

Stabilizing controller for riser subsys.

Riser dynamics:

$$\begin{cases} \dot{x}_3 = w_g - \alpha w \\ \dot{x}_4 = w_g + w_l - w \end{cases} \quad (x_3, x_4) = (m_{gr}, m_{lr} + m_{gr})$$

System equations in y coordinates:

$$y_1 = P_{rb} = y_2 + cx_4 + F_r \quad y_2 = P_{rt} = \frac{ax_3}{b+x_3-x_4}$$

$$\begin{cases} \dot{y}_1 = (w_g + w_l) [F(y) + c] - [F(y) + c] w \\ \dot{y}_2 = (w_g + w_l) F(y) - F(y) w \end{cases}$$

$$F(y) = c \left(1 - \frac{y_2}{a} \right) \frac{a\alpha + y_2(1 - \alpha)}{bc - (y_1 - y_2 - F_r)}$$



Stabilizing Dynamics

Judd E. Hollander



Stabilizing Dynamics:

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