialah untuk menambah dan meningkatkan lagi prestasi pengawal pengatur linear kuadratik (LQR) dengan fokus kepada pengurangan masa tindak balas bandul dan darjah ayunan dengan peningkatan keteguhan terhadap gangguan input pada kedudukan bandul dan voltan kepada motor. Tesis ini pada awalnya menganalisa secara komprehensif parameter pengawal LQR berdasarkan masa minima imbang bandul. Pengawal LQR dengan sendirinya menghasilkan darjah ayunan yang tinggi, masa imbang yang panjang dan tahap keteguhan yang rendah terhadap gangguan input. Sebagai satu peningkatan atas pengawal ini, satu pekali boleh laras ditambah kepada struktur pengawal LQR sedia ada. Keputusan yang diperolehi untuk kawalan keseimbangan 30° menunjukkan yang pengawal LQR dengan pekali boleh laras telah menurunkan sehingga 70% masa imbang dan 98% darjah ayunan serta memperbaiki tahap keteguhan sistem dengan menghasilkan masa imbang yang lebih cepat dan darjah ayunan yang lebih rendah apabila terdedah kepada gangguan input. Secara kesimpulannya, pengawal LQR yang ditambah baik dengan pekali boleh laras telah memperbaiki secara jelas prestasi kawalan sistem bandul terbalik berputar ini.

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TABLE OF CONTENTS

	PAGE
DECLARATION	
APPROVAL	
DEDICATION	
ABSTRACT	i
ABSTRAK	ii
ACKNOWLEDGEMENTS	iii
TABLE OF CONTENTS	iv
LIST OF TABLES	vi
LIST OF FIGURES	vii
LIST OF APPENDICES	xi
LIST OF ABBREVIATIONS	xii
LIST OF SYMBOLS	xiv
LIST OF PUBLICATIONS	xviii
CHAPTER	
1. INTRODUCTION	1
1.1 Background	1
1.2 Problem Statement	2
1.3 Objectives	3
1.4 Scopes	3
1.5 Significance of Study	4
1.6 Outline of Thesis	5
2. LITERATURE REVIEW	6
2.1 Inverted Pendulum System	6
2.1.1 Linear Inverted Pendulum	7
2.1.2 Rotary Inverted Pendulum	9
2.2 Application of Inverted Pendulum System	10
2.3 Controller Design for Balance Control of Inverted Pendulum	12
2.3.1 Proportional Integrated Derivative Controller	13
2.3.2 Linear Quadratic Regulator Controller	14
2.3.3 Sliding Mode Controller	17
2.3.4 Fuzzy Logic Controller	18
2.4 Summary	20
3. EXPERIMENTAL SETUP AND SYSTEM IDENTIFICATION	22
3.1 Project Planning	22
3.2 Experimental Setup	24
3.3 System Identification and Modelling	26
3.3.1 Mathematical Model	28
3.3.1.1 Non-linear Mathematical Model	31
3.3.1.2 Linearization of Non-linear Mathematical Model	32
3.3.1.3 State-space Model for the Pendulum in Upright Position	33

	3.3.1.4	State-space Model for the Pendulum in Downward Position	35
	3.3.2	Frequency Response Method	37
	3.3.3	Validation of System Model	39
3.4		Summary	40
4.		Controller Design	42
	4.1	Introduction	42
	4.2	Design of Linear Quadratic Regulator Controller	43
	4.2.1	Numerical Analysis	46
	4.3	Design of Linear Quadratic Regulator Controller with Adjustable Gain Function	54
	4.4	Summary	62
5.		RESULT AND DISCUSSION	63
	5.1	Analysis of Control Performance	63
	5.2	Analysis of Control Performance with Applied Disturbance	67
	5.2.1	Disturbance at Input Voltage	67
	5.2.2	Input Disturbance at the Pendulum Position	74
	5.3	Analysis of Tracking Control Performance	78
	5.4	Summary	81
6.		CONCLUSION AND FUTURE STUDY	83
	6.1	Conclusion	83
	6.2	Recommendation and Future Study	84
		REFERENCES	86
		APPENDICES	90

LIST OF TABLES

TABLE	TITLE	PAGE
3.1	Mechanical and electrical system parameters based on Teraoft (2009)	30
4.1	Summary on effects of Q matrix on control performance	50
4.2	Average gain for the first trial data	57
4.3	Average gain values of 5 trials	58
5.1	Analysis result of the pendulum oscillation	66
5.2	Summary of percentage reduction in the pendulum oscillation for disturbance input voltage at two different time locations	71
5.3	Analysis of pendulum oscillation results with the disturbance applied at the pendulum position for first input disturbance and second input disturbance	77
G.1	Trial 1	111
G.2	Trial 2	111
G.3	Trial 3	111
G.4	Trial 4	111
G.5	Trial 5	112
G.6	Trial 6	112

