

Contents

1	Introduction	1
1.1	Mechatronics, Mechatronic Systems.....	2
1.2	Systems Design	9
1.3	Introductory Examples	17
1.3.1	Telescope with adaptive optics	17
1.3.2	Optomechatronic remote sensing camera	31
1.4	About This Book	37
	Bibliography for Chapter 1	44
2	Elements of Modeling.....	47
2.1	Systems Engineering Context.....	48
2.2	System Modeling with Structured Analysis	55
2.2.1	Definitions.....	56
2.2.2	Ordering principles	57
2.2.3	Modeling elements of structured analysis.....	58
2.2.4	Example product: autofocus camera.....	64
2.2.5	Alternative modeling methods	69
2.3	Modeling Paradigms for Mechatronic Systems	72
2.3.1	Generalized power and energy.....	74
2.3.2	Energy-based modeling: LAGRANGE formalism	79
2.3.3	Energy-based modeling: HAMILTON's equations	87
2.3.4	Multi-port modeling: KIRCHHOFF networks	89
2.3.5	Multi-port modeling: bond graphs	102
2.3.6	Energy / multi-port modeling: port-HAMILTONian systems	103
2.3.7	Signal-coupled networks.....	106
2.3.8	Model causality	112
2.3.9	Modular modeling of mechatronic systems	118
2.4	Systems of Differential-Algebraic Equations.....	131
2.4.1	Introduction to DAE systems.....	131
2.4.2	DAE index tests	133
2.4.3	DAE index reduction	138
2.5	Hybrid Systems	140

2.5.1	General structure of a hybrid system	140
2.5.2	Hybrid phenomena.....	141
2.5.3	Net-state models.....	144
2.6	Linear System Models.....	148
2.6.1	Local linearization of nonlinear state space models ...	149
2.6.2	Local linearization of nonlinear DAE systems	153
2.6.3	LTI systems: transfer function, frequency response ...	154
2.7	Experimental Determination of the Frequency Response	160
2.7.1	General considerations.....	160
2.7.2	Methodological approach.....	161
2.7.3	Frequency responses measurement via noise excitation.....	162
	Bibliography for Chapter 2.....	166
3	Simulation Issues	171
3.1	Systems Engineering Context	172
3.2	Elements of Numerical Integration	173
3.2.1	Numerical integration of differential equations	173
3.2.2	Concepts of stability.....	175
3.2.3	Numerical stability	177
3.3	Stiff Systems	181
3.4	Weakly-Damped Systems	185
3.5	High-Order Linear Systems.....	188
3.5.1	General numerical integration methods	188
3.5.2	Solution via the state transition matrix	189
3.5.3	Accuracy of the simulation solutions.....	191
3.6	Numerical Integration of DAE Systems.....	194
3.6.1	Explicit integration methods	194
3.6.2	Implicit integration methods	196
3.6.3	Scaling for index-2 systems	199
3.6.4	Consistent initial values	200
3.7	Implementation Approaches for Simulation of Hybrid Phenomena	201
3.7.1	Handling discontinuities	201
3.7.2	Event detection.....	202
3.8	Simulation Example: Ideal Pendulum.....	203
	Bibliography for Chapter 3.....	209
4	Functional Realization: Multibody Dynamics	211
4.1	Systems Engineering Context	212
4.2	Multibody Systems.....	213
4.3	Physical Fundamentals	216

