

## 12 – Aeroservoelasticity

Vibraciones y Aeroelasticidad

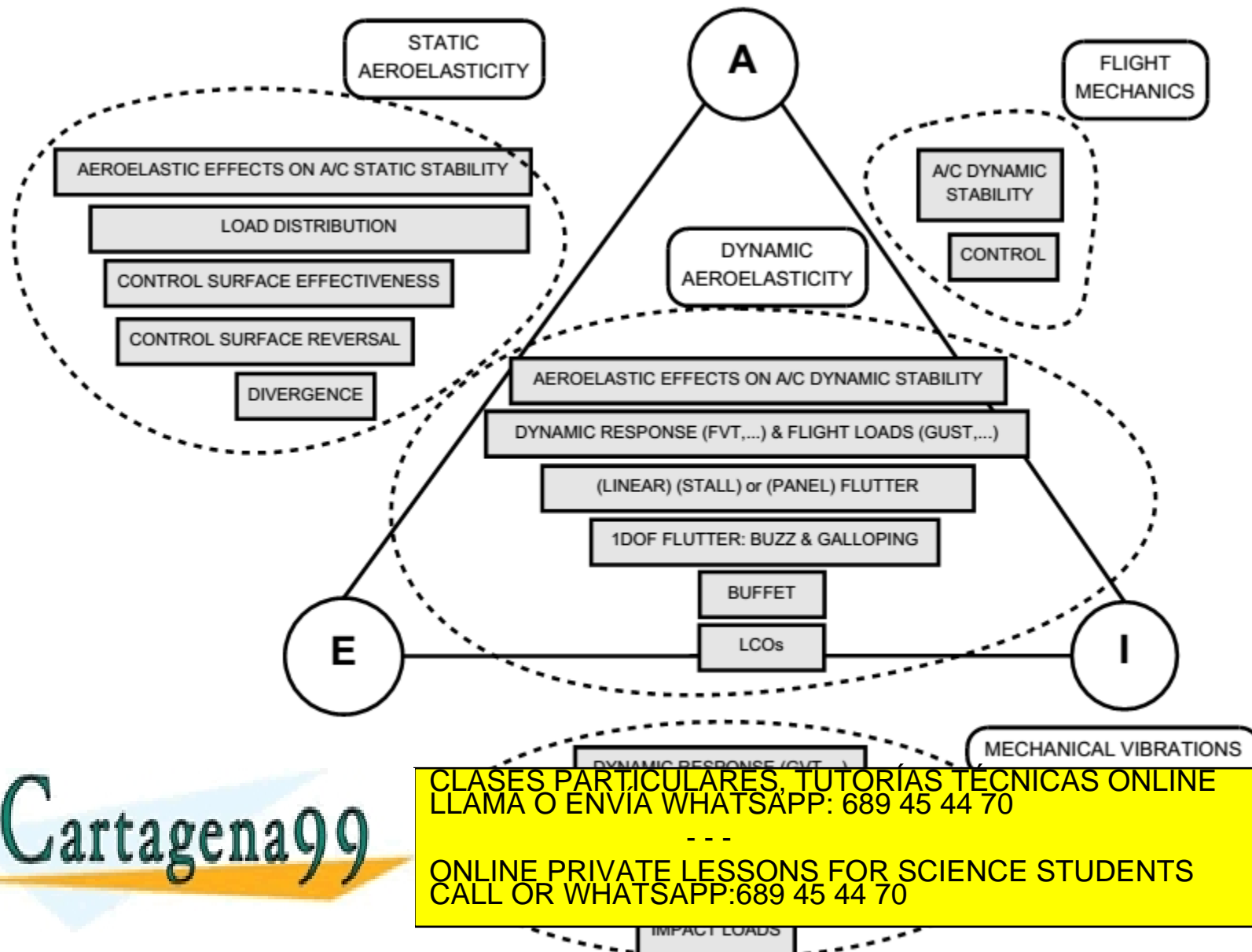
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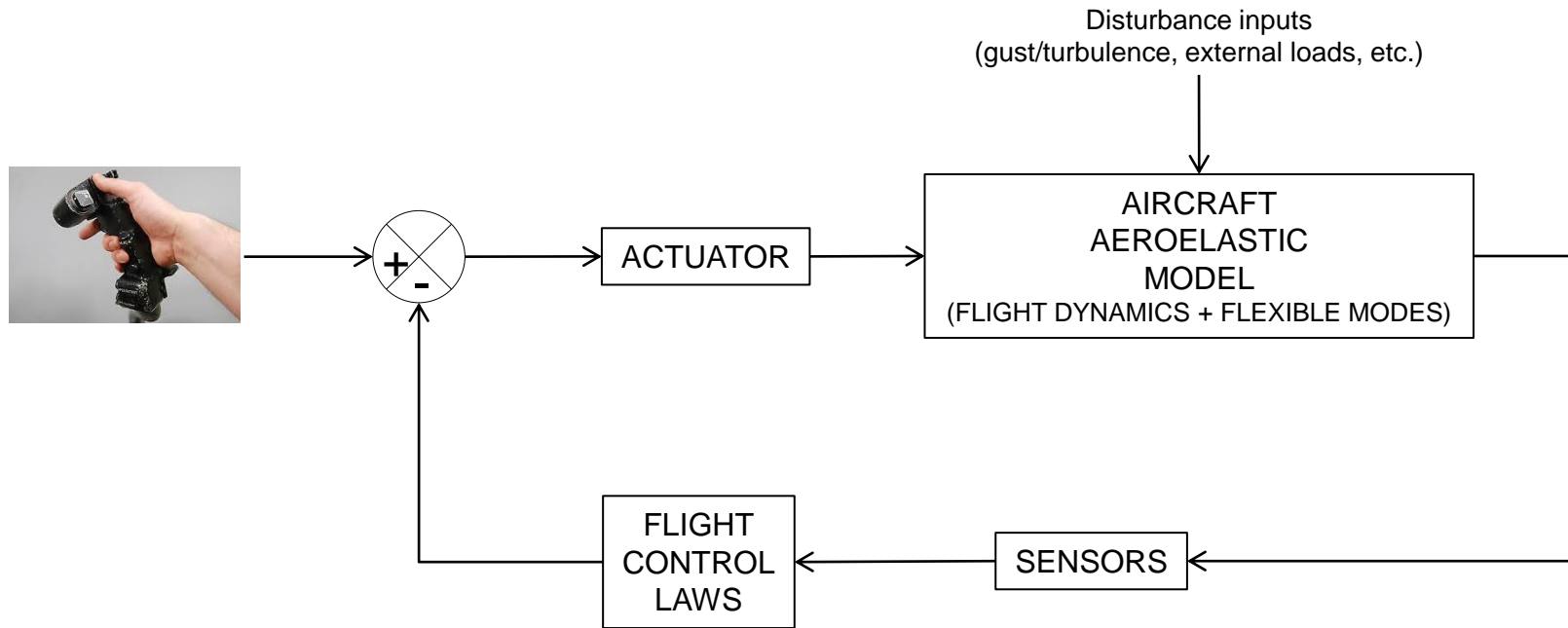
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ESCUELA TÉCNICA SUPERIOR DE INGENIERÍA AERONÁUTICA Y DEL ESPACIO



