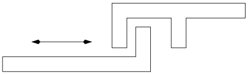
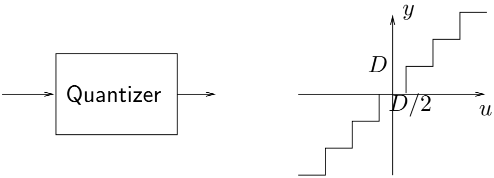
Lecture 8 — Backlash and Quantization

Today's Goal:

- To know models and compensation methods for backlash



- Be able to analyze the effect of quantization errors

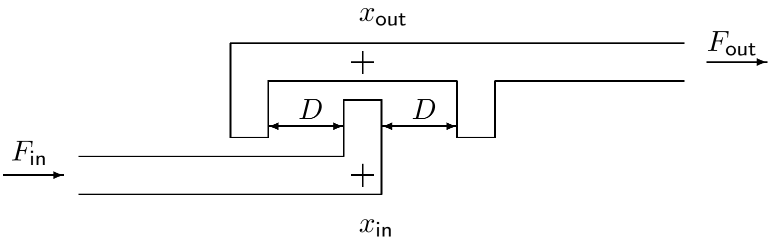


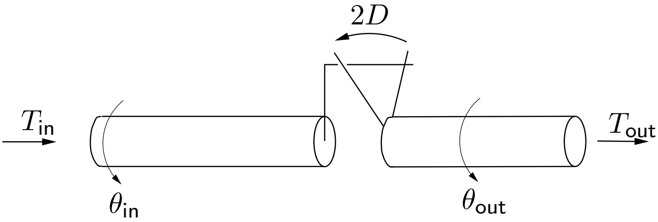
Material

- Lecture slides

Note: We are using analysis methods from previous lectures (describing functions, small gain theorem etc.), and these have references to the course book(s).

Linear and Angular Backlash





Example: Parallel Kinematic Robot

Gantry-Tau robot: Need backlash-free gearboxes for high precision

EU-project: SMErobot™ www.smerobot.org

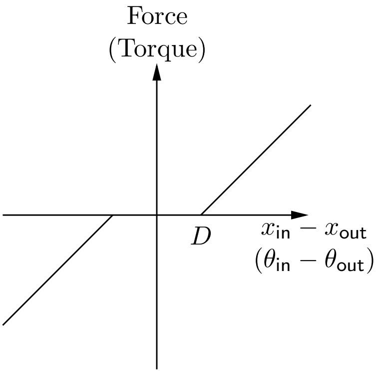
Backlash

Backlash (*glapp*) is

- present in most mechanical and hydraulic systems
- increasing with wear
- bad for control performance
- may cause oscillations

Note: A gear box without any backlash will not work if temperature rises

Dead-zone Model

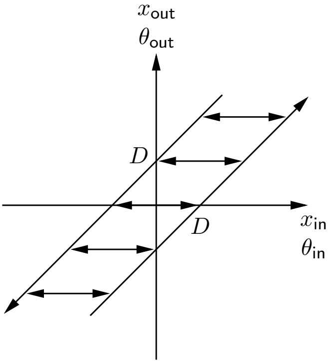


- Often easier to use model of the form $x_{\text{in}}(\cdot) \to x_{\text{out}}(\cdot)$
- Uses implicit assumption: $F_{\text{out}} = F_{\text{in}}, T_{\text{out}} = T_{\text{in}}$. Can be **wrong**, especially when "no contact".

