

**NON-LINEAR CONTROL FOR UNDERACTUATED  
MECHANICAL SYSTEMS (COMMUNICATIONS AND  
CONTROL ENGINEERING)**

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**Furuta's Pendulum: A Conservative Nonlinear Model for Theory and Practise**

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Non-linear Control for Underactuated Mechanical Systems (Communications and Control Engineering) [Isabelle Fantoni, Rogelio Lozano] on rudigogy.tk

Non-linear Control for Underactuated Mechanical Systems  
(Communications and Control Engineering) by Rogelio Lozano.  
Rogelio Lozano; Published

Non-linear Control for Underactuated Mechanical Systems.  
(Communications and Control Engineering) by Rogelio Lozano.  
This book deals with the application.

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In Figure 7 we show a successful experiment, where in the top  
figure we show the time histories of the position and the  
velocity of the pendulum and, in the bottom figure the time  
histories of the control input. We reproduce, and comment  
briefly, here Figure 6 from [ 57 ], where the results of the  
experiments were collected.

However, remind that the system has two degrees of freedom and just one actuator.  
This technique was a step ahead after the development of the  
well-known State Feedback Linearisation which linearises the  
state of the system from the control input through a  
non-trivial change of coordinates and control. In Figure 4 we  
show how the added torque compensates the friction.  
The model used for the design was 2. Furuta's pendulum has been an  
excellent benchmark for the automatic control community in the  
last years, providing, among others, a better understanding of  
model-based Nonlinear Control Techniques. Thus, to derive the

Euler-Lagrange equations we calculate the Lagrangian of the system as the difference between the kinetic and potential energies of the whole system from equations 2.