LIST OF FIGURES

FIGURE	TITLE	PAGE
2.1	Simplified linear inverted pendulum	8
2.2	Simplified rotary inverted pendulum	9
2.3	The Segway personal transporter	11
2.4	HRP-4C Humanoid	11
2.5	Transporting the loads by using a crane	11
3.1	Flow chart of overall methodology	22
3.2	Experimental setup of rotary inverted pendulum	24
3.3	System setup of EMECS	25
3.4	Rotary inverted pendulum from TeraSoft	25
3.5	Flow chart of the system identification and modelling	27
3.6	Free body diagram of a rotary inverted pendulum	29
3.7	Schematic diagram of a rotary inverted pendulum when the pendulum is in the upright position	32
3.8	Schematic diagram of a rotary inverted pendulum when the pendulum is in the downward position	35
3.9	Simulink diagram for FRF measurement	38
3.10	Comparison between system FRF, parametric model and mathematical model in frequency response	39
4.1	Flow chart of the controller design	42
4.2	Balance interval of pendulum for the analysis of the Q parameter	45
4.3	The LQR simulation control scheme	46

4.4	Effect of Q_1 on (a) arm and (b) pendulum angular positions	47
4.5	Effect of Q_2 on (a) arm and (b) pendulum angular positions	48
4.6	Effect of Q_3 on (a) arm and (b) pendulum angular positions	48
4.7	Effect of Q_4 on (a) arm and (b) pendulum angular positions	49
4.8	Simulation results for balance control of the LQR controller for angular positions of the (a) arm and (b) pendulum	52
4.9	Direction of (a) arm rotation and (b) pendulum rotation in actual system	53
4.10	The LQR experiment control scheme	53
4.11	Experimental result of the LQR controller for pendulum	54
4.12	Result of the first trial data for the angular position of the pendulum and the angular velocity of the arm in rejecting disturbance forces using only the LQR controller	56
4.13	The graph of arm velocity against pendulum position	59
4.14	A schematic diagram of the LQR control scheme with added adjustable gain	60
4.15	Balance interval of pendulum for the LQR controller with adjustable gain	61
5.1	Experimental result for balance control of the LQR controller and the improved LQR controller for angular positions of the (a) arm and (b) pendulum	64
5.2	Analysis of control performance in terms of the pendulum oscillation	65
5.3	The improved LQR control scheme with disturbance applied as input voltage	68
5.4	Characteristics of disturbance input voltage in signal builder	68
5.5	Input disturbance signal and experimental result of the pendulum with disturbance applied as input voltage	69
5.6	Analysis of control performance with disturbance applied as input voltage for (a) first input disturbance and (b) second input disturbance	70
5.7	Schematic diagram of the input disturbance at different direction as the balance control	72

5.8	Schematic diagram of the input disturbance in the same direction as the balance control	73
5.9	The improved LQR control scheme with disturbance applied at the pendulum position	74
5.10	Continuous disturbance signal passed at the pendulum position	75
5.11	Experimental results for the system with disturbance input applied at the pendulum position	75
5.12	Analysis of control performance with disturbance applied at the pendulum position for (a) first input disturbance and (b) second input disturbance	77
5.13	Step input signal and the improved LQR control scheme for tracking performance	79
5.14	Step input signal and the measured angular position of the arm with the step input	80
5.15	Measured angular position of the pendulum with the input step function	80
E.1	Rotary inverted pendulum system	102
E.2	3-1	102
E.3	3-2	103
E.4	3-3	103
E.5	3-4	103
E.6	4-1	104
E.7	4-2	104
E.8	4-3	104
F.1	The LQR experiment Simulink diagram	105
F.2	The LQR with adjustable gain experiment Simulink diagram	105
F.3	Simulink diagram for the disturbance applied as input voltage	106
F.4	Simulink diagram for the disturbance applied at the pendulum position	106

F.5	Simulink diagram for the tracking performance	107
G.1	Trial 1	108
G.2	Trial 2	109
G.3	Trial 3	109
G.4	Trial 4	110
G.5	Trial 5	110

LIST OF APPENDICES

APPENDIX	TITLE	PAGE
A	Determination of Linear Mathematical Model for the Pendulum in Upright Position	90
B	Determination of State-space Model for the Pendulum in Upright Position	94
C	Determination of Linear Mathematical Model for the Pendulum in Downward Position	96
D	Determination of State-space Model for the Pendulum in Downward Position	100
E	Rotary Inverted Pendulum System Scheme	102
F	Simulink Block Diagrams of the LQR Control Scheme and the LQR with Adjustable Gain Function Control Scheme	105
G	Determination of the Adjustable Gain Function	108

LIST OF ABBREVIATIONS

AC/DC	-	Analogue converter/ digital converter
ACO	-	Ant colony optimization
ADC	-	Analogue-to-digital converter
D	-	Derivative
DAC	-	Digital-to-analogue converter
DAQ	-	Data acquisition system
DC	-	Direct current
DOF	-	Degree of freedom
EMECS	-	Electro-Mechanical Engineering Control System
FL	-	Fuzzy logic
FRF	-	Frequency response function
FSF	-	Full state feedback
GA	-	Genetic algorithm
GPIO	-	General-purpose input/output
I	-	Integral
LIP	-	Linear inverted pendulum
LQR	-	Linear quadratic regulator
P	-	Proportional
PC	-	Personal computer
PID	-	Proportional integrated derivative
PWM	-	Pulse-width modulation