The Standard Model

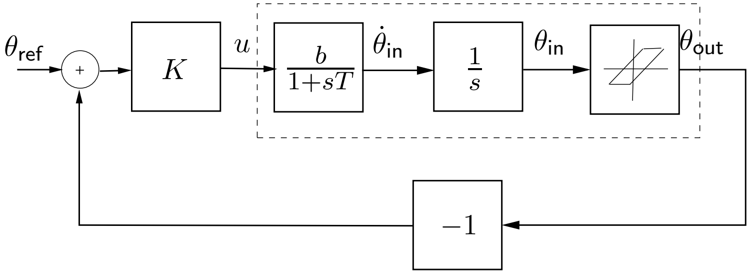
Assume instead

- $\dot{x}_{\text{out}} = \dot{x}_{\text{in}}$ when "in contact"
- $\dot{x}_{\text{out}} = 0$ when "no contact"
- No model of forces or torques needed/used



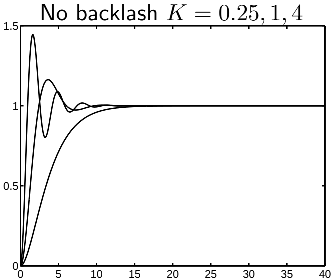
Servo motor with Backlash

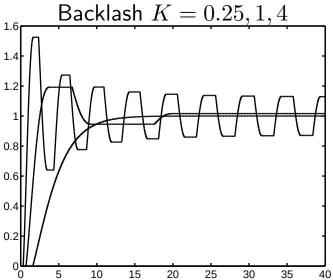
P-control of servo motor



How does the values of K and D affect the behavior?

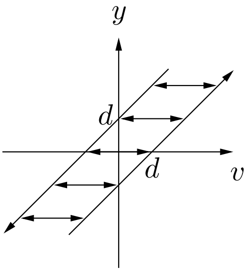
Effects of Backlash

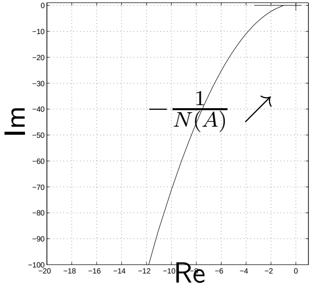




Oscillations for $K = 4$ but not for $K = 0.25$ or $K = 1$. Why?
Limit cycle becomes smaller if D is made smaller, but it never disappears

Describing Function for a Backlash





If $A > d$ then

$$N(A) = \frac{b_1 + ia_1}{A} \quad \text{with} \quad a_1 = \frac{4d}{\pi}\left(\frac{d}{A} - 1\right) \quad \text{and}$$

$$b_1 = \frac{A}{\pi}\left(\frac{\pi}{2} - \arcsin\left(\frac{2d}{A} - 1\right) + 2\left(1 - \frac{2d}{A}\right)\sqrt{\frac{d}{A}}\sqrt{1 - \frac{d}{A}}\right)$$

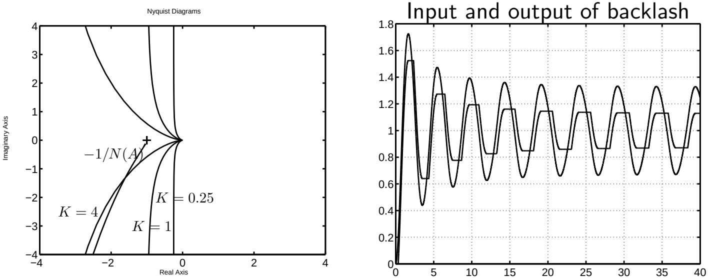
else $N(A) = 0$.

1 minute exercise

Study the plot for the describing function for the backlash on the previous slide.

Where does the function $-\dfrac{1}{N(A)}$ end for $A \to \infty$ and why?

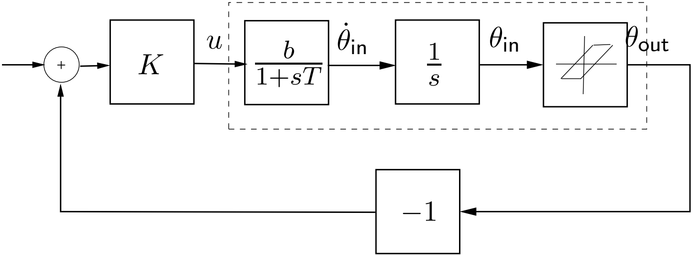
Describing Function Analysis



- For $K = 4, D = 0.2$: intersection between $G(j\omega)$ and $-1/N(A)$ occurs for $A = 0.33, \omega = 1.24$
- Simulation: $A = 0.33$, $\omega = 2\pi/5.0 = 1.26$
  Describing function predicts oscillation well!

