

بسم الله الرحمن الرحيم

**SUDAN UNIVERSITY OF SCIENCE AND TECHNOLOGY**  
**COLLEGE OF GRADUATE STUDIES**

**DESIGN OF AIRCRAFT LANDING CONTROL  
SYSTEM USING FUZZY LOGIC**

**تصميم نظام تحكم في هبوط الطائرة بإستخدام  
المنطق الغامض**

**A Thesis Submitted in Partial Fulfillment to the Requirements for the  
Degree of M.Sc. In Electrical Engineering (Control and Microprocessor)**

**Prepared by:**

**Elnail Kamal Eldin Idris Ahmed**

**Supervised by:**

**Dr. Awadalla Taifour Ali**

**January 2012**

الآلية

بِسْمِ اللَّهِ الرَّحْمَنِ الرَّحِيمِ

( أَوَلَمْ يَرُوا إِلَى الطَّيْرِ فَوْقَهُمْ صَافَّاتٍ وَيَقْبِضُنَّ مَا  
يُمْسِكُهُنَّ إِلَّا الرَّحْمَنُ إِنَّهُ بِكُلِّ شَيْءٍ بَصِيرٌ )

(سورة الملك الآية 19)

## **DEDICATION**

*To my father and mother*

*To my wife and my daughter (omnia)*

*And my sons (Abdelrohman and Arife)*

*To my brothers and sisters*

*To all my friends*

## **ACKNOWLEDGMENT**

**Thankfulness firstly and lastly to GOD for his blessing for accomplishing this project in this form.**

**I would like to express my sincere appreciation to my supervisor for their countless support, Dr. Awadalla Taifor Ali.**

**I'm forever grateful for his words of encouragement, moral support, friendship, and advice he has been giving me, Ing.Mustafa Eltsyeb Mohammed.**

**In addition, I great fully acknowledge the support of my family, and my friends who aided me to complete this project.**

## **ABSTRACT**

Since the Climate factors have strong negative effect on the process of landing, which makes crew needs a proper automatic landing system, to reduce the total landing cost by landing the aircraft at prescribed time.

This project presents an intelligent control scheme that use a fuzzy logic controller in automatic aircraft landing control that will make the automatic landing systems (ALS) more intelligent. A design methodology has been proposed based on conventional control and repeated using fuzzy logic.

The main goal of this research is to design a fuzzy logic controller to aid in landing the aircraft safely in all weather conditions. To examine the fuzzy controller performance, MATLAB fuzzy tool box is used.

## مستخلص

بما ان العوامل المناخية تؤثر سلباً وبقوة في عملية الهبوط، مما يجعل الطاقم في حوجة الى نظام هبوط آلي فعال، لتقليل تكلفة الهبوط الاجمالية وذلك بهبوط الطائرة في زمن الهبوط المحدد.

هذا البحث يعرض فكرة التحكم الذكي في الهبوط الآلي للطائرات باستخدام متحكم المنطق الغامض لجعل النظام اكثراً ذكاءً. خطة التصميم المقترنة هي التصميم باستعمال التحكم التقليدي من ثم اعادته باستخدام المنطق الغامض.

الهدف الاساسي لهذا البحث هو تصميم متحكم غامض للمساعدة في هبوط الطائرة بأمان في جميع حالات الطقس. لاختبار أداء المتحكم الغامض تم استخدام صندوق ادوات المنطق الغامض في برنامج الماتلاب.

## **TABLE OF CONTENTS:**

|                                  |     |
|----------------------------------|-----|
| الآية .....                      | i   |
| DEDICATION .....                 | ii  |
| ACKNOWLEDGMENT .....             | iii |
| ABSTRACT .....                   | Iv  |
| مستخلص .....                     | v   |
| TABLE OF CONTENTS .....          | vi  |
| TABLE OF SYMBOLS .....           | ix  |
| List of ABBREVIATION .....       | xi  |
| <b>CHAPTER ONE: INTERDOCTION</b> |     |
| 1.1 General .....                | 1   |
| 1.2 Problem Statement .....      | 2   |
| 1.3 Methodology .....            | 2   |
| 1.4 Objectives .....             | 2   |
| 1.5 Layout .....                 | 3   |

## **CHAPTER TWO: THEORETICAL BACKGROUND**

|  |    |
|--|----|
| 2.1 Introduction .....                   | 5  |
| 2.2 Control Surface Actuator .....       | 6  |
| 2.3 PID Controller .....                 | 9  |
| 2.3.1 Ziegler- Nichols criteria .....    | 11 |
| 2.4 Root Locus Technique .....           | 12 |
| 2.5 Instrument Landing System .....      | 14 |
| 2.6 The Displacement Autopilot .....     | 18 |
| 2.6.1 Pitch displacement autopilot ..... | 19 |
| 2.6.2 Roll attitude autopilot .....      | 20 |
| 2.6.3 Altitude hold control system ..... | 20 |

|   |    |
|---|----|
| 2.6.4 Velocity hold control .....                 | 23 |
| 2.7 Fuzzy Logic And Fuzzy Controller .....        | 24 |
| 2.8 The Fuzzy Logic Methodology .....             | 26 |
| 2.8.1 The fuzzification .....                     | 26 |
| 2.8.2 The fuzzy Inference .....                   | 26 |
| 2.8.3 The defuzzification .....                   | 27 |
| 2.9 Decoupled Fuzzy Control Design .....          | 28 |
| 2.9.1 PID like fuzzy controller .....             | 28 |
| 2.9.2 Fuzzy PD+I controller .....                 | 29 |
| 2.9.3 Fuzzy inference system (FIS) editor .....   | 30 |
| 2.10 Fully Automatic Control Landing System ..... | 31 |
| 2.11 Glide Slope Coupler Control .....            | 33 |