4.3.1	Kinematics vs. dynamics.....	216
4.3.2	Rigid bodies	217
4.3.3	Degrees of freedom and constraints	223
4.4	MBS Models in the Time Domain	230
4.4.1	Model hierarchy for systems design	230
4.4.2	MBS equations of motion	232
4.4.3	MBS state space model	237
4.5	Natural Oscillations.....	237
4.5.1	Eigenvalue problem for conservative multibody systems	237
4.5.2	Eigenmodes	239
4.5.3	Dissipative multibody systems.....	245
4.6	Response Characteristics in the Frequency Domain	249
4.7	Measurement and Actuation Locations	258
4.7.1	General multiple-mass oscillator.....	258
4.7.2	Zeros of a multiple-mass oscillator	259
4.7.3	Collocated measurement and actuation.....	264
4.7.4	Non-collocated measurement and actuation	266
4.7.5	Antiresonance.....	267
4.7.6	Migration of MBS zeros	268
	Bibliography for Chapter 4.....	275
5	Functional Realization: The Generic Mechatronic	
	Transducer	277
5.1	Systems Engineering Context.....	278
5.2	General Generic Transducer Model	280
5.2.1	System configuration	280
5.2.2	Modeling approach	283
5.3	The Unloaded Generic Transducer.....	288
5.3.1	Energy-based model.....	288
5.3.2	Constitutive ELM transducer equations.....	300
5.3.3	ELM two-port model	304
5.4	The Loaded Generic Transducer	311
5.4.1	Energy-based model.....	311
5.4.2	Nonlinear equations of motion.....	311
5.4.3	Equilibrium positions: operating points	316
5.4.4	Linear signal-based transducer model.....	320
5.4.5	Transfer matrix.....	323
5.4.6	Discussion of the response characteristics	324
5.5	Lossy Transducer	330
5.5.1	General transducer behavior	330
5.5.2	Nonlinear model: equilibrium positions.....	333

5.5.3	Linear signal-based model	335
5.5.4	Constitutive two-port equations with dissipative resistors	337
5.5.5	Linear dynamic analysis.....	338
5.5.6	General impedance and admittance feedback	343
5.6	Electromechanical Coupling Factor	350
5.6.1	General significance and attributes	350
5.6.2	Model for calculating ELM coupling factors.....	352
5.6.3	Discussion of ELM coupling factors	358
5.7	Transducers with Multibody Loads.....	362
5.7.1	Frequency response.....	362
5.7.2	Impedance and admittance feedback	367
5.8	Mechatronic Resonator.....	370
5.9	Mechatronic Oscillating Generator	373
5.10	Self-Sensing Actuators.....	376
5.10.1	Principle of operation.....	376
5.10.2	Signal-based self-sensing solution approach	378
5.10.3	Analog electrical self-sensing solutions.....	379
	Bibliography for Chapter 5.....	385
6	Functional Realization: Electrostatic Transducers	389
6.1	Systems Engineering Context	390
6.2	Physical Foundations.....	391
6.3	Generic Electrostatic Transducer	394
6.3.1	System configuration	394
6.3.2	Electrostatic constitutive transducer equations	395
6.3.3	ELM two-port model	399
6.3.4	Loaded electrostatic transducer.....	401
6.3.5	Structural principles	403
6.4	Transducer with Variable Electrode Separation and Voltage Drive	406
6.4.1	General dynamic model	406
6.4.2	Increasing the range of motion with serial capacitors	411
6.4.3	Passive damping with serial resistance	413
6.5	Transducer with Variable Electrode Separation and Current Drive.....	420
6.6	Differential Transducers.....	423
6.6.1	Generic transducer configuration.....	423
6.6.2	Push-push control: mechanically symmetric configuration	425
6.6.3	Push-push control: transverse comb transducer	426

6.6.4	Push-pull control: electrostatic bearing.....	431
6.6.5	Push-pull control: axisymmetric double-comb transducer.....	435
6.7	Transducers with Constant Electrode Separation.....	437
6.7.1	General dynamic model	437
6.7.2	Longitudinal comb transducer	440
6.7.3	Comb transducer with linearly stepped teeth	444
	Bibliography for Chapter 6.....	446
7	Functional Realization: Piezoelectric Transducer.....	449
7.1	Systems Engineering Context.....	450
7.2	Physical Foundations.....	451
7.3	Generic Piezoelectric Transducer.....	459
7.3.1	System configuration	459
7.3.2	Constitutive piezoelectric transducer equations.....	460
7.3.3	ELM two-port model	462
7.3.4	Loaded piezoelectric transducer.....	463
7.3.5	Structural principles	468
7.4	Transducers with Impedance Feedback.....	477
7.5	Mechanical Resonators.....	483
7.5.1	Proportional operation vs. resonant operation	483
7.5.2	Ultrasonic piezo motors	484
	Bibliography for Chapter 7.....	490
8	Functional Realization: Electromagnetically-Acting Transducers.....	493
8.1	Systems Engineering Context.....	494
8.2	Physical Foundations.....	497
8.3	Generic EM Transducer: Variable Reluctance.....	507
8.3.1	System configuration	507
8.3.2	Constitutive electromagnetic transducer equations.....	508
8.3.3	ELM two-port model	512
8.3.4	Loaded electromagnetic (EM) transducer	514
8.3.5	Structural principles	517
8.3.6	EM transducers with variable working air gaps.....	524
8.3.7	Differential EM transducers: magnetic bearings.....	539
8.3.8	EM transducers with constant working air gaps	546
8.3.9	Reluctance stepper motor.....	549
8.4	Generic ED Transducer: LORENTZ Force.....	558
8.4.1	System configuration	558
8.4.2	Constitutive electrodynamic transducer equations.....	559
8.4.3	ELM two-port model	562