Limit cycles?

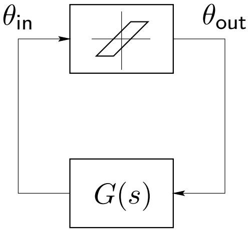
The describing function method is only approximate.
Can one determine conditions that **guarantee** stability?

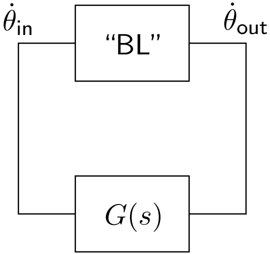


Note: θ_{in} and θ_{out} will not converge to zero
Idea: Consider instead $\dot{\theta}_{\text{in}}$ and $\dot{\theta}_{\text{out}}$

Backlash Limit Cycles

Rewrite the system as





Note that the block "BL" satisfies

$$\dot{\theta}_{\text{out}} = \begin{cases} \dot{\theta}_{\text{in}} & \text{in contact} \\ 0 & \text{otherwise} \end{cases}$$

Analysis by small gain theorem

Backlash block has gain ≤ 1 (from $\dot{\theta}_{\text{in}}$ to $\dot{\theta}_{\text{out}}$)

Hence closed loop is BIBO stable provided that

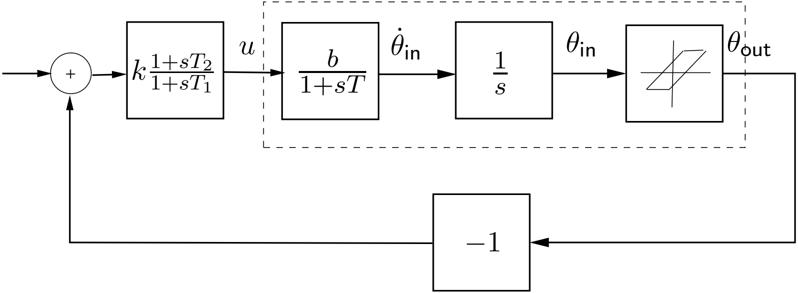
$G(s)$ is asymptotically stable and $|G(i\omega)| < 1$ for all ω

Backlash compensation

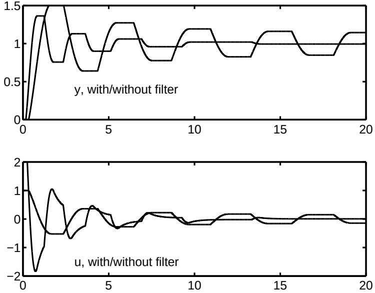
- Mechanical solutions
- Dead-zone
- Linear controller design
- Backlash inverse

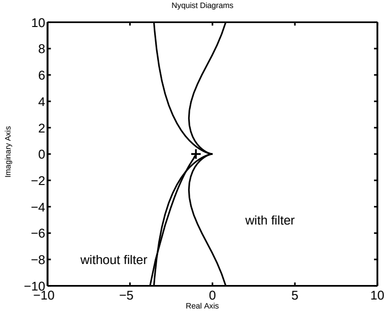
Linear Controller Design

Introduce phase lead **to avoid** the $-1/N(A)$ curve:
Instead of only a P-controller we choose $K(s) = k\frac{1+sT_2}{1+sT_1}$



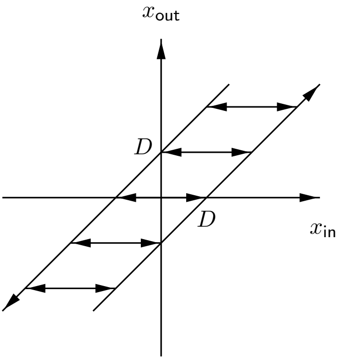
Controller $K(s) = k\frac{1+sT_2}{1+sT_1}$
Simulation with $T_1 = 0.5, T_2 = 2.0$

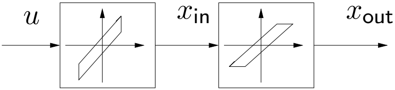




No limit cycle, oscillation removed!