# BLOCK DIAGRAM OF A TYPICAL AEROSERVOELASTIC SYSTEM



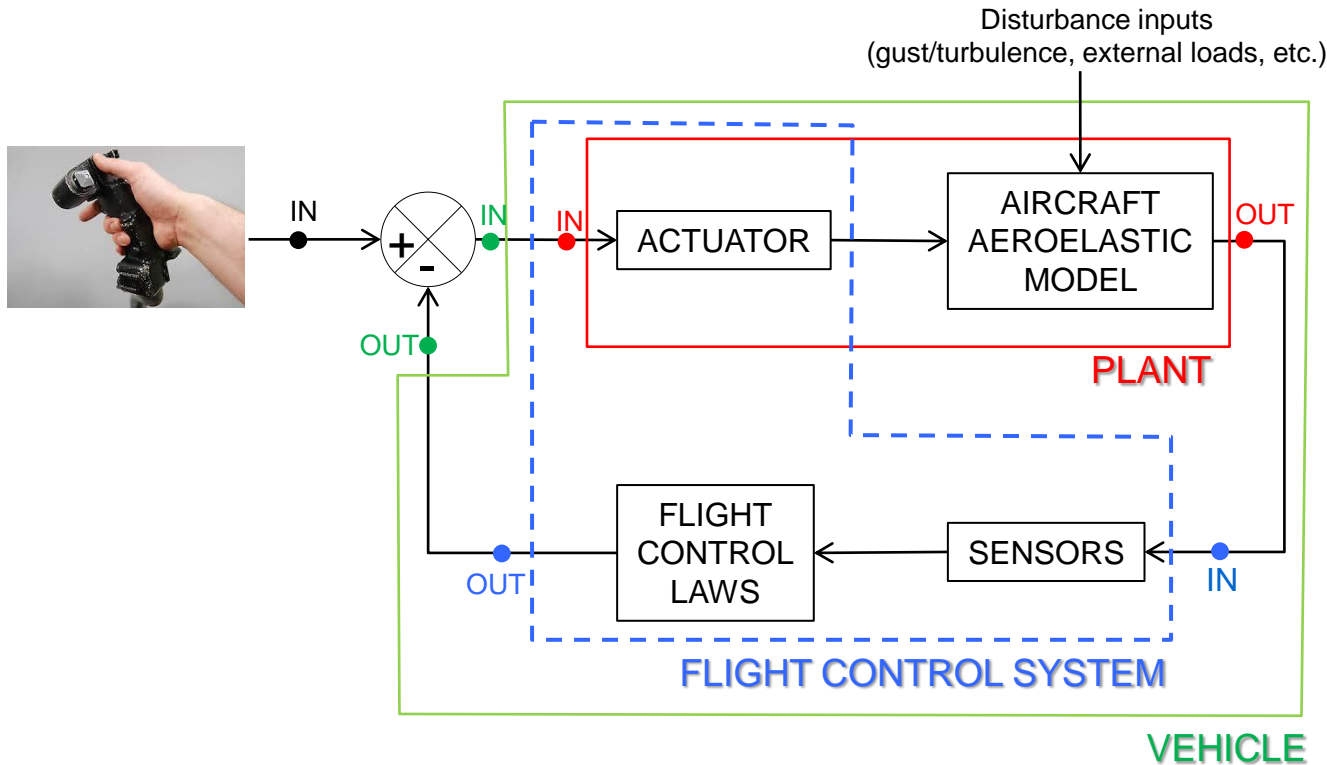
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# CONCEPT OF “PLANT”, “FLIGHT CONTROL SYSTEM”, AND “VEHICLE”



- IN = demanded control surfaces (CS) rotations (pilot inputs)
- IN ●IN = commanded CS rotations
- OUT ●IN = sensors' inputs (displacements, velocities, and accelerations at structural points)

