

STABILITY OF A TWO WHEELS MOBILE ROBOT USING ROBUST CONTROL

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SUPERVISOR'S DECLARATION

“I hereby acknowledge that the scope and quality of this thesis is qualified for the award of the Bachelor Degree of Electrical Engineering (Control and Instrumentation)”

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Date : **23 NOVEMBER 2009**

Dedicated to My mother, father, lectures, brothers and sisters.

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Alhamdulillah, I am greatly indebted to ALLAH SWT on His blessing upon completing this project successfully.

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ABSTRACT

The research on two wheels mobile robots or commonly known as balancing robots have gained momentum over the last decade in a number of robotic laboratories around the world. The objectives of this thesis are to present a modeling of a two wheels mobile robot and the design of Sliding Mode Control (SMC) for the system. A robust controller based on Sliding Mode Control is proposed to perform the robust stabilization and disturbance rejection of the system. In order to compensate the disturbances, position, speed, angle and angle rate of the two wheels mobile robot will be observed. The performance of the proposed controller will be compared to the pole placement techniques. A computer simulation study is carried out to access the performance of the proposed control law.

ABSTRAK

Penyelidikan tentang robot mobil dua roda atau yang biasa dikenali sebagai robot keseimbangan telah mendapatkan momentum selama sedekad terakhir di sejumlah makmal robot di seluruh dunia. Objektif daripada tesis ini adalah untuk menerbitkan model untuk sebuah sistem robot mobil dua roda dan reka bentuk “Sliding Mode Control” (SMC) untuk sistem ini. Sebuah pengawalan yang kukuh berdasarkan “Sliding Mode Control” (SMC) dicadangkan untuk melakukan keseimbangan dan menghapuskan gangguan terhadap sistem. Dalam rangka untuk mengkompensasi gangguan, kedudukan, kelajuan, sudut dan sudut laju daripada robot mobil dua roda akan diamati. Prestasi kawalan yang dicadangkan akan dibandingkan dengan teknik “Pole Placement”. Sebuah pelajaran simulasi komputer dilakukan untuk mencapai prestasi kawalan yang dicadangkan hukum.

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TABLE OF CONTENTS

CHAPTER	TITLE	PAGE
	DECLARATION	ii
	DEDICATION	iii
	ACKNOWLEDGEMENT	iv
	ABSTRACT	v
	ABSTRAK	vi
	TABLE OF CONTENTS	viii
	LIST OF APPENDICES	xi
	LIST OF TABLES	xii
	LIST OF FIGURES	xiii
	LIST OF SYMBOLS	xiv
	LIST OF ABBREVIATIONS	xv
1.	INTRODUCTION	
	1.1. Project Overview	1
	1.2. Objective Research	2
	1.3. Scope of Project	3
	1.4. Problem Statement	3
	1.5. Research Methodology	4
	1.6. Literature Review	6
	1.7. Layout of Thesis	7

2. SYSTEM MODEL

2.1. Introduction	8
2.2. System Model for Two Wheels Mobile Robot	8
2.3. Disturbance Profile	14
2.4. Conclusion	15

**3. CONTROLLER DESIGN FOR TWO WHEELS
MOBILE ROBOT SYSTEM**

3.1. Introduction	16
3.2. Overview on Sliding Mode Control	16
3.2.1. Sliding Mode Control Design	17
3.2.2. Switching Surface Design	18
3.2.3. Stability During Sliding Mode	20
3.2.4. SMC Controller Design	21
3.3. Overview on Pole Placement	24
3.3.1. Pole Placement Controller Design	24
3.4. Conclusion	26

4. SIMULATIONS

4.1. Introduction	27
4.2. Simulations on SMC Controller	27
4.2.1. Performance of SMC on Disturbance Profiles	30

4.2.2.	Effect on varying the value of C	30
4.2.3.	Effect of the Stability of Two Wheels Mobile Robot on Varying Sliding Gain, ρ .	32
4.2.4.	Effect on varying the value of boundary layer thickness, δ	34
4.3.	Simulations on Pole Placement Controller	36
4.4.	Results And Discussion	37
4.4.1.	Simulation Of SMC Controller and Pole Placement Controller for Position	38
4.4.2.	Simulation of SMC Controller and Pole Placement Controller for speed	39
4.4.3.	Simulation of SMC Controller and Pole Placement Controller for angle	40
4.4.4.	Simulation of SMC Controller and Pole Placement Controller for angle rate	41
4.5.	Conclusion	42

5. CONCLUSION AND RECOMMENDATIONS

5.1.	Conclusion	43
5.2.	Strength and Weakness	44
5.3.	Suggestion for Future Work	45
5.4.	Costing And Commercialization	45

REFERENCES	46
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APPENDICES

LIST OF APPENDICES

APPENDIX	TITLE	PAGE
A	Two Wheels Mobile Robot System With SMC Controller	48
B	Two Wheels Mobile Robot Plant	50
C	SMC Controller Model	52
D	Pole Placement Controller Model	54
E	Matlab Command for Simulations Of Two Wheels Mobile Robot System	56
F	MATLAB Command for Calculations Of The Value A_{23} , A_{43} , B_2 , B_4 , X , And Y	59