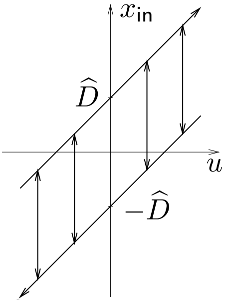
Backlash Inverse





Idea: Let x_{in} jump $\pm 2D$ when $\dot{x}_{\text{out}}$ should change sign. Works if the backlash is directly on the system input!

Backlash Inverse



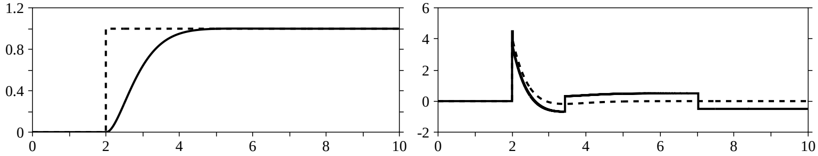
$$x_{\text{in}}(t) = \begin{cases} u + \widehat{D} & \text{if } u(t) > u(t-) \\ u - \widehat{D} & \text{if } u(t) < u(t-) \\ x_{\text{in}}(t-) & \text{otherwise} \end{cases}$$

If

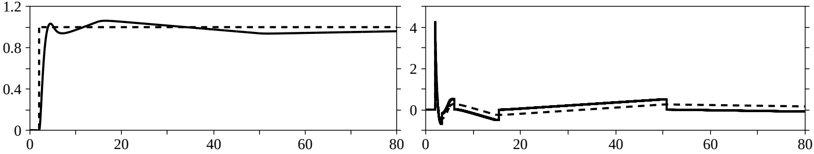
- $\widehat{D} = D$ then $x_{\text{out}}(t) = u(t)$ (perfect compensation)
- $\widehat{D} < D$: Under-compensation (decreased backlash)
- $\widehat{D} > D$: Over-compensation, often gives oscillations

Example–Perfect compensation

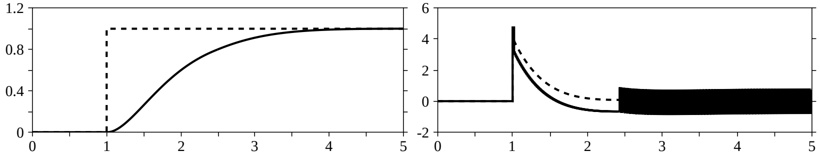
Motor with backlash on input, PD-controller



Example–Under compensation



Example–Over compensation



Backlash–More advanced models

Warning: More detailed models needed sometimes
Model what happens when contact is attained
Model external forces that influence the backlash
Model mass/moment of inertia of the backlash.

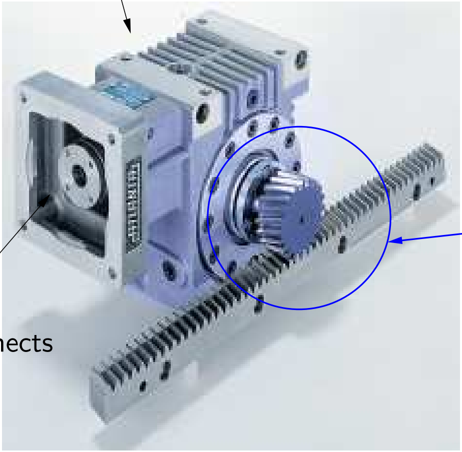
Example: Parallel Kinematic Robot

Gantry-Tau robot:
Need backlash-free gearboxes for very high precision

EU-project: SMErobot™ `http://www.smerobot.org`

"Rotational to Linear motion"