- RIP - Rotary inverted pendulum
- SMC - Sliding mode controller
- TORA - Translational oscillations with a rotational actuator
- VSC - Variable structure control
- VTOL - Vertical take-off and landing

LIST OF SYMBOLS

Mathematical Symbol:

\approx	-	Approximately equivalent
∞	-	Infinity
Ω	-	Ohm
$\frac{\partial f}{\partial x}$	-	Partial derivative
π	-	Pi
\pm	-	Plus or minus
-	-	Minus
%	-	Percentage
/	-	Divide
+	-	Plus
=	-	Equal
A	-	Ampere
\cos	-	Cosine
dB	-	Decibel
$f(x)$	-	Function notation
G	-	Gravitational acceleration
Hz	-	Hertz
kg	-	Kilogram
m	-	Meter
N	-	Newton

$^{\circ}$	-	Degree
rad	-	Radian
s	-	Second
\sin	-	Sine
t	-	Time
T	-	Transpose
V	-	Volt

System Model Symbol:

$\ddot{\theta}_1$	-	Angular acceleration of arm
$\ddot{\theta}_2$	-	Angular acceleration of pendulum
$\ddot{\alpha}_2$	-	Angular acceleration of pendulum (downward position)
θ_1	-	Angular position of arm
θ_2	-	Angular position of pendulum
α_2	-	Angular position of pendulum (downward position)
$\dot{\theta}_1$	-	Angular velocity of arm
$\dot{\theta}_2$	-	Angular velocity of pendulum
$\dot{\alpha}_2$	-	Angular velocity of pendulum (downward position)
R_m	-	Armature resistance
τ_1	-	Control torque
e	-	Control voltage
c_1	-	Distance to centre of arm mass
c_2	-	Distance to centre of pendulum mass
J_1	-	Inertia of arm

J_2	-	Inertia of pendulum
l_1	-	Length of arm
l_2	-	Length of pendulum
m_1	-	Mass of arm
m_2	-	Mass of pendulum
K_b	-	Motor back-emf constant
K_u	-	Motor driver amplifier gain
K_t	-	Motor torque constant
C_1	-	Viscous friction co-efficient of arm
C_2	-	Viscous friction co-efficient of pendulum

Control System Symbol:

\dot{x}	-	Future state
A	-	System matrix
B	-	Control matrix or input matrix
C	-	Output matrix
D	-	Feed forward matrix
$G(s)$	-	Transfer function of system model
$G_{PID}(s)$	-	Transfer function of PID controller
J	-	Quadratic performance index
K_d	-	Derivative gain (PID controller)
K_d	-	State-feedback gains (LQR controller)
K_i	-	Integral gain
m	-	Adjustable gain
Q	-	Diagonal weight matrix

R	-	Weight factor
S	-	Riccati solution
T_s	-	Sampling time
u	-	Input
$u(t)$	-	Input signal
x	-	Current state
$y(t)$	-	Output

LIST OF PUBLICATIONS

Journal:

1. Fong, T.T., Jamaludin, Z. and Abdullah, L., 2014. System Identification and Modelling of Rotary Inverted Pendulum. *International Journal of Advances in Engineering & Technology (IJAET)*, 6(6), pp. 2342–2353.

Conference:

1. Fong, T.T., Jamaludin, Z., Hashim, A.Y.B. and Rahman, M.A.A., 2014. Design and Analysis of Linear Quadratic Regulator for a Non-linear Positioning System. *3rd International Conference on Design and Concurrent Engineering (iDECON)*, Melaka, 22nd – 23rd September 2014. [Accepted]

CHAPTER 1

INTRODUCTION

This chapter introduces the research work on control system design and development for rotary inverted pendulum (RIP). Sections included in this chapter are the background of the RIP system, problem statement, outlines of research, objectives, scopes, and the content of this thesis. In addition, a segment on contribution to knowledge based on the research work done is also included.

1.1 Background

Since the last few decades, control system design for non-linear and under-actuated systems has generated great interest among researchers. These interests cover a wide spectrum of applications that include control of a space booster rocket, satellite, an automatic aircraft landing system, and stabilisation of a robot. Rotary inverted pendulum (RIP) system is an example of a classical under-actuated system. The RIP consists of a rigid rod called pendulum, which is rotating freely in the vertical plane. The vertical pendulum is naturally unstable with the oscillation as it hangs downward at the equilibrium point. A swing-up action using rotary actuation of a pivot arm in the horizontal plane by a servo-motor would then result in the vertical pendulum achieving upright equilibrium point. A robust and stable controller must be applied in order to control the torque of the servo-motor for the purpose of rotating the arm and stabilising the pendulum in upright position.

The balancing control of a pendulum in the upright position is studied in this research. Firstly, the system model was derived mathematically using Lagrange's