## **CHAPTER THREE: CONTROL SYSTEM DESIGN**

|  |    |
|--|----|
| 3.1 Introduction .....                               | 36 |
| 3.2 Cross-Coupling .....                             | 36 |
| 3.4 Conventional Design .....                        | 37 |
| 3.4.1 Decoupling design .....                        | 37 |
| 3.4.1.1 Pitch displacement autopilot design .....    | 37 |
| 3.4.1.2 roll attitude autopilot .....                | 43 |
| 3.4.1.3 Altitude hold control system .....           | 45 |
| 3.4.1.4 Velocity hold control .....                  | 48 |
| 3.5 Decoupled Design Using Fuzzy Logic Control ..... | 50 |
| 3.5.1 pitch displacement autopilot design .....      | 50 |
| 3.5.2 roll attitude autopilot .....                  | 54 |

|   |    |
|---|----|
| 3.5.3 Altitude hold control system .....              | 56 |
| 3.5.4 Velocity control system using fuzzy logic ..... | 58 |
| 3.6 Coupled Design .....                              | 59 |
| 3.6.1 Conventional design .....                       | 59 |
| 3.6.1.1 Glide slope control system .....              | 59 |
| 3.6.2 Coupled fuzzy control design .....              | 63 |

## **CHAPTER FOUR:SIMULATION, RESULTS AND DISCUSSIONS**

|   |    |
|---|----|
| 4.1 Decoupled Conventional Design: .....              | 65 |
| 4.1.1 pitch displacement autopilot .....              | 65 |
| 4.1.2 roll attitude autopilot .....                   | 67 |
| 4.1.3 Altitude hold control system .....              | 68 |
| 4.1.4 Velocity hold control .....                     | 70 |
| 4.2 Decoupled Fuzzy Logic Design .....                | 71 |
| 4.2.1 pitch displacement autopilot .....              | 71 |
| 4.2.2 roll attitude autopilot using fuzzy logic ..... | 73 |
| 4.2.3 Altitude hold control .....                     | 74 |
| 4.2.4 Velocity hold control system .....              | 75 |
| 4.3 Conventional Coupled Design .....                 | 76 |
| 4.4 Coupled Design Using Fuzzy Logic Control .....    | 78 |
| 4.5 Comparisons And Discussions .....                 | 79 |
| 4.5.1 Comparisons .....                               | 79 |
| 4.5.2 Discussions .....                               | 84 |

## **CHAPTER FIVE: CONCLUSION AND RECOMMENDATIONS**

|                      |    |
|----------------------|----|
| 5.1 CONCLUSION ..... | 85 |
|----------------------|----|

|                                  |           |
|----------------------------------|-----------|
| <b>5.2 RECOMMENDATIONS .....</b> | <b>87</b> |
| <b>REFERENCES .....</b>          | <b>88</b> |

## TABLE OF SYMBOLS:

|                           |   |
|---------------------------|---|
| $\theta$                  | Pitch angle , Motor shaft angle.                                |
| $\theta_c$                | Pitch command angle.  |
| $T_m$                     | Motor Torque.   |
| $K_m$                     | Motor Gain.   |
| $I$                       | Motor current.  |
| $B_m$                     | Constant of reverse E.M.F                                       |
| $\delta$                  | Control surface deflection angle.                               |
| $\delta_e$                | Elevator angle deflection.                                      |
| $\zeta$                   | Damping ratio.  |
| $\omega_n$                | Undamped natural frequency.                                     |
| $K_a$                     | Elevator servo gain.  |
| $v$                       | Input voltage.  |
| $\tau_m$                  | Motor time constant.  |
| $\emptyset$               | Bank angle or wing level attitude.                              |
| $\emptyset_c$             | Bank angle command.   |
| $K_{rg}$                  | Rate gyro gain.   |
| $h$                       | Height of airplane.   |
| $\Delta h$                | Rate of climb.  |
| $u_\circ$                 | Reference flight speed.   |
| $\delta_r$                | Rudder angle.   |
| $q$                       | Pitch rate.   |
| $A_q, B_q$                | Matrix of pitch rate.   |
| $M_\alpha, M_q, M_\delta$ | The parameters of constrained pitching angle.                   |
| $\Gamma$                  | The difference between the actual and desired glide path angle. |

|          |  |
|----------|--|
| $\alpha$ | Angle of attack.   |
| $\gamma$ | Flight path angle.   |
| D        | Normal distance of the airplane above or below the desired glide path. |
| R        | The radial distance of the airplane from the glide path.               |
| $K_P$    | Gain in proportional path.   |
| $K_D$    | Gain in derivative path.   |
| $K_I$    | Gain in integral path.   |
| $G_u$    | Fuzzy controller scaling gain.   |

**List of ABBREVIATION:**

|     |                                  |
|-----|----------------------------------|
| FCS | Flight Control System            |
| FIS | Fuzzy Inference System           |
| GA  | General Aviation                 |
| ILS | Instrument Landing System        |
| PID | Proportional-Integral-Derivative |