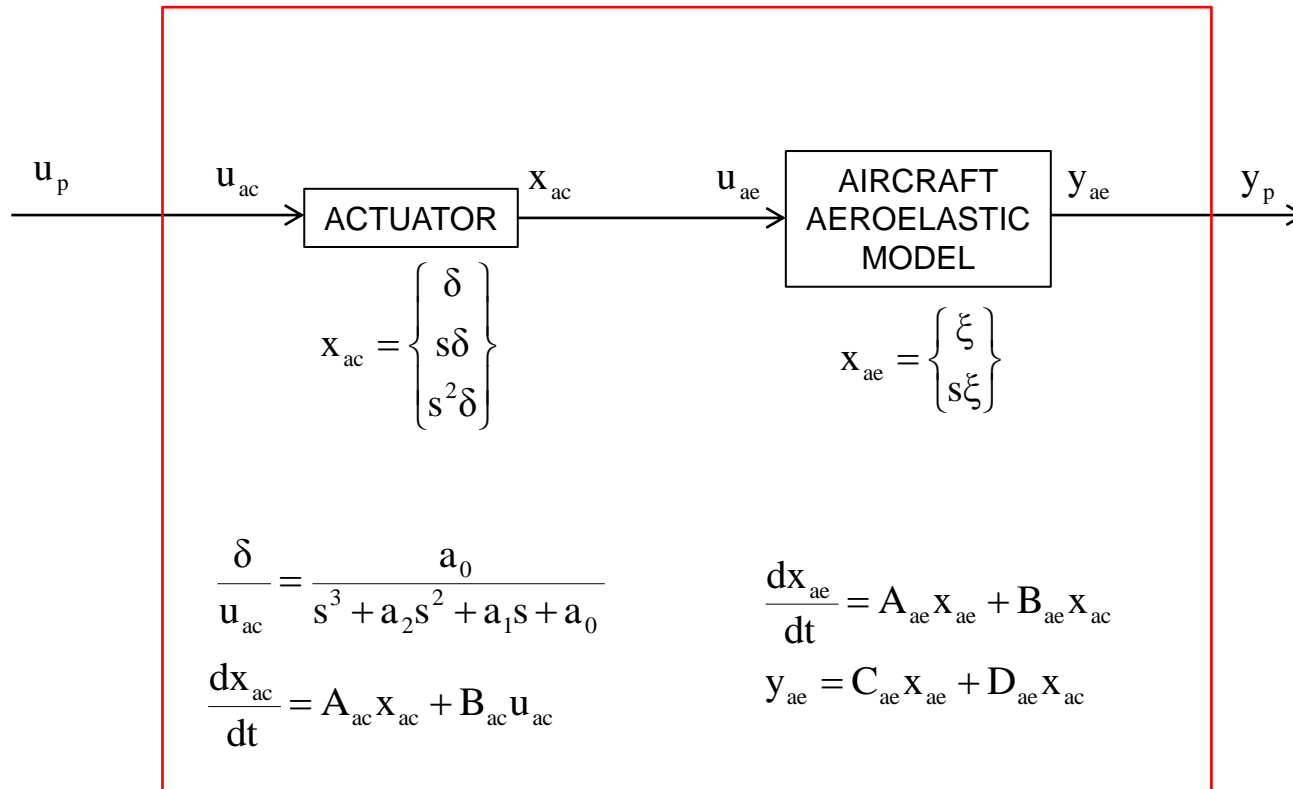
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PLANT



$$\frac{\delta}{u_{ac}} = \frac{a_0}{s^3 + a_2s^2 + a_1s + a_0}$$

$$\frac{dx_{ac}}{dt} = A_{ac}x_{ac} + B_{ac}u_{ac}$$

$$\frac{dx_{ae}}{dt} = A_{ae}x_{ae} + B_{ae}x_{ac}$$

$$y_{ae} = C_{ae}x_{ae} + D_{ae}x_{ac}$$

$$\frac{dx_p}{dt} = \frac{d}{dt} \begin{Bmatrix} x_{ae} \\ x_{ac} \end{Bmatrix} = \begin{bmatrix} A_{ae} & B_{ae} \\ 0 & A_{ac} \end{bmatrix} \begin{Bmatrix} x_{ae} \\ x_{ac} \end{Bmatrix} + \begin{bmatrix} 0 \\ B_{ac} \end{bmatrix} u_{ac} = A_p x_p + B_p u_p$$

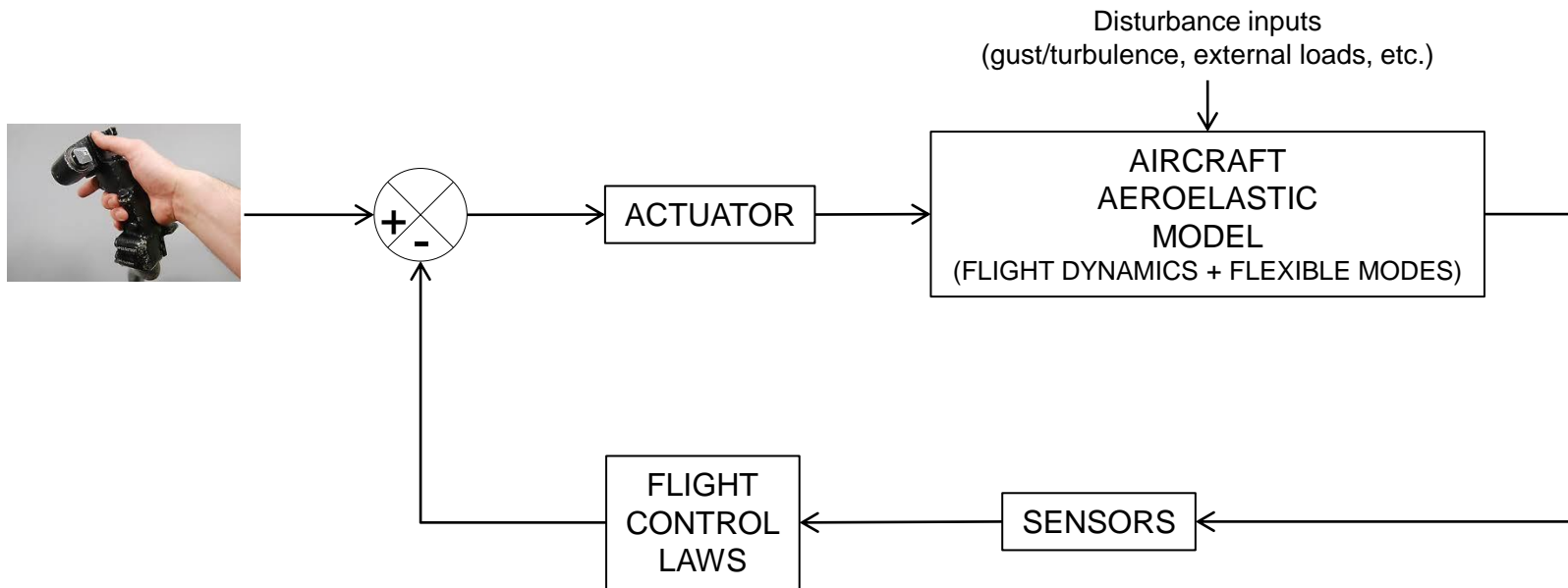
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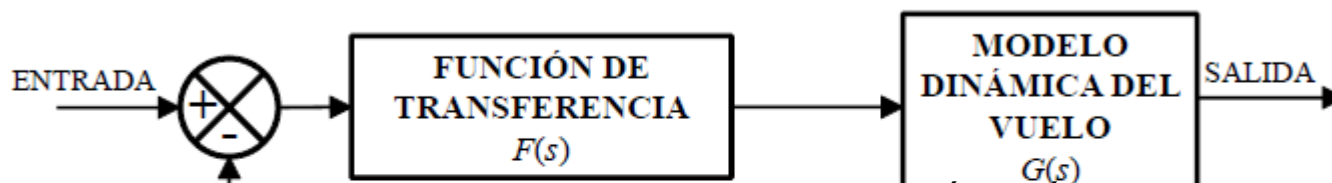
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# SIMPLIFIED BLOCK DIAGRAM



