

Nonlinear Robust H-Infinity PID Controller for the Multivariable System Quadrotor

J. P. Ortiz, *Member, IEEE*, L. I. Minchala, *Member, IEEE* and M. J. Reinoso

Abstract— This paper presents the methodology of design of a nonlinear robust controller for attitude regulation and its implementation in an experimental platform of an unmanned aerial vehicle (UAV) quadrotor. Details on the kinematic and dynamic modeling based on the Euler-Lagrange formalism are provided, as well as the particulars of the design of a nonlinear robust H-infinity PID controller to regulate the rotational moments. The performance and effectiveness of the proposed controller are tested in a simulation and an experimental platform. The performance of the proposed controller is compared with a conventional PID controller by using the integral square error (ISE) as performance parameter. Experimental results help to demonstrate the correct operation of the system for real-time applications in the presence of unmodeled dynamics and the uncertainties of the parameters.

Keywords— Nonlinear system, quadrotor, robust control, attitude regulation, UAV

I. INTRODUCCIÓN

LOS sistemas de control para vehículos aéreos no tripulados del tipo quadrotor se han desarrollado con gran rapidez en los últimos años. La necesidad de desarrollar sistemas con mayor autonomía, que puedan realizar maniobras de alta complejidad, que realicen misiones de largo alcance, que operen en entornos de alto riesgo para los seres humanos, sin duda han permitido que este campo este bajo continua investigación y desarrollo [1-3].

En [4] se establece un controlador robusto para despegue, seguimiento de trayectoria y aterrizaje, constituido por un controlador de posición y un controlador de orientación. El controlador de posición usa el método de realimentación estática para obtener la altura deseada, mientras que el control de orientación utiliza un proporcional-derivativo (PD) con una técnica de compensación robusta. En [5] se propone agregar a la estructura del controlador PD un método robusto de sintonización de parámetros, que permite modificar en línea los parámetros del compensador durante el seguimiento de una trayectoria.

Los estudios realizados en [6] plantean un controlador robusto no lineal H_{∞} para estabilizar los momentos de rotación y un control basado en el enfoque de *backstepping* para el seguimiento de trayectoria. La referencia [7] sugiere un controlador del tipo integral predictivo para resolver el problema de seguimiento de trayectoria. Ambos resultados simulados son robustos ante perturbaciones externas del sistema.

En [8] se propone un controlador tolerante a fallos para posicionamiento y re-posicionamiento de trayectorias. En [9] se implementan y comparan dos algoritmos de control tolerante a fallos basados en: un regulador lineal cuadrático y un controlador de modelo predictivo, los resultados demuestran un desempeño aceptable de los algoritmos para el control de altura en presencia de pérdidas parciales de la acción de los actuadores.

Diversas investigaciones [10-12] han realizado comparaciones entre varias técnicas de control y también usado diferentes modelos matemáticos del sistema [13-15]. Entre los controladores más usados para resolver los problemas de seguimiento de trayectoria y de regulación están: el control por linealización entrada-salida [16], el control por visión [17], el control adaptivo [18], el control por modos deslizantes [19], el control óptimo *backstepping* [20], el control robusto no lineal adaptivo [21], entre otros.

Este artículo propone un controlador robusto para afrontar el problema de regulación del subsistema de orientación de un quadrotor. El problema se divide en tres etapas: en la primera, se obtienen los modelos matemáticos, cinemático y dinámico. En la segunda etapa se presenta el diseño y la implementación del controlador robusto no lineal H_{∞} que compensa las fuentes de incertidumbre en el modelo debido a dinámicas no modeladas, errores en la estimación de parámetros, perturbaciones exógenas y ruido. En la tercera etapa se realizan los pruebas de funcionamiento y el análisis de desempeño del controlador en las plataformas de simulación y experimental, usando el ISE como criterio de desempeño y obteniéndose buenos resultados en comparación con un sistema de control clásico PID.

