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# Hybrid integrator-gain based elements for nonlinear motion control

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## 1 Introduction

To meet future performance specifications, the product roadmap of high-precision mechatronic systems is typically translated toward servo-control in the direction of increased controller bandwidths. However, using linear control elements, the associated bandwidth is often limited by Bode's gain-phase relationship. In order to possibly surpass this fundamental limitation, recently in [1] a hybrid integrator-gain element (HIGS) has been introduced. Depending on specific switching conditions, this element switches between an integrator and gain mode in such a manner that the output is continuous, confined to a sector, and always of equal sign to the input. As such, the corresponding describing function  $\mathcal{D}(j\omega)$  demonstrates first-order low-pass characteristics with a phase lag of only 38.15 degrees. Driven by the apparent phase advantage, in this abstract the idea of HIGS-based controller elements for bandwidth improvements of essentially linear systems is discussed.

## 2 HIGS-Based Controller Elements

A HIGS-based controller element is proposed as the series interconnection of the HIGS and a linear filter  $\mathcal{N}(s)$ . Through specific design of this filter, the element's describing function

$$\mathcal{D}_{NL}(j\omega) = \mathcal{D}(j\omega)\mathcal{N}(j\omega), \quad (1)$$

can be shaped in such a manner that it has desirable magnitude characteristics with reduced phase lag. For the purpose of example, consider the HIGS in series with a filter  $\mathcal{N}(s)$ , given in frequency domain by:

$$\mathcal{N}(s) = \frac{\omega_p^2}{\omega_2} \cdot \frac{1}{s + \omega_1} \cdot \frac{(s + \omega_1)(s + \omega_2)}{s^2 + 2\beta\omega_p s + \omega_p^2}, \quad (2)$$

with corner frequencies  $\omega_i$ ,  $i \in \{1, 2\}$ ,  $\omega_p$ , and dimensionless damping coefficient  $\beta$ . It follows from the first-order low-pass characteristics of the HIGS, that by appropriate tuning of  $\omega_2$  in (2), the describing function (1) has similar magnitude characteristics as a classical linear second-order low-pass filter with complex poles, however, with significantly reduced phase lag. From a linear point-of-view, elements with such apparent properties could potentially aid the loopshaping design, and give rise to increased bandwidths.

## 3 Wafer Stage Measurement Results

To illustrate the potential of a HIGS-based controller, the nonlinear second-order low-pass filter is experimentally em-

bedded in the motion control context of Fig. 1. Here,  $\mathcal{C}$  is some base-linear controller (e.g. PID and notch filters) and  $\mathcal{P}$  represents a scanning stage of an industrial wafer scanner. Using a quasi-linear loopshaping procedure, eval-

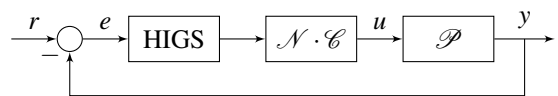


Figure 1: Feedback control structure.

uated through describing functions, the controller is structurally tuned and shows a bandwidth improvement of around 11% compared to an optimal linear controller design. Time-domain measurement results of several experiments are presented in Fig.2 in terms of the moving average  $\mathcal{M}_A$  and the moving standard deviation  $\mathcal{M}_{SD}$ . These performance measures reflect the low- and high-frequency content of the measured data-sampled error  $e(t)$ , respectively. The results of the nonlinear controller (red) are compared to those of an optimally tuned linear controller (black). A substantial im-

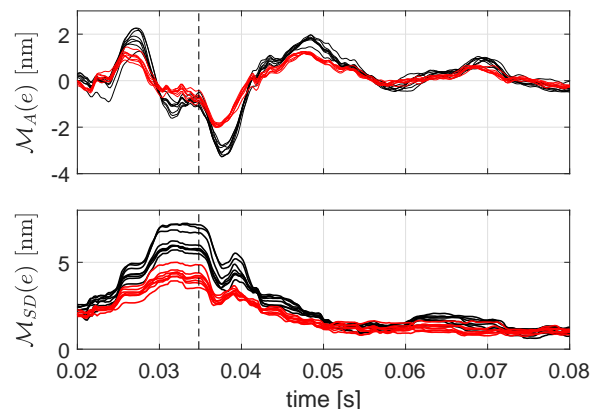


Figure 2: Moving average  $\mathcal{M}_A(e)$  and moving standard deviation  $\mathcal{M}_{SD}(e)$  for the linear (black) and nonlinear (red) closed-loop system.

provement in low-frequency disturbance suppression can be observed, without deterioration of the  $\mathcal{M}_{SD}$ . Although no rigorous stability criteria for the true nonlinear system are specified, this real-world closed-loop example shows convincingly robustly stable behavior.

## References

- [1] D.A. Deenen, M.F. Heertjes, W.P.M.H. Heemels and H. Nijmeijer, Hybrid integrator design for enhanced tracking in motion control, *American Control Conference*, (2017).