Gear box

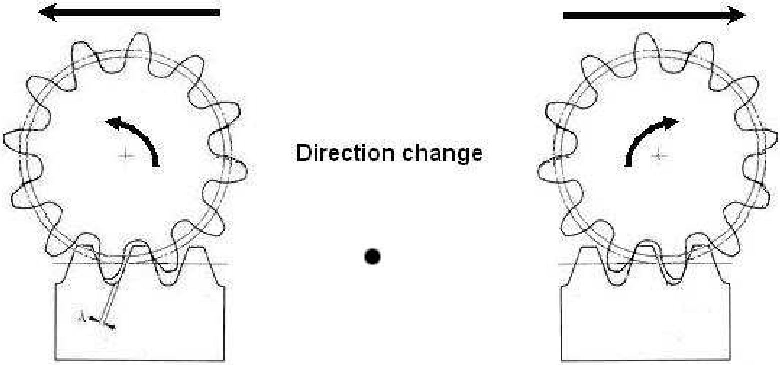


Rack-and-pinion
(Swe. "kuggstng")

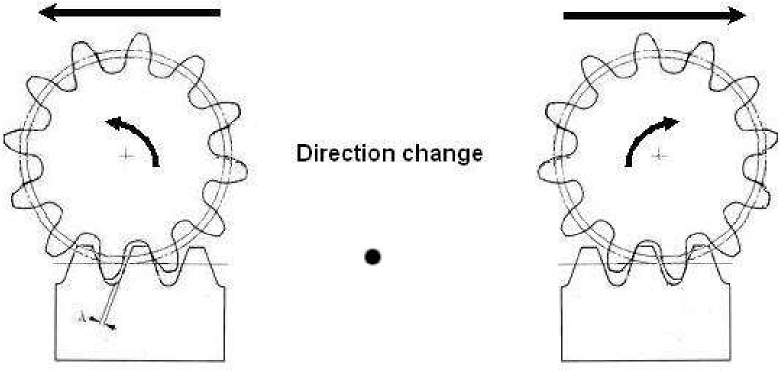
Motor connects

here

Backlash in gearbox and rails

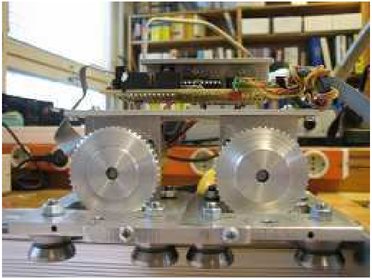


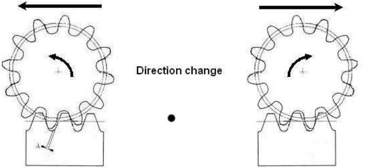
Backlash in gearbox and rails



Remedy:
Use two motors, possible to motors in opposite directions: One motor can act as spring and brake to "reduce" backlash. Need measurements on both motor and arm-side.

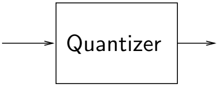
Backlash compensation

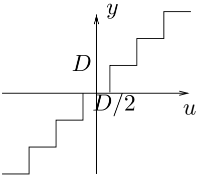




From master thesis by B. Brochier, *Control of a Gantry-Tau Structure, LTH, 2006*
See also master theses by j. Schiffer and L. Halt, 2009.

Quantization





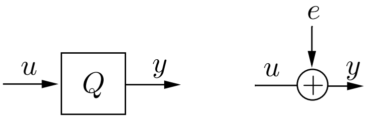
How accurate should the converters be? (8-14 bits?)
What precision is needed in computations? (8-64 bits?)

- Quantization in A/D and D/A converters
- Quantization of parameters
- Roundoff, overflow, underflow in operations

NOTE: Compare with **(different)** limits for "quantizer/dead-zone relay" in Lecture 6.

