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磁浮定位系統之適應性類神經控制設計  
Adaptive neural control of a magnetic levitation system



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## ABSTRACT

This thesis considers the position-tracking problem of a magnetic levitation system in the presence of modeling errors due to uncertainties of physical parameters. First, a dynamic model of the magnetic levitation system is derived. Then, a smooth switching adaptive robust control is proposed. The controller consists of three part, an adaptive linearizing controller using RBFN, robust controller, and an smooth function to switch between the above two controllers . The proposed controller improves the tracking performance and avoids the so-called control singularity occurred in a standard adaptive linearizing controller. Both simulation and experiments are carried out to verify the proposed method.

**Keywords:** Magnetic levitation system (Maglev), sliding mode control, smooth switching, neural network.



## TABLE OF CONTENTS

<b>LIST OF FIGURES.....</b>	<b>9</b>
<b>LIST OF TABLE.....</b>	<b>11</b>
<b>CHAPTER 1 INTRODUCTION .....</b>	<b>12</b>
<b>1.1. Magnetic Levitation Technology and applications.....</b>	<b>12</b>
<b>1.2. Magnetic levitation test platform – ECP model 730 Maglev.....</b>	<b>14</b>
1.2.1. System overview .....	14
1.2.2. Electromechanical plant .....	17
1.2.3. Controller and driver electronics .....	18
1.2.4. ECP executive software.....	19
<b>1.3. Motivation .....</b>	<b>19</b>
<b>1.4 Contributions of the thesis.....</b>	<b>20</b>
<b>1.5. Organization of the thesis.....</b>	<b>21</b>
<b>CHAPTER 2 LITERATURE REVIEW .....</b>	<b>22</b>
<b>2.1. Previous research on magnetic levitation system .....</b>	<b>22</b>
<b>2.2. Sliding mode control .....</b>	<b>23</b>
<b>2.3. Neural network.....</b>	<b>24</b>
<b>2.4. Combination between NNs and SMC .....</b>	<b>25</b>
<b>CHATER 3 DYNAMICS ANALYSIS OF MEGLEV SYSTEM-MODEL 730 ..</b>	<b>26</b>
<b>3.1. Force dynamics of magnet disk.....</b>	<b>26</b>
<b>3.3. Linearization using Taylor’ Series expansion.....</b>	<b>31</b>
<b>3.4. Nonlinear model of Maglev .....</b>	<b>33</b>

<b>CHAPTER 4</b>	<b>CONTROL DESIGN</b> .....	<b>34</b>
<b>4.1</b>	<b>Sliding mode control</b> .....	<b>34</b>
<b>4.2</b>	<b>Adaptive controller</b> .....	<b>35</b>
4.2.1	Radial Basic function neural network .....	35
4.2.2	Adaptive controller .....	36
<b>4.3</b>	<b>Proposed controller</b> .....	<b>37</b>
<b>CHAPTER 5</b>	<b>RESULTS AND DISCUSSION</b> .....	<b>39</b>
<b>5.1</b>	<b>Simulation results</b> .....	<b>39</b>
5.1.1	Sliding mode controller .....	39
5.1.2	Robust controller .....	41
5.1.3	Smooth switching adaptive robust controller .....	43
<b>5.2</b>	<b>Experimental results</b> .....	<b>46</b>
5.2.1	Sliding mode controller .....	46
5.2.2	Robust controller .....	47
5.2.3	Adaptive controller .....	49
5.2.4	Smooth switching adaptive robust controller .....	50
<b>5.2</b>	<b>Discussion</b> .....	<b>52</b>
<b>CHAPTER 6</b>	<b>CONCLUSION AND FUTURE WORKS</b> .....	<b>54</b>
<b>6.1.</b>	<b>Conclusion</b> .....	<b>54</b>
<b>6.2.</b>	<b>Future works</b> .....	<b>55</b>
<b>REFERENCES</b>	.....	<b>56</b>

## LIST OF FIGURES

Figure 1. 1: Transrapid Maglev .....	13
Figure 1. 2 Schematic diagram of ElectroMagnetic Suspension maglev system [6] ...	13
Figure 1. 3: The model 730 Experimental Control System.....	15
Figure 1. 4: Schematic Diagram for the Model 730 Magnetic Levitation apparatus .....	15
Figure 1. 6: MagLev Apparatus, side view and front view [10] .....	18
Figure 1. 5: ECP Model 730 Magnetic Levitation Plant.....	17
Figure 2.1: Structure of a neuron .....	24
Figure 2.2: Structure of a multilayer feed-forward neural network .....	25
Figure 3. 1: MIMO configuration of the magnetic levitation system	26
Figure 3. 2: SISO configuration of the magnetic levitation system .....	28
Figure 3. 3: Physical measurements obtained from the Maglev plant .....	29
Figure 3. 4: Representation of the estimated curve against the experimental data .....	31
Figure 4.1 Network structure of an RBFN .....	36
Figure 4.2: Control block diagram of an proposed controller system.....	38
Figure 5. 1: Tracking performance of SMC system .....	40
Figure 5.2: Tracking error of SMC system .....	41
Figure 5. 3: Sliding surface of SMC system .....	41
Figure 5.4: Control effort of SMC system .....	41
Figure 5. 5: Tracking performance of robust controller .....	42
Figure 5. 6: Tracking error of robust controller .....	42
Figure 5.7: Sliding surface of robust controller .....	43
Figure 5.8: Control effort of robust controller .....	43
Figure 5.9: Tracking performance of proposed controller .....	44
Figure 5.10: Tracking error of proposed controller.....	44
Figure 5.11: Tracking surface of proposed controller .....	45
Figure 5.12: Control effort of proposed controller .....	45
Figure 5.13: Tracking performance of sliding mode control .....	46
Figure 5.14: Tracking error of sliding mode control.....	47
Figure 5.15: Control effort of sliding mode control .....	47
Figure 5.16: Tracking performance of robust control .....	48
Figure 5.17: Tracking error of robust control.....	48
Figure 5. 18: Control effort of robust control.....	49

Figure 5.19: Tracking performance of adaptive control.....	49
Figure 5.20: Tracking error of adaptive control.....	50
Figure 5.21: Control effort of adaptive control.....	50
Figure 5.22: Tracking performance of proposed control.....	51
Figure 5.23: Tracking error of proposed control.....	51
Figure 5.24: Control effort of proposed control.....	52





## LIST OF TABLE

Table 3.1: Definition of Maglev plant-specific variables.....	27
Table 3.2: Relation between position and control effort .....	30
Table 5.1: Performance measures of four controllers .....	52

