

Contents

Preface

1	Introduction	1
1.1	History	1
1.2	Definitions	3
1.3	Types of Structures	5
1.4	Types of Problems	7
1.5	Qualitative Analysis in State Space	7
1.5.1	Example of Static Transient Loading	8
1.5.2	Example of Dynamic Transient Loading	9
1.6	Constituents of Adaptive Structures	10
1.6.1	Structure	10
1.6.2	Sensors	14
1.6.3	Actuators	15
1.6.4	Microprocessors and Their Software	16
1.7	Objectives, Scope, and Outline	17
2	Incremental Excitation-Response Relations, Static Case	19
2.1	Basic Definitions	19
2.1.1	Structure	19
2.1.2	Excitations	21
2.1.3	Incremental Response	22
2.1.4	Excitation-Response Relations	25
2.2	Equilibrium of Forces	25

2.2.1	Equilibrium of Structural Elements	26
2.2.2	Equilibrium of Nodes	28
2.2.3	Effect of Preexisting Internal Forces	31
2.3	Geometric Relations	36
2.3.1	Case When $\Delta \mathbf{v}_o = \mathbf{o}$	36
2.3.2	Case When $\Delta \xi = \mathbf{o}$	37
2.3.3	Final Form	39
2.4	Stiffness Relations of Elements	39
2.4.1	Element Stiffness Matrices	40
2.4.2	Element Flexibility Matrices	41
2.4.3	Obtaining $\mathbf{K}^k$ from $\mathbf{F}^k$	43
2.5	Incremental Excitation-Response Relations	45
3	Active Control of Response, Static Case	47
3.1	Inverse Relations	48
3.1.1	By Displacement Method	48
3.1.2	By Force Method	50
3.1.3	Statically Determinate Case	53
3.2	Actuators of Adaptive Structures	54
3.3	Basic Equations for Adaptive Structures	55
3.4	Actuator Locations and Controls	56
3.5	Observed Response Components and Output	57
3.6	Determination of Controls	58
3.7	Fate of Unobserved Response Components	60
3.8	Control Energy	62
3.9	Compatibility of Controls in Adaptive Structures	64
3.10	Recapitulation	65
4	Statically Determinate Adaptive Structures	67
4.1	Excitation-Response Relations	67
4.2	Observed Response Components and Disturbances	69
4.3	Actuators and Controls	70
4.4	Actuator Placement and Control Problems	71
4.5	Actuator Placement and Control Computation When $q =$ $p < n$	73
4.5.1	Actuator Placement Problem	73
4.5.2	Computation of Controls	74
4.6	Actuator Selection and Control Computation When $p < q = n$	75
4.6.1	Actuator Selection Problem	75
4.6.2	Computation of Controls in Selected Actuators	76
4.7	Actuator Placement and Control When $p < q < n$	76
4.7.1	Actuator Placement Problem	77
4.7.2	Selection of Actuators and Computation of Controls	78
4.8	Precision Control	78
4.9	Adaptive Trusses as Slow Moving Mechanical Manipulators	79

4.9.1	Actuator Placement When $p = q < n$	82
4.9.2	Actuator Selection When $p < q = n$	82
4.9.3	Actuator Placement When $p < q < n$	82
4.9.4	Computation of Controls	83
4.10	Generation of Output-Control Matrix	83
4.11	Recapitulation	86
5	Statically Indeterminate Adaptive Structures	87
5.1	Excitation-Response Relations	87
5.1.1	Relations for Adaptive Structures	88
5.1.2	Inverse Relations	88
5.1.3	Computation of Matrices $\mathbf{C}$ and $\mathbf{C}'$	89
5.1.4	Response due to $\Delta \mathbf{v}_o$	90
5.2	Observed Response Components and Disturbances	92
5.3	Actuators and Controls	93
5.4	Prevention of Stress Build-up	94
5.5	Secondary Actuators	97
5.5.1	Transformation of Compatibility Equation	97
5.5.2	Placement and Control of Secondary Actuators	99
5.6	Primary Actuators	100
5.6.1	Number of Primary Actuators q	101
5.6.2	Placement and Control of Primary Actuators	103
5.6.3	Generation of Matrix $\mathbf{I}_\alpha^T \mathbf{B}_1^{-T}$	107
5.7	Recapitulation of Actuator Placement	107
5.8	Recapitulation	108
6	Excitation-Response Relations, Dynamic Case	109
6.1	Equilibrium Equations	109
6.1.1	Restoring Forces	110
6.1.2	Inertial Forces	111
6.1.3	Frictional Forces	113
6.1.4	External Forces	114
6.1.5	Dynamic Equilibrium Equations of Nodes	114
6.2	Geometric Relations	115
6.2.1	Uncontrolled Part of Prescribed Element Deformations	115
6.2.2	Controlled Part of Prescribed Element Deformations	116
6.3	Stiffness Relations of Elements	117
6.4	Excitation-Response Relations	117
6.4.1	Dynamic Equilibrium Equations in terms of ξ	118
6.4.2	Equations of Motion of Nodes	119
6.4.3	Initial Conditions	120
7	Inverse Relations, Dynamic Case	121
7.1	Method for Obtaining the Inverse Relations	121
7.2	Undamped Free Vibrations of Nodes	124