Linear Model of Quantization

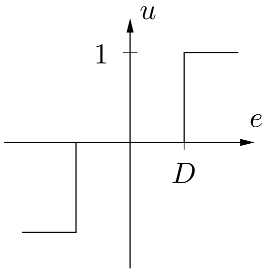
Model the quantization error as a stochastic signal e independent of u with rectangular distribution over the quantization size.
Works if quantization level is small compared to the variations in u

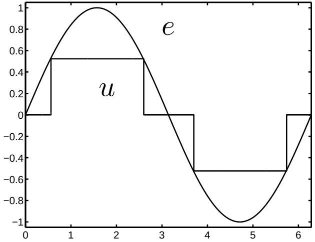


Rectangular noise distribution over $[-\frac{D}{2}, \frac{D}{2}]$ has the variance

$$Var(e) = \int_{-\infty}^{+\infty} e^2 f_e \, de = \int_{-D/2}^{D/2} e^2 \frac{1}{D} de = \frac{D^2}{12}$$

Describing Function for Deadzone Relay

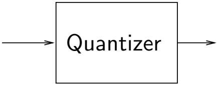


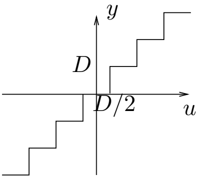


Lecture 6 $\Rightarrow$

$N(A) = \dfrac{4}{\pi A}\sqrt{1 - D^2/A^2}$ for $A > D$ and zero otherwise

Describing Function for Quantizer

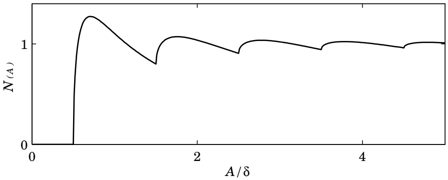




$$N(A) = \begin{cases} 0 & A < \frac{D}{2} \\ \dfrac{4D}{\pi A} \displaystyle\sum_{k=1}^{n} \sqrt{1 - \left(\dfrac{2k-1}{2A} D\right)^2} & \frac{2n-1}{2} D < A < \frac{2n+1}{2} D \end{cases}$$

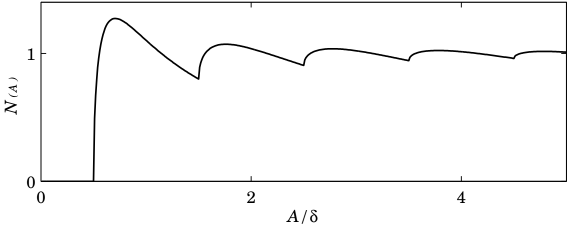
(See exercise)

Describing Function for Quantizer



The maximum value is $4/\pi \approx 1.27$ for $A \approx 0.71D$.
Predicts limit cycle if Nyquist curve intersects negative real axis to the left of $-\pi/4 \approx -0.79$.
Should design for gain margin ¿ $1/0.79 = 1.27$!
Note that reducing D only reduces the size of the limit oscillation, the oscillation does not vanish completely.

5 minute exercise

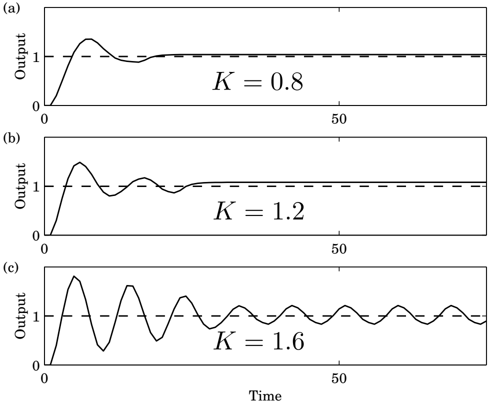


How does the shape of the describing function relate to the number of possible limit cycles and their stability.
What if the Nyquist plot

- intersects the negative real axis at -0.80?
- intersects the negative real axis at -1?
- intersects the negative real axis at -2?

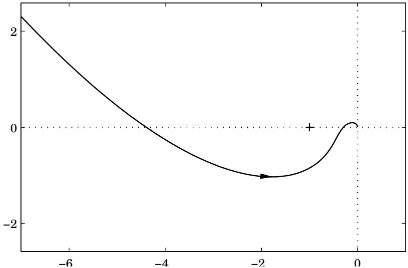
Example – Motor with P-controller.