Previous block diagram is simplified by the following scheme:



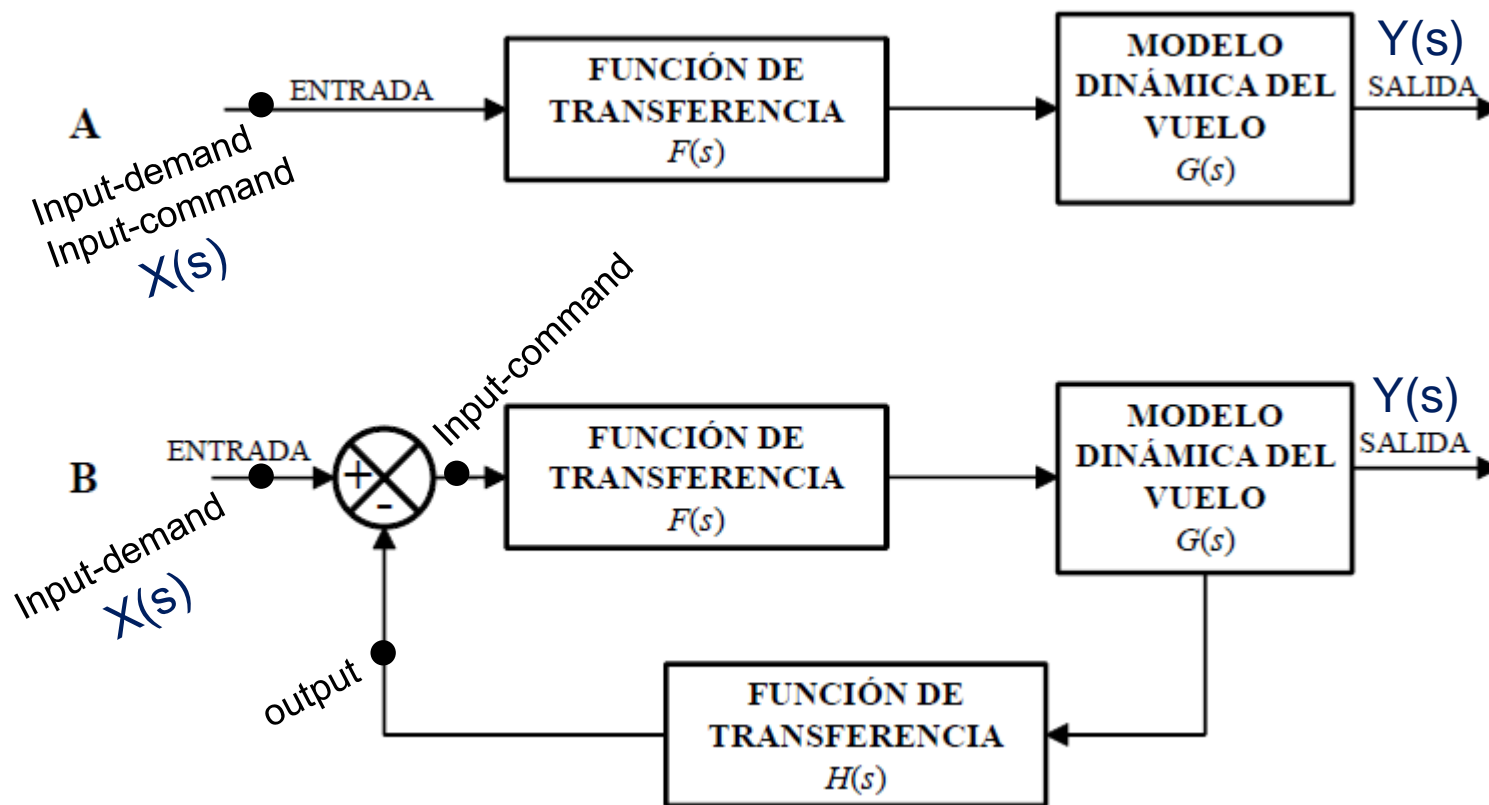
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$H(s)$

# OPEN-LOOP vs. CLOSE-LOOP



Open loop system:

- ❑ The input-demand is used as input-command, which in turn does not depend of the output