7.3	Damped Free Vibrations of Nodes	128
7.4	Nodal Motion due to Nodal Forces	130
7.5	Nodal Motion due to Prescribed Element Deformations . .	132
7.6	Nodal Vibrations due to Support Movements	133
7.7	Nodal Motion due to Actuator Induced Deformations . . .	134
7.8	Trajectory of Nodes in State Space	135
7.8.1	Uncontrolled Autonomous System	136
7.8.2	Uncontrolled Non-Autonomous System	140
7.8.3	Controlled Autonomous System	143
7.8.4	Controlled Non-Autonomous System	144
7.9	Steady State of Nodal Deflections	145
7.9.1	Time Function of Loads Becomes Constant	146
7.9.2	Time Function of Loads is Cyclic	146
7.10	Recapitulation of Inverse Relations	148
8	Active Control of Response, Autonomous Case	149
8.1	Response to Actuator Induced Element Deformations . . .	149
8.2	Energy Cost of Inducing Element Deformations	151
8.2.1	Element Forces by the Displacement Method	152
8.2.2	Element Forces by the Force Method	152
8.3	Response Control	154
8.4	Open-Loop Control	155
8.5	Optimal State Feedback Control	157
8.5.1	Identification of Optimal Trajectory	158
8.5.2	Identification of the Optimal Control Law	160
8.5.3	Practical Difficulties with Optimal State Control . .	162
8.6	Optimal Output Feedback Control	163
8.7	Optimal Direct Output Feedback Control	165
8.8	Alternatives to Optimal Control	169
8.8.1	Choosing Gain Matrix by Trial and Error	169
8.8.2	Choosing Gain Matrix by Eigenvalue Assignment . .	172
8.9	Actuator Placement	176
8.9.1	Placement Criteria to Minimize Control Time	177
8.9.2	Placement Criteria to Minimize Spill-Over	178
8.10	Time Lag in Feedback Control	180
8.11	Recapitulation, Autonomous Case	181
9	Active Control of Response, Non-Autonomous Case	183
9.1	Total Response Including Control Excitations	183
9.1.1	Treatment in n -Space	183
9.1.2	Treatment in State Space	186
9.2	Response Control	187
9.3	Energy Considerations	188
9.4	Optimal State Feedback Control	190
9.4.1	Case When Excitation is Known <i>a Priori</i>	190

9.4.2	Case When Tracked Trajectory is Known <i>a Priori</i> . . .	192
9.4.3	Case When Excitation is not Known <i>a Priori</i>	193
9.5	Non-Optimal Control Possibilities	193
9.6	Actuator Placement	194
9.7	Recapitulation, Non-Autonomous Case	196
10	Active Control Against Wind	197
10.1	State Equations for Wind Type Excitations	198
10.2	Control Possibilities of Nodal Motion	199
10.2.1	Insulate Structure Against Wind Forces	199
10.2.2	Determine Controls by Measuring Nodal Wind Forces	199
10.2.3	Determine Controls by Measuring the State	200
10.3	Excitation Power	201
10.4	What to Control	202
10.5	Actuator Placement	204
10.6	Control Law	206
10.7	Recapitulation of Active Control Against Wind	207
11	Active Control Against Seismic Loads	209
11.1	State Equations for Seismic Excitations	209
11.2	Control Possibilities of Nodal Motion	210
11.2.1	Insulate Structure Against Support Motions	211
11.2.2	Determine Controls by Sensing Support Motion . . .	211
11.2.3	Determine Controls by Sensing the State	212
11.3	Managing Excitation Power	213
11.4	Passive Base Isolation Systems	214
11.4.1	Justification	215
11.4.2	Analysis	217
11.5	Actuator Placement for Active Base Isolation	219
11.5.1	Planar Frames under Horizontal Ground Motion . .	219
11.5.2	Planar Frames under Vertical Ground Motion . . .	220
11.5.3	Space Frames under Horizontal Ground Motion . . .	221
11.6	Control of Active Base Isolation Systems	222
11.6.1	Control Energy	222
11.6.2	Control System	223
11.6.3	Control Law	223
11.7	Recapitulation of Active Control Against Seismic Excitations	225
12	Distributed Parameter Adaptive Structures	227
12.1	Incorporating Intelligence	227
12.2	Composite Materials	229
12.2.1	Piezo-Electric Composite Materials as Actuators . .	229
12.2.2	Piezo-Electric Composite Materials as Sensors . . .	230
12.2.3	Distributed Parameter Adaptive Structures	230
12.3	Static Case	233

Contents

12.3.1	Incremental Linear Excitation-Response Relations .	233
12.3.2	Inverse Relations	242
12.3.3	Compatibility of Induced Strains	248
12.3.4	Control	249
12.4	Dynamic Case	250
12.4.1	Excitation-Response Relations	250
12.4.2	Inverse Relations	252
12.4.3	Control	253
12.5	Recapitulation	254
References		255