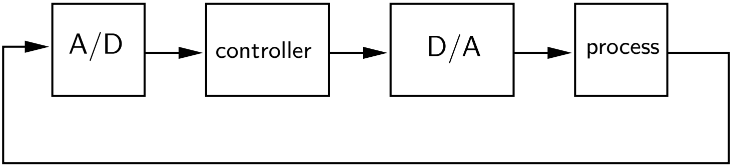
Roundoff at input, $D = 0.2$. Nyquist curve intersects at $-0.5K$. Hence stable for $K < 2$ without quantization. Stable oscillation predicted for $K > 2/1.27 = 1.57$.



Example – Double integrator with 2nd order controller

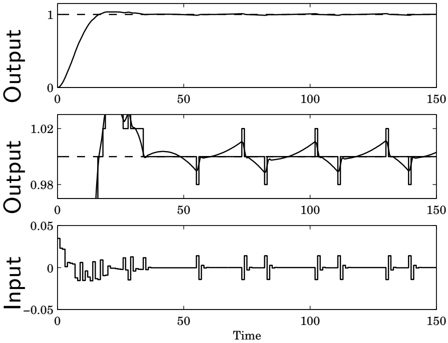
Nyquist curve





Quantization at A/D converter

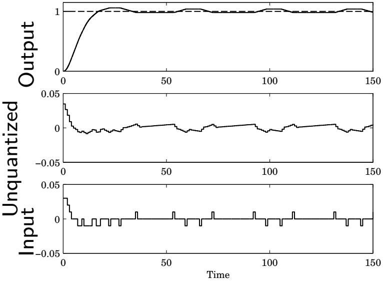
Double integrator with 2nd order controller, $D = 0.02$



Describing function: $A_y \approx D/2 = 0.01$, period $T = 39$
Simulation: $A_y = 0.01$ and $T = 28$

Quantization at D/A converter

Double integrator with 2nd order controller, $D = 0.01$



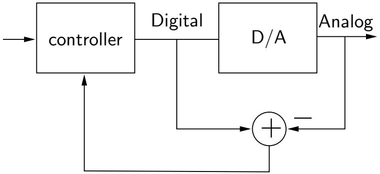
Describing function: $A_u \approx D/2 = 0.005$, period $T = 39$

Simulation: $A_u = 0.005$ and $T = 39$

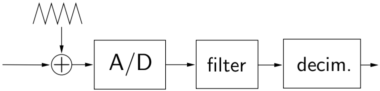
Better prediction, since more sinusoidal signals

Quantization Compensation

- Use improved converters, (small quantization errors/larger word length)
- Linear design, avoid unstable controller, ensure gain margin¿1.3
- Use the tracking idea from anti-windup to improve D/A converter

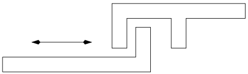


- Use analog dither, oversampling and digital low-pass filter to improve accuracy of A/D converter

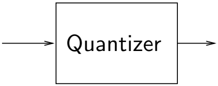


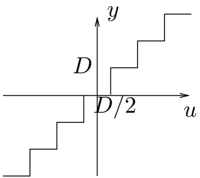
Today's Goal

- To know models and compensation methods for backlash



- Be able to analyze the effect of quantization errors





Note: summary of schedule changes for the last weeks

- this week's exercise sessions (Tuesday and Wednesday, November 24 and 25, 15;17) will be held in **Lab C** of the Automatic Control Department, M-building, first floor

During the last two weeks

- exercise sessions of Tuesday **December 8**, 15-17, and Wednesday **December 9 13-15** (NOTE TIME CHANGE), when they will be held in **Lab B**;
- additional lecture on **December 10, 8:15-10:00**, in the **seminar room** of the Automatic Control Department, M2112B, M-building, second floor.
- no lectures during last week (December 14 and 16), only exercise sessions (usual time) and labs (see schedule)