8.4.4	Loaded electrodynamic (ED) transducer	563
8.4.5	Structural principles	567
	Bibliography for Chapter 8.....	574
9	Functional Realization: Digital Information Processing.....	575
9.1	Systems Engineering Context	576
9.2	Definitions	578
9.2.1	Reference configuration.....	578
9.2.2	Modeling approaches	579
9.3	Sampling.....	581
9.4	Aliasing	586
9.5	Hold Element.....	589
9.6	Sampled Plant Frequency Response.....	593
9.7	Aliasing in Oscillatory Systems	596
9.8	Digital Controllers.....	601
9.9	Transformed Frequency Domain.....	604
9.10	Signal Conversion	614
9.11	Digital Data Communications	618
9.12	Real-Time Aspects	622
9.13	Design Considerations.....	624
	Bibliography for Chapter 9.....	626
10	Control Theoretical Aspects	629
10.1	Systems Engineering Context	630
10.2	General Design Considerations	631
10.3	Modeling Uncertainties	642
10.3.1	MBS parameter uncertainties.....	642
10.3.2	Unmodeled eigenmodes.....	644
10.3.3	Parasitic dynamics	645
10.4	Robust Stability for Multibody Systems	645
10.4.1	NYQUIST criterion in intersection formulation.....	645
10.4.2	Stability analysis with the NICHOLS diagram	650
10.4.3	Robust stability of elastic eigenmodes.....	654
10.5	Manual Controller Design in the Frequency Domain	656
10.5.1	Robust control strategies	656
10.5.2	Generic controller types for multibody systems	659
10.5.3	Transient dynamics under unity feedback.....	666
10.5.4	Control of a single-mass oscillator.....	668
10.5.5	Collocated MBS control.....	674
10.5.6	Non-collocated MBS control	680
10.6	Vibration Isolation.....	686
10.6.1	Passive vibration isolation	686

10.6.2	Active vibration isolation: the skyhook principle	688
10.6.3	Active proof mass damper	700
10.7	Observability and Controllability Aspects	700
10.7.1	General properties	700
10.7.2	MBS control in relative coordinates	704
10.7.3	Measurement and actuation locations at oscillation nodes	710
10.8	Digital Control.....	711
10.8.1	General design process.....	711
10.8.2	Rigid-body-dominated systems.....	714
10.8.3	Systems with unmodeled eigenmodes (spillover).....	717
11.8.4	Aliasing in digital controllers.....	719
10.8.5	Aliasing of measurement noise	720
	Bibliography for Chapter 10.....	724
11	Stochastic Dynamic Analysis	727
11.1	Systems Engineering Context.....	728
11.2	Elements of Stochastic Systems Theory.....	730
11.2.1	Random variables.....	730
11.2.2	Stochastic time functions, random processes.....	736
11.2.3	LTI systems with stochastic inputs	740
11.3	White Noise.....	742
11.4	Colored Noise.....	744
11.5	Modeling Noise Sources	749
11.6	Covariance Analysis.....	754
	Bibliography for Chapter 11.....	763
12	Design Evaluation: System Budgets.....	765
12.1	Systems Engineering Context.....	766
12.2	Performance Metrics: Performance Parameters	767
12.3	Linear Budgeting of Metrics	770
12.4	Nonlinear Budgeting of Metrics.....	774
12.5	Product Accuracy	779
12.6	Budgeting Heterogeneous Metrics	780
12.7	Design Optimization Using Budgets	784
12.8	Design Examples	786
	Bibliography for Chapter 12.....	794
Appendix A		795
Covariance Formulae.....		795
Index		799