LIST OF TABLES

TABLE	TITLE	PAGE
Table 2.1	Parameters of two wheels mobile robot	10
Table 4.1	Result from simulation for position control of SMC controller and Pole placement controller	38
Table 4.2	Result from simulation for speed control of SMC controller and Pole placement controller	39
Table 4.3	Result from simulation for angle control of SMC controller and Pole placement controller	40
Table 4.4	Result from simulation for angle rate control of SMC controller and Pole placement controller	42

LIST OF FIGURES

FIGURE	TITLE	PAGE
Figure 1.1	Methodology flow chart	4
Figure 2.1	Coordinate system of the Two Wheels Mobile Robot	9
Figure 2.2	Disturbance profile	14
Figure 4.1	Control Input signal	29
Figure 4.2	$C = [4 \ 0.91 \ 2.75 \ 0.46]$, $\rho = 0.15$, $\delta = 0.05$	29
Figure 4.3	$C = [2 \ 0.91 \ 5.75 \ 7.46]$	31
Figure 4.4	$C = [1.2 \ 4.91 \ 0.75 \ 0.46]$	31
Figure 4.5	Sliding gain, $\rho = 1.50$	32
Figure 4.6	Sliding gain, $\rho = 0.015$	33
Figure 4.7	boundary layer thickness, $\delta = 0.005$	34
Figure 4.8	boundary layer thickness, $\delta = 0.5$	35
Figure 4.9	Control Input signal	36
Figure 4.10	Pole chosen at $[-3.5-i, -3.5+i, -4.5-4.5i, -4.5+4.5i]$	37
Figure 4.11	Simulation result for position control of SMC controller and Pole Placement controller	38
Figure 4.12	Simulation for speed control of SMC controller and Pole Placement controller.	39
Figure 4.13	Simulation for angle control of SMC controller and Pole Placement controller	40
Figure 4.14	Simulation for angle rate control of SMC controller and Pole Placement controller	41

LIST OF SYMBOLS

x_r	–	Position of Two Wheels Mobile Robot System
\dot{x}_r	–	Speed of Two Wheels Mobile Robot System
θ_p	–	Angle of Two Wheels Mobile Robot System
$\dot{\theta}_p$	–	Angle Rate of Two Wheels Mobile Robot System

LIST OF ABBREVIATIONS

DOF	Degree of Freedom
SMC	Sliding Mode Control
TWIP	Two Wheels Inverted Pedulum
VSCS	Variable Structure Control System

CHAPTER 1

INTRODUCTION

1.1 Project Overview

The stability of two wheels mobile robot problem is commonly issued in the field of control engineering. The uniqueness and wide application of technology derived from this unstable system has drawn interest from many researches and robotics enthusiasts around the world. In recent years, researchers have applied the idea of a balancing two wheels mobile robot model to various problems like designing walking gaits for humanoid robots, robotic wheelchairs and personal transport systems.

This project is based on controller design and modeling the two wheels mobile robot system by using Sliding Mode Controller. SMC controller is developed based on mathematical modeling of two wheels mobile robot model to control a stability of this system.

In this project, a mathematical model of two wheels mobile robot is presented and the system model of two wheels mobile robot is designed and will be used for the design of a new robust controller by using MATLAB/SIMULINK application. The dynamic modeling is done directly in terms of variables which are of interest with

respect to the planning and control of the two wheels mobile robot position, speed, angle and angle rate.

In this study, the controllers that will be determined use both combination of Hierarchy Control method and Equivalence Control method. The deterministic approach is used to get the bounded condition value of the model for controller design purpose. Simulation result of comparison between SMC controller and Pole Placement controller is shown. Result for both controllers is discussed in next chapter.

1.2 Objective Research

The objectives of this research are as follows:

- i. To develop a SMC controller that base on the robust control strategy that will stabilize a two wheels mobile robot system.
- ii. To evaluate and analyzed the performance of the system with a proposed controller.

To achieve these objectives various parameters such as position, speed, angle and angle rate of two wheels mobile robot will be observed by using extensive computer simulation that will be performed using MATLAB software and SIMULINK Toolbox. Performance of the SMC controller will be compared to Pole Placement techniques.

1.3 Scope of Project

The work undertaken in this project are limited to the following aspects:

- i. Design a system of two wheels mobile robot system by referred to mathematical model as described in [12].
- ii. A two wheels mobile robot system is evaluated due to disturbance at angle rate is utilised.
- iii. Design a controller for a two wheels mobile robot model using Sliding Mode Control technique to compensate disturbance.
- iv. Perform a simulation works by using a MATLAB/SIMULINK to observe robustness of the controller.
- v. Compare the stability performance of the proposed SMC with Pole Placement techniques.

1.4 Problem Statement

The problem of controlling uncertain dynamical systems that are subjected to external disturbances is a topic which is of considerable interest to control researchers. One approach to solve this problem is by means of variable structure control (VSC). The VSC is utilized a high-speed switching control law to drive the nonlinear plant's state trajectory onto a specified and user chosen surface in the state space, and to maintain the plant's state trajectory on this surface for all subsequent time.

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