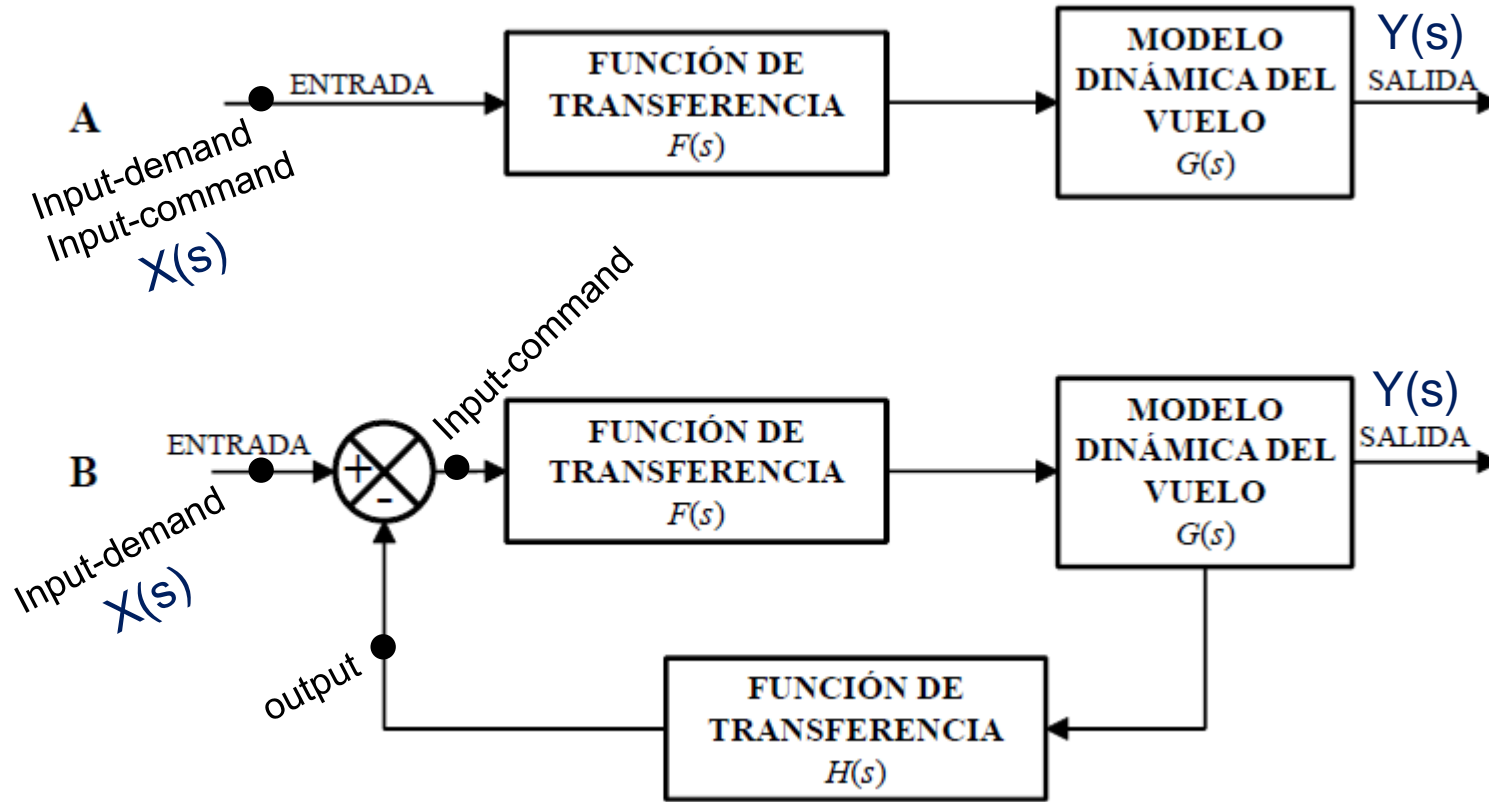
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# TRANSFER FUNCTION



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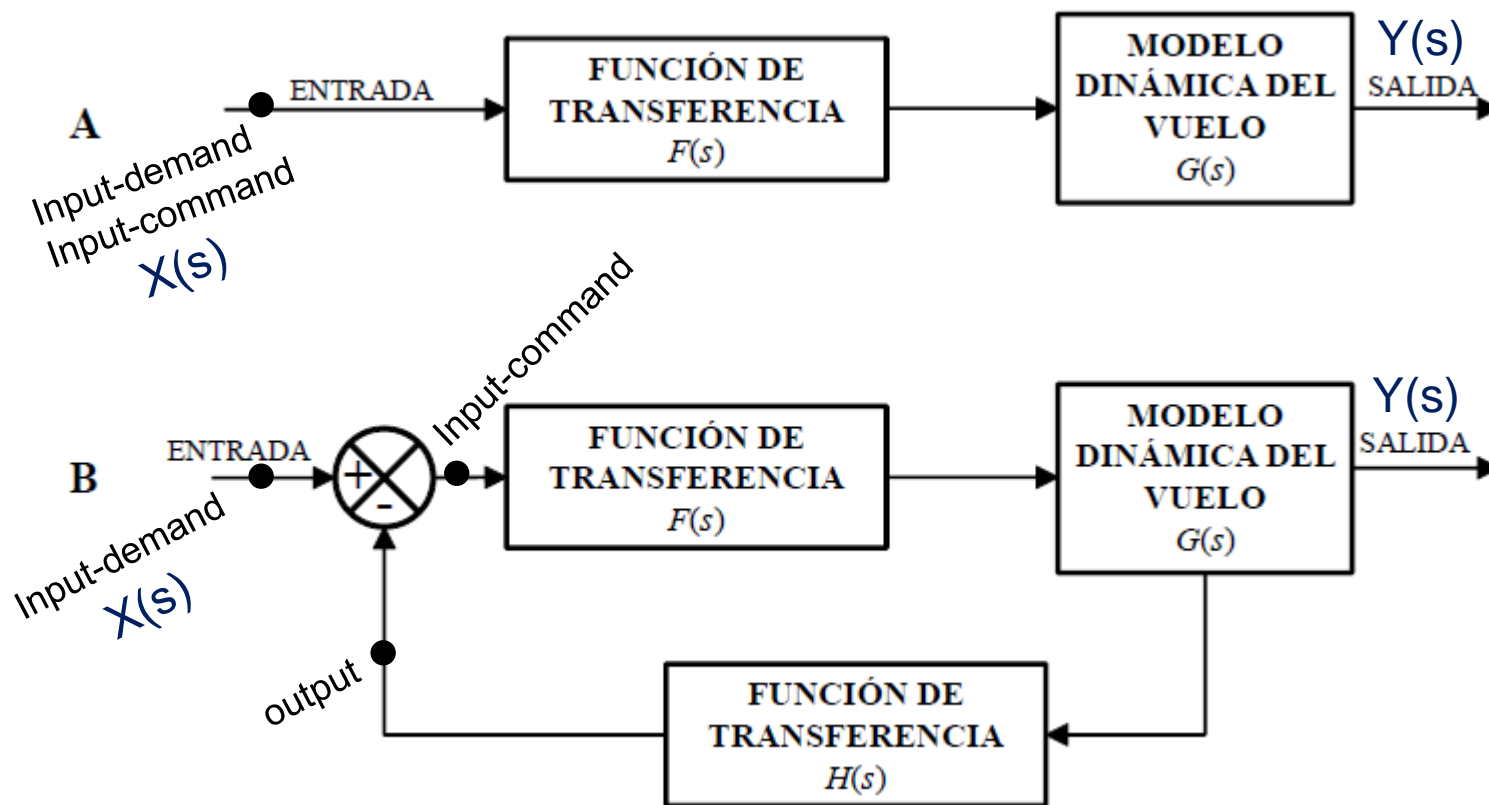
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# TRANSFER FUNCTION



