

Fig. 2. Experimental setup.

3. Experimental results

3.1. Experimental setup

The laboratory prototype consist of a servomotor from Moog, model C34-L80-W40 (Fig. 2) driven by a Copley Controls power servoamplifier, model 423, configured in current mode. A BEI optical encoder, model L15 with 2500 pulses per revolution, allows measuring the servomotor position. The algorithms are coded using the MatLab/Simulink software platform under the program Wincon from Quanser Consulting, and a Quanser Consulting. Q8 board performs data acquisition. The data card electronics increases four times the optical encoder resolution up to 2500 ×. 4 = 10 000 pulses per revolution. The control signal produced by the Q8 board passes through a galvanic isolation box. The software runs on a personal computer using an Intel Core 2 quad processor. and the Q8 board is allocated in a PCI slot inside this computer. The following transfer function, which is composed of a high-pass filter in cascade with a low-pass filter, allows obtaining velocity estimates from position measurements

$$G(s) = \frac{400s}{s + 400} \frac{500}{s + 500}$$

The low pass filter attenuates the high frequency components of the position signal. The Simulink diagrams use a sampling period of 0.1 ms and the ODE5 solver. Fig. 2 depicts the experimental setup.

3.2. Experiments

3.2.1. Parameter identification

Two Duffing systems generate the signal used for exciting the servomechanism

$$\dot{x}_{1i} = x_{2i}\omega_{0}\pi$$
 (31)
 $\dot{x}_{2i} = [-0.25 + x_{2i} + x_{1i} - 1.05x_{1i}^{3} + 0.3 \sin(\omega_{0}\pi t)]\omega_{0}\pi$; $i = 1, 2$
 $s_{r} = 7x_{11} - 5x_{32}$; $x_{3i}(0) = 0$; $x_{2i}(0) = 0$;
 $\omega_{1} = 1 \text{ rad/s}$; $\omega_{2} = 2 \text{ rad/s}$,

This type of chaotic excitation was proposed in [24] for parameter identification of a speed controlled servomotor. Fig. 3 shows the time evolution of s_e . The gains for the PD controller are $k_p = 10$ and $k_d = 0.28$, and the update law gains are I' = diag [12 3000 180 90].

Fig. 4 shows the time evolution of the parameter estimates obtained using the proposed approach. Fig. 5 depicts the input error e_a and the evaluation of the PE condition (30) with $w = \frac{1}{2} \begin{bmatrix} 1 & 1 & 1 \end{bmatrix}^T$; the values for the PE condition in Fig. 5(b) are

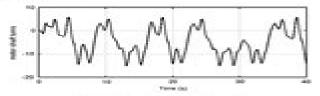
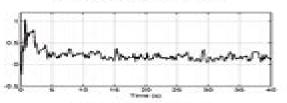
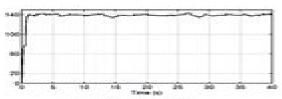


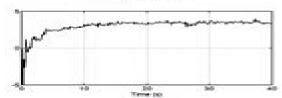
Fig. 3. Chaotic excitation signal.



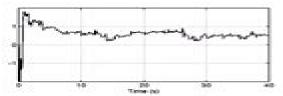
Parameter estimate à



Parameter estimate 5



Parameter estimate &



Panameter estimate al.

Fig. 4. Parameter estimates obtained using the CLIE method: å. å. å. and ål.

shown every five seconds, i.e. 3 = 5 s. Hence, the regressor vector fulfills the PE condition during the experiment. Table 1 shows the parameter estimates obtained from the experiment. They were

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United States. Wright Air Development Division

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WADC Technical Report United States. Wright Air Development Division,1954 The Analysis and Synthesis of **Linear Servomechanisms** Albert C. Hall, 1942-12 A standard reference on the application of network theory to the design of automatic control systems The 1943 printing of The Analysis and Synthesis of Linear Servomechanisms was classified as restricted and distributed accordingly After the close of WWII the book was declassified in order to permit general dissemination of the material From the Preface This book is a formulation of a servomechanism design procedure based primarily upon an analysis of the system response to sinusoidal inputs of various frequencies Although a knowledge of the transient performance of a servomechanism provides an excellent basis for predicting the response of the system to the conditions of a particular application the complexity of most physical systems makes the computation of the transient performance and the translation of the resulting information into physical design criteria extremely laborious On the other hand knowledge of the response of the servomechanisms to sinusoidal inputs is not quite as useful in enabling a prediction to be made of the servo response to the conditions of most practical applications but the computation of the sinusoidal response and the translation of this information into useful design criteria are much simpler A Differential Analyzer Study of Certain Nonlinearly Damped Servomechanisms for Various Input Signals Ralph Russell Caldwell,1952 Handbook of Supersonic Aerodynamics R. J. Volluz, 1961 Research in Nonlinear Mechanics as Applied to Servomechanisms Cook Electric Company. Cook Research Laboratories, 1954 Handbook of Supersonic Aerodynamics Johns Hopkins University. Applied Physics Laboratory, 1961 Technical Abstract Bulletin ,1964 **Applied Mechanics Reviews** .1974 **AFPTRC-TN.** ,1956 United States Air Force Academy United States Air Force Academy, 1963 Annual Catalog - United States Air Force Academy United States Air Force Academy, 1962 Current Hydraulic Laboratory

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