Este documento se organiza como sigue: La sección II presenta el modelado matemático del sistema considerando dinámicas no lineales traslacional y rotacional. La sección III muestra el procedimiento para el diseño del controlador robusto no lineal H_{∞} del sistema de orientación de la aeronave. La sección IV presenta los detalles de la implementación del controlador, tanto en la plataforma de simulación como en la plataforma experimental. La sección V presenta las conclusiones del trabajo.

II. MODELADO MATEMÁTICO DEL SISTEMA

A. Consideraciones del sistema

Un vehículo aéreo no tripulado (UAV por sus siglas en inglés) posee la configuración de cuatro motores coplanares, como se muestra en la Fig. 1. La variación controlada de las velocidades en los motores permite el movimiento del quadrotor. El movimiento del sistema hacia adelante (pitch) se logra disminuyendo y aumentando las velocidades de los motores delantero (F1) y trasero (F3) respectivamente. Un desplazamiento lateral (roll) demanda el mismo procedimiento

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Nonlinear H Infinity Controller For The Quad Rotor

David Kirk



Nonlinear H Infinity Controller For The Quad Rotor:

This book delves into Nonlinear H Infinity Controller For The Quad Rotor. Nonlinear H Infinity Controller For The Quad Rotor is a vital topic that needs to be grasped by everyone, ranging from students and scholars to the general public. This book will furnish comprehensive and in-depth insights into Nonlinear H Infinity Controller For The Quad Rotor, encompassing both the fundamentals and more intricate discussions.

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 - Chapter 3: Nonlinear H Infinity Controller For The Quad Rotor in Everyday Life
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 - Chapter 5: Conclusion
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Table of Contents Nonlinear H Infinity Controller For The Quad Rotor

1. Understanding the eBook Nonlinear H Infinity Controller For The Quad Rotor
 - The Rise of Digital Reading Nonlinear H Infinity Controller For The Quad Rotor
 - Advantages of eBooks Over Traditional Books
2. Identifying Nonlinear H Infinity Controller For The Quad Rotor
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in a Nonlinear H Infinity Controller For The Quad Rotor
 - User-Friendly Interface
4. Exploring eBook Recommendations from Nonlinear H Infinity Controller For The Quad Rotor
 - Personalized Recommendations
 - Nonlinear H Infinity Controller For The Quad Rotor User Reviews and Ratings
 - Nonlinear H Infinity Controller For The Quad Rotor and Bestseller Lists
5. Accessing Nonlinear H Infinity Controller For The Quad Rotor Free and Paid eBooks
 - Nonlinear H Infinity Controller For The Quad Rotor Public Domain eBooks
 - Nonlinear H Infinity Controller For The Quad Rotor eBook Subscription Services
 - Nonlinear H Infinity Controller For The Quad Rotor Budget-Friendly Options
6. Navigating Nonlinear H Infinity Controller For The Quad Rotor eBook Formats
 - ePub, PDF, MOBI, and More
 - Nonlinear H Infinity Controller For The Quad Rotor Compatibility with Devices
 - Nonlinear H Infinity Controller For The Quad Rotor Enhanced eBook Features
7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Nonlinear H Infinity Controller For The Quad Rotor
 - Highlighting and Note-Taking Nonlinear H Infinity Controller For The Quad Rotor
 - Interactive Elements Nonlinear H Infinity Controller For The Quad Rotor

8. Staying Engaged with Nonlinear H Infinity Controller For The Quad Rotor
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Nonlinear H Infinity Controller For The Quad Rotor
9. Balancing eBooks and Physical Books Nonlinear H Infinity Controller For The Quad Rotor
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Nonlinear H Infinity Controller For The Quad Rotor
10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
11. Cultivating a Reading Routine Nonlinear H Infinity Controller For The Quad Rotor
 - Setting Reading Goals Nonlinear H Infinity Controller For The Quad Rotor
 - Carving Out Dedicated Reading Time
12. Sourcing Reliable Information of Nonlinear H Infinity Controller For The Quad Rotor
 - Fact-Checking eBook Content of Nonlinear H Infinity Controller For The Quad Rotor
 - Distinguishing Credible Sources
13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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