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# Stability criteria: root-locus method of Evans



$$TF_{\text{closed}}(s) = K \frac{s^m + b_{m-1}s^{m-1} + \dots + b_1s + b_0}{s^n + a_{n-1}s^{n-1} + \dots + a_1s + a_0} = K \frac{(s - z_1)(s - z_2) \dots (s - z_m)}{(s - p_1)(s - p_2) \dots (s - p_n)}$$

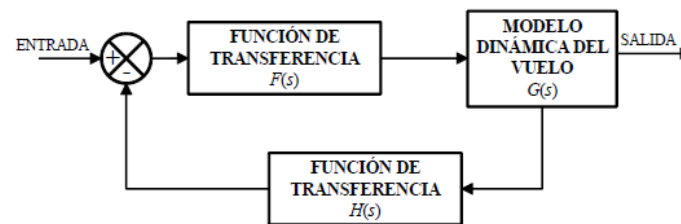
- $s=p_i$  are the “poles” and  $s=z_i$  are the “zeros” of the transfer function
- The “complex conjugate root” theorem states that if  $P(s)$  is a polynomial in one variable with real coefficients, and  $a + bi$  is a root of  $P(s)$  with  $a$  and  $b$  real numbers, then its complex conjugate  $a - bi$  is also a root of  $P(s)$ . Then, the “poles” are real or complex values that are written as:

$$\sigma \pm i\omega = -\zeta\omega \pm i\omega\sqrt{1 - \zeta^2} = -\zeta\omega \pm i\omega_d \approx -\zeta\omega \pm i\omega$$

- The time-domain response is therefore written as (1):

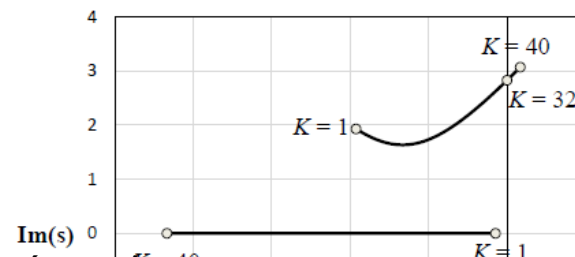
$$A \cdot e^{-\zeta\omega t} \cdot \sin(\omega t + \varphi)$$

- The system is unstable if the real part of one of the poles is positive. The graph of all possible poles with respect to some particular variable (whether system gain or some other parameter) is called the “root locus”, and the design technique based on this graph is called the root-locus method of Evans



$$F(s) = 1, G(s) = \frac{K}{s(s^2 + 4s + 8)} \text{ y } H(s) = 1$$

$$TF_{\text{closed}} = \frac{\frac{K}{s(s^2 + 4s + 8)}}{1 + \frac{K}{s(s^2 + 4s + 8)}} = \frac{K}{s^3 + 4s^2 + 8s + K}$$



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# Stability criteria: the Nyquist plot



$$TF_{\text{closed}}(i\omega) = \frac{F(i\omega)G(i\omega)}{1 + F(i\omega)G(i\omega)H(i\omega)}$$

- For most systems, a simple relationship exists between closed-loop stability and the open-loop frequency response, i.e.,

$$F(i\omega) \cdot G(i\omega) \cdot H(i\omega)$$

- All points at the intersection of the root locus with the imaginary axis (neutral stability) have the property

$$|F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 1 \quad \angle F(i\omega) \cdot G(i\omega) \cdot H(i\omega) = 180^\circ$$

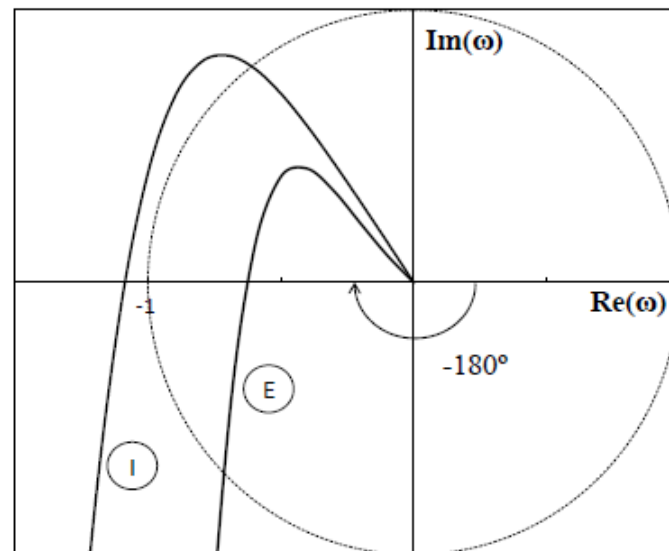
- The stability condition based on the open-loop frequency response is:

$$|F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| < 1 \quad \text{at} \quad \angle F(i\omega) \cdot G(i\omega) \cdot H(i\omega) = -180^\circ$$

