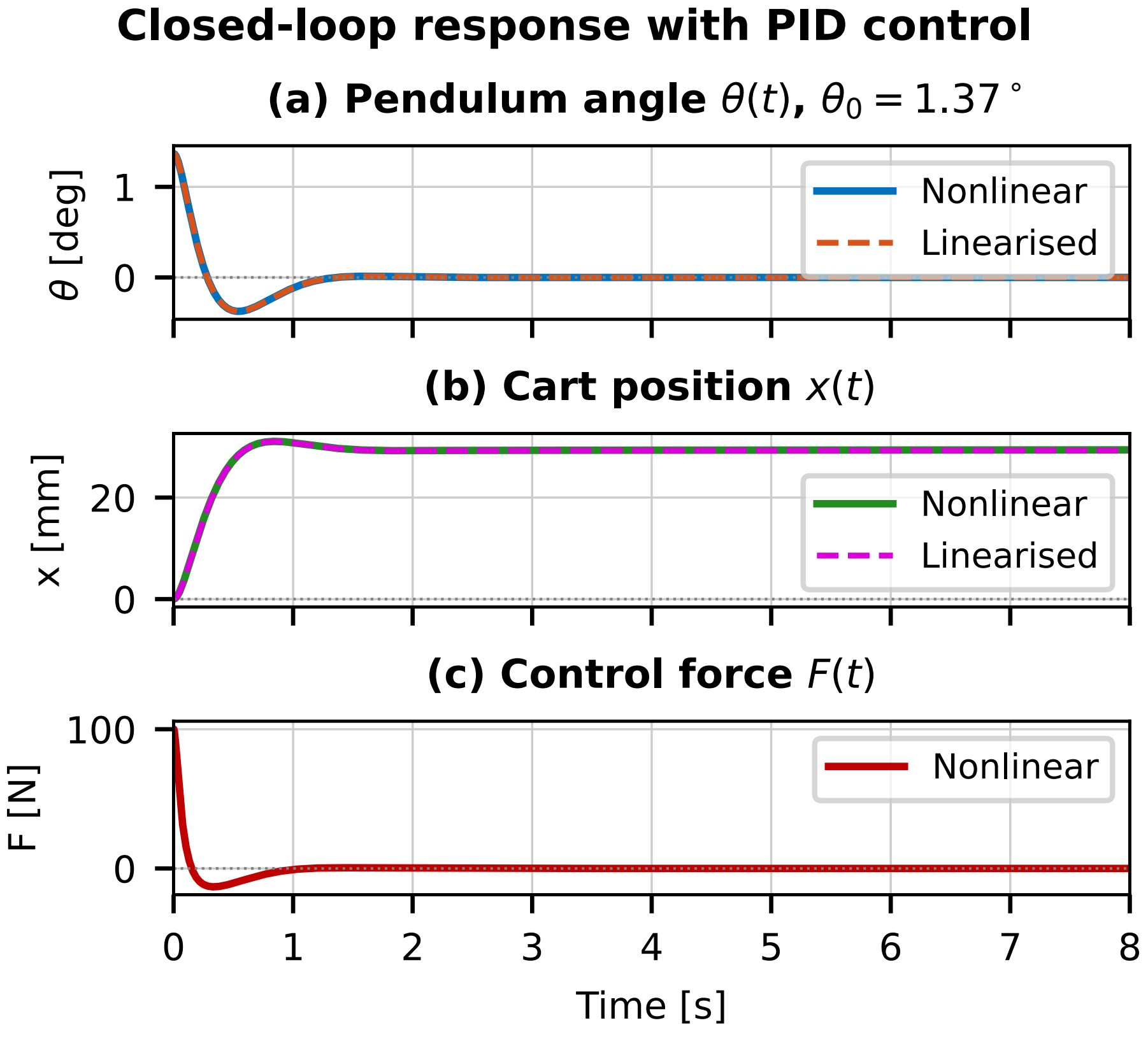

Closed-loop response with PID control
(a) Pendulum angle $\theta(t)$, $\theta_0 = 1.37^\circ$
θ [deg]
1
0
Nonlinear
Linearised
(b) Cart position $x(t)$
x [mm]
20
0
Nonlinear
Linearised
(c) Control force $F(t)$
F [N]
100
0
Nonlinear
0
1
2
3
4
5
6
7
8
Time [s]