Comment on "Optimum Placement of Controls for Static Deformations of Space Structures"

Menahem Baruch*
*Technion—Israel Institute of Technology
Haifa, Israel*

IN an interesting paper,[1] Professor Haftka describes a method for optimum control of static deformations of space structures. However, it must be emphasized that not only are the deformations of the space structures static but, appropriately, the means of control are also static. Having this in mind, it is not apparent to this author why Prof. Haftka had to involve the mass of the structure in his equations. In an approach somewhat different to that given in the paper,[1] it will be shown here that one can develop adequate equations for the static control of a space structure without involving the mass of the structure.

It will be assumed that the free space structure is represented by its stiffness matrix $K(n \times n)$, usually obtained by using finite element methods. This matrix is needed to calculate the deformations of the structure constrained in a statically definite way. The distortion from the desired shape of the structure is represented by the deformation vector $\psi(n \times 1)$. Thermal or force controls are applied on the structure to minimize the distortion. The rigid body displacements of the structure are characterized by the matrix $R(n \times r)$. (For space structures, $r = 6$.) For convenience, the matrix R can be orthonormalized to obtain

$$R^T R = I \tag{1}$$

The vector ψ is assumed to represent only shape distortion. Hence, it is orthogonal to R,

$$R^t \psi = 0 \tag{2}$$

The vector $\Delta T(m \times 1)$ represents the temperature of m heating control points on the structure. By restraining the structure in a statically definite way, one can calculate the deformations caused by applying a separate unit temperature at any one of the control points. The result will be a field of displacements represented by the matrix $u_0(n \times m)$. Note that the displacements of the r restrained points are zero. The displacement vector of the free structure is given by

$$u = u_0 \Delta T + R\beta \tag{3}$$

where $\beta(r \times 1)$ represents the amount of any of the rigid body displacements. u, like ψ, has to be orthogonal to R,

$$R^t u = R^t u_0 \Delta T + R^t R\beta = 0 \tag{4}$$

From Eqs. (1), (3), and (4), one obtains

$$\beta = -R^t u_0 \Delta T \tag{5}$$

and

$$u = (I - RR^t) u_0 \Delta T \tag{6}$$

The total displacement vector caused by the distortion and the controls will be given by

$$u_T = \psi + u \tag{7}$$

It is appropriate to minimize the Euclidian norm of u_T

$$u_T^2 = (\psi^t + u^t)(\psi + u) \tag{8}$$

Now,

$$\frac{\partial u_T^2}{\partial \Delta T} = 0 = 2u_0^t \psi + 2u_0^t [I - RR^t] u_0 \Delta T \tag{9}$$

or

$$A \Delta T = q \tag{10}$$

where

$$A = u_0^t [I - RR^t] u_0, \qquad q = -u_0^t \psi \tag{11}$$

As pointed out by Prof. Haftka,[1] in the case of force control the forces applied on the free structure must be in equilibrium. This means that any particular group of control forces can be characterized by one parameter P_i. The number of control forces is now represented by the vector $P(m \times 1)$ where m is the number of independent force parameters. Clearly, for the force control, one has to replace ΔT by P and no special treatment is needed.

Following Ref. 1, one can define an efficient coefficient

$$g^2 = u_T^2 / \psi^2 \tag{12}$$

It is easy to show that

$$g^2 = \frac{u_T^t u_T}{\psi^t \psi} = 1 - \frac{\Delta T^t q}{\psi^t \psi} \tag{13}$$

Equation (13) is identical to Eq. (16) of Ref. 1. However, the ΔT (or P) are different than those obtained by Prof. Haftka.[1] Now, g or some power of it can be minimized with respect to the placement of the control points by using some of the powerful procedures existing in the literature.[1] ΔT or P must satisfy Eq. (10). An additional constraint is that the control points must belong to the structure.

References

[1]Haftka, R. T., "Optimum Placement of Controls for Static Deformations of Space Structures," *AIAA Journal*, Vol. 22, Sept. 1984, pp. 1293-1298.

Reply by Author to M. Baruch

Raphael T. Hafkta*
*Virginia Polytechnic Institute and State University
Blacksburg, Virginia*

PROFESSOR Baruch's Comment covers three main points:

1) To note that in a static problem there is no need to use the mass properties (mass matrix) of the structure.

2) To present an alternate derivation of the equations for static control for discrete models.

3) To suggest using equilibrated actuator force groups instead of individual nodal forces as a way of making the force control problem indentical in form to the thermal control problem.

I agree with all of the comments, but the following clarifications are in order.

1) The alternate discrete derivation presented by Professor Baruch is very similar to that presented in Ref. 1 (Ref. 15 of my paper), and can be obtained from it by setting the mass matrix equal to the identity matrix.

2) The use of equilibrated force groups does remove the need for special treatment for force controls, but it may not be as convenient to the designer. Therefore the special treatment presented in the paper is useful.

References

[1]Haftka, R. T. and Adelman, H. M., "An Analytical Investigation of Shape Control of Large Space Structures by Applied Temperatures," presented at the 4th VPI&SU/AIAA Symposium on Dynamics and Control of Large Structures, Blacksburg, Va., June 1983; also, *AIAA Journal*, Vol. 23, March 1985, pp. 450-457.

ERRATA

• "Swirling Flow in a Research Combustor," Vol. 23, No. 2, 1985, pp. 241-248. The second author's name is H. T. Somer; he is Assistant Professor at Carnegie-Mellon University. In Ref. 11, the last name of the second author is Gouldin.

• "The Circular Cylinder in Subsonic and Transonic Flow," Vol. 22, No. 2, 1984, pp. 1713-1718. In the caption for Fig. 8, $\Delta t = 30$ μs, not 0.30 μs.

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