- Gain margin

$$20 \cdot \log_{10} |G_M \cdot F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 20 \log_{10} G_M + 20 \log_{10} |F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 1$$

- The system is unstable if the real part of one of the poles is



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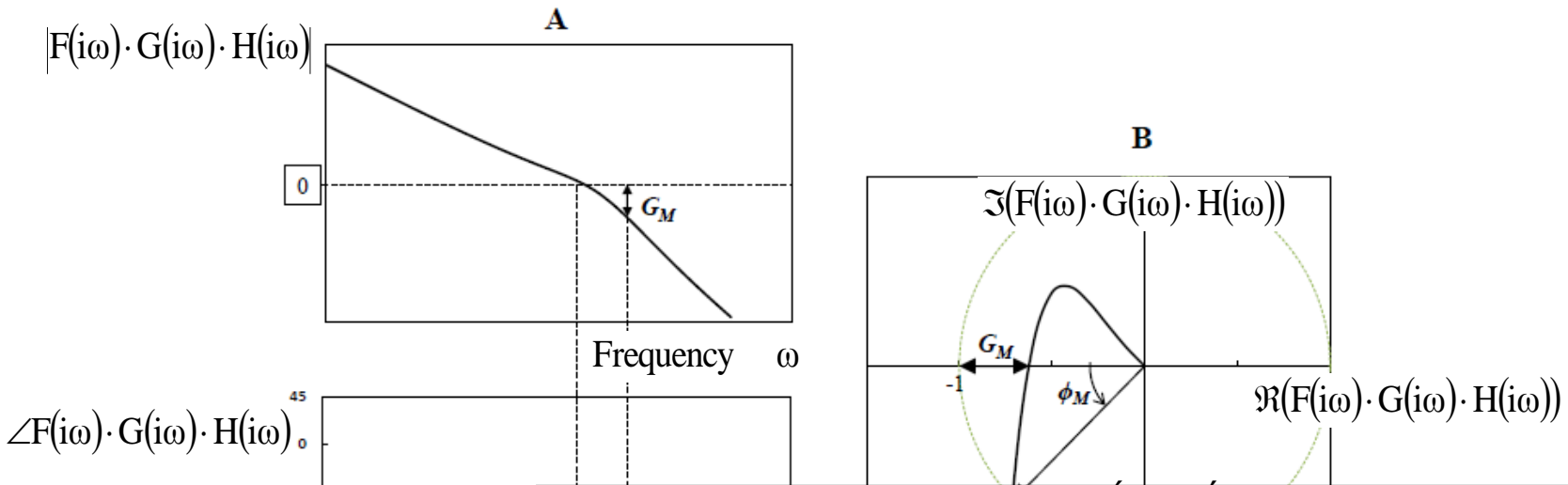
(1070) (4)

# Gain margin and phase margin in Bode and Nyquist plots



$$TF_{\text{closed}}(i\omega) = \frac{F(i\omega)G(i\omega)}{1 + F(i\omega)G(i\omega)H(i\omega)}$$

- Gain margin  $20 \cdot \log_{10} |G_M \cdot F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 20 \log_{10} G_M + 20 \log_{10} |F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 1$
- Phase margin: phase when  $|F(i\omega) \cdot G(i\omega) \cdot H(i\omega)| = 1$



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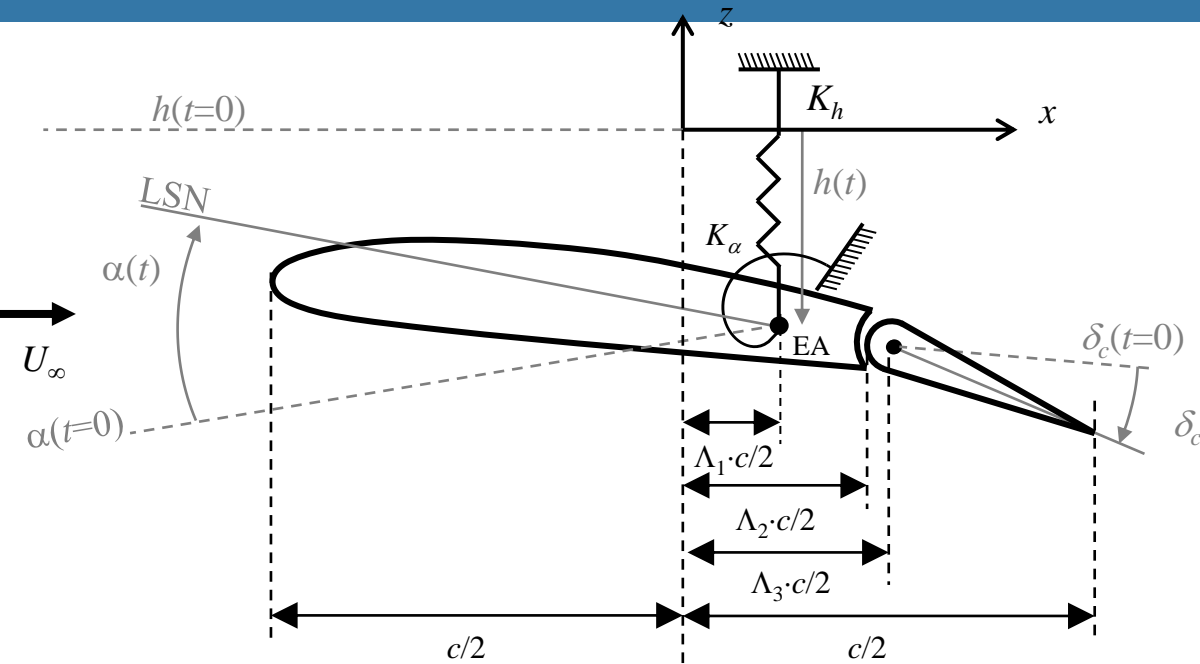
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Frequency  $\omega$

# Example: 2D airfoil



$$\begin{bmatrix} 1 & x_\alpha \\ x_\alpha & r_\alpha^2 \end{bmatrix} \begin{Bmatrix} \ddot{h} \\ \ddot{\alpha} \end{Bmatrix} + \omega_\alpha^2 \begin{bmatrix} \left(\frac{\omega_h}{\omega_\alpha}\right)^2 & 0 \\ 0 & r_\alpha^2 \end{bmatrix} \begin{Bmatrix} \frac{h}{c/2} \\ \alpha \end{Bmatrix} =$$

$$= \frac{q_\infty}{M} \begin{bmatrix} 0 & -4\pi \\ 0 & 4\pi \left(\frac{1}{2} + \Lambda_1\right) \end{bmatrix} \begin{Bmatrix} \frac{h}{c/2} \\ \alpha \end{Bmatrix} +$$

$$\begin{bmatrix} -4\pi & -4\pi \left(\frac{1}{2} + \Lambda_1\right) \end{bmatrix} \begin{Bmatrix} \dot{h} \\ \dot{\alpha} \end{Bmatrix}$$

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$$\frac{1}{M} \begin{bmatrix} 4\pi \left(\frac{1}{2} + \Lambda_1\right) & -4\pi \end{bmatrix} \begin{Bmatrix} r_\delta + \Lambda_3 \cdot c/2 \\ \delta \end{Bmatrix}$$

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$$[\hat{M}_{ij}] \{\ddot{u}_h\} + \omega_\alpha^2 [\hat{K}_{ij}] \{u_h\} \approx \frac{1}{2\pi\mu t_0^2} [\hat{Q}_{ij}^0] \{u_h\} + \frac{1}{2\pi\mu t_0} [\hat{Q}_{ij}^1] \{\dot{u}_h\} + \frac{q_\infty}{2\pi\mu t_0^2} \{\hat{Q}_{ic}\} \delta_c.$$

$$\begin{aligned} \delta_c &= K_p \begin{bmatrix} a_1 & a_2 \end{bmatrix} \begin{Bmatrix} \frac{h}{c/2} \\ \alpha \end{Bmatrix} + t_0 K_d \begin{bmatrix} b_1 & b_2 \end{bmatrix} \begin{Bmatrix} \dot{h} \\ \dot{\alpha} \end{Bmatrix} = \\ &= K_p \begin{bmatrix} a_1 & a_2 \end{bmatrix} \{u_h\} + t_0 K_d \begin{bmatrix} b_1 & b_2 \end{bmatrix} \{\dot{u}_h\}, \end{aligned}$$

$$\begin{aligned} [\hat{M}_{ij}] \{\ddot{u}_h\} + \omega_\alpha^2 [\hat{K}_{ij}] \{u_h\} &= \frac{1}{2\pi\mu t_0^2} [\hat{Q}_{ij}^0] \{u_h\} + \frac{1}{2\pi\mu t_0} [\hat{Q}_{ij}^1] \{\dot{u}_h\} + \\ &+ \frac{1}{2\pi\mu t_0^2} \{\hat{Q}_{ic}\} \left( K_p \begin{bmatrix} a_1 & a_2 \end{bmatrix} \begin{Bmatrix} \frac{h}{c/2} \\ \alpha \end{Bmatrix} + t_0 K_d \begin{bmatrix} b_1 & b_2 \end{bmatrix} \begin{Bmatrix} \dot{h} \\ \dot{\alpha} \end{Bmatrix} \right) = \\ &= \frac{1}{2\pi\mu t_0^2} [\hat{Q}_{ij}^0] \{u_h\} + \frac{1}{2\pi\mu t_0} [\hat{Q}_{ij}^1] \{\dot{u}_h\} + \frac{1}{2\pi\mu t_0^2} [G_p] \{u_h\} + \frac{1}{2\pi\mu t_0} [G_d] \{\dot{u}_h\}, \end{aligned}$$

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$$\begin{aligned} \left\{ \begin{array}{c} L_g \\ M_{ACg} \end{array} \right\} &= q_{\infty} c \left\{ \begin{array}{c} C_{L\alpha} \\ e C_{L\alpha} \end{array} \right\} \frac{w_g}{U_{\infty}} \\ &= \frac{1}{2} \frac{\rho_{\infty} U_{\infty}^2}{M} \left\{ \begin{array}{c} 2 C_{L\alpha} \\ 2 \frac{e}{c} C_{L\alpha} \end{array} \right\} \frac{w_g}{U_{\infty}} = \\ &= \frac{1}{2\pi} \frac{M}{\rho_{\infty} \left(\frac{c}{2}\right)^2} \left(\frac{c}{2U_{\infty}}\right)^2 \left\{ \begin{array}{c} 2 C_{L\alpha} \\ 2 \frac{e}{c} C_{L\alpha} \end{array} \right\} \frac{w_g}{U_{\infty}} = \\ &= \frac{1}{2\pi \mu t_0^2} \left\{ \hat{Q}_{ig} \right\} \hat{w}_g. \end{aligned}$$

$$\begin{aligned} [\hat{M}_{ij}] \{\ddot{u}_h\} - \frac{1}{2\pi \mu t_0} \left( [\hat{Q}_{ij}^1] + [G_d] \right) \{\dot{u}_h\} + \\ + \left[ \omega_{\alpha}^2 [\hat{K}_{ij}] - \frac{1}{2\pi \mu t_0^2} \left( [\hat{Q}_{ij}^0] + [G_p] \right) \right] \{u_h\} = \frac{1}{2\pi \mu t_0^2} \left\{ \hat{Q}_{ig} \right\} \hat{w}_g. \end{aligned}$$

$$\frac{\{\tilde{u}_h\}}{\hat{w}_0} = H_{ig}(\omega) =$$

$$= \frac{1}{\left[ \dots \right]}$$

$$PSD_{OUT} = |H_{ig}(\omega)|^2 PSD_{CT}$$

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