



HAL
open science

Optimal design of a vibro-impact electro-mechanical system with uncertainties

Roberta Lima, Christian Soize, Rubens Sampaio

► **To cite this version:**

Roberta Lima, Christian Soize, Rubens Sampaio. Optimal design of a vibro-impact electro-mechanical system with uncertainties. 17th International Symposium on Dynamic Problems of Mechanics (DINAME 2015), ABCM, Feb 2015, Natal, Rio Grande do Norte, Brazil. pp.1-6. hal-01158255

HAL Id: hal-01158255

<https://hal.science/hal-01158255>

Submitted on 30 May 2015

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L'archive ouverte pluridisciplinaire **HAL**, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d'enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.

Optimal design of a vibro-impact electro-mechanical system with uncertainties

Roberta Lima^{1,2}, Christian Soize¹, and Rubens Sampaio²

¹ Université Paris-Est, Laboratoire Modélisation et Simulation Multi Echelle, MSME UMR 8208 CNRS, 5 bd Descartes, 77454 Marne-la-Vallée, France

² Pontifícia Universidade Católica do Rio de Janeiro, Avenida Marquês de São Vicente, 255, Gávea, Rio de Janeiro, Brasil

Abstract: In this paper, the robust design with an uncertain model of a vibro-impact electromechanical system is done. The electromechanical system is composed of a cart, whose motion is excited by a DC motor (motor with continuous current), and an embarked hammer into this cart. The hammer is connected to the cart by a nonlinear spring component and by a linear damper, so that a relative motion exists between them. A linear flexible barrier, placed outside of the cart, constrains the hammer movements. Due to the relative movement between the hammer and the barrier, impacts can occur between these two elements. Some system parameters are uncertain, such as the stiffness and the damping coefficients of the flexible barrier. The objective of the paper is to perform an optimization of this electromechanical system with respect to design parameters (spring component, and barrier gap) in order to maximize the impact power under the constraint that the electric power consumed by the DC motor is lower than a maximum value. This optimization is formulated and solved in the framework of robust design due to the presence of uncertainties in the model.

Keywords: electro-mechanical systems, vibro-impact, robust design, nonlinear dynamics.

NOMENCLATURE

ν = source voltage, V	Δ = eccentricity of the pin, m	c_{int} = friction coefficient between the cart and the hammer, Ns/m
c = electric current, A	m_c = cart mass, Kg	ζ_{int} = damping ratio of friction between the cart and the hammer, dimensionless
$\dot{\alpha}$ = angular speed of the motor, rad/s	m_h = hammer mass, Kg	k_i = barrier stiffness, N/m
l = electric inductance, H	h = hammer displacement, m	c_i = barrier damping coefficient, Ns/m
j_m = inertia moment, Kg m ²	k_{h1} = linear hammer stiffness, N/m	g = gap barrier, m
b_m = damping ratio in the transmission of the torque, Nm/(rad/s)	k_{h3} = cubic hammer stiffness, N/m ²	π_{imp} = sum of the averages of the impact power, W
k_e = constant of the motor electromagnetic force, (rad/s) /V	c_{pin} = friction coefficient between the pin and the slot, Ns/m	π_{elec} = average of the electric power, W
r = electrical resistance, Ω	c_{ext} = friction coefficient between the cart and the rail, Ns/m	

INTRODUCTION

The design of electro-mechanical systems is of a great interest in many areas. Many works have been done in this topic, as Zhankui and Sun (2013), Sadeghian and Rezazadeh (2009) and Lee, Cho and Chang(2006), trying to characterize the mutual interaction between electrical and mechanical parts. This interaction leads us to analyze very interesting nonlinear dynamical systems (see for instance Cartmell (1990)), in which the nonlinearities vary with the coupling conditions, and also affects the two most important variables used to evaluate the performance of electro-mechanical systems, related to the power consumed by the electrical part, and the power used into the movement of the mechanical part. As the mutual interaction between electrical and mechanical parts affects the two powers used to evaluate the system performance, the coupling effects must be analyzed in the design optimization problem for electro-mechanical systems.

The present work deals with the robust design optimization of a vibro-impact electric-mechanical system in order to improve its performance. The electrical part of the system is a DC motor, and the mechanical part is a vibro-impact system. It should be noted that, in Lima and Sampaio (2012), the equations and the numerical integration were presented for a similar electric-mechanical system for which the embarked mass was replaced by a pendulum and for which there was no impact. This first work has allowed the electro-mechanical coupling to be analyzed as a function of the mass of the mechanical system.

The analysis of vibro-impact systems is not a new subject, and is frequently encountered in technical applications of mechanisms. The interest of analyzing the optimization of their performance is reflected by the increasing amount of research in this area (see for instance Luo et al (2008), Ostasevicius, Gaidys and Dauksevicius (2009), Yue, Xu and Wang (2013)), and also the book Ibrahim (2009), which is completely devoted to this problem).

The objective of the paper is to perform an optimization of this electro-mechanical system with respect to design pa-

rameters. The optimization consists in maximizing the impact power under the constraint that the electric power consumed by the DC motor is lower than a maximum value. This optimization is formulated in the framework of robust design due to the presence of uncertainties in the computational nonlinear dynamics model of the electro-mechanical system.

This paper is organized as follows. In Section 1, the elements (motor, cart, hammer, and barrier) of the electro-mechanical system are presented and the initial value problem is formulated for the vibro-impact electro-mechanical system. In Section 2, we define the variables of interest for the design optimization. The construction of the probabilistic models of the uncertain parameters, and the formulation of the robust design optimization problem are given in Section 3. The robust design optimization consists in finding the optimal design point using the computational model in presence of uncertainties. The numerical results of the robust design optimization problem are presented in Section 4.

1 DYNAMIC OF THE COUPLED SYTEM

1.1 Electrical component: DC motor

The modeling of DC motors is based on the Kirchhoff law (see Karnopp (2006)), which is written as

$$\begin{aligned} l \dot{c}(t) + r c(t) + k_e \dot{\alpha}(t) &= \nu, \\ j_m \ddot{\alpha}(t) + b_m \dot{\alpha}(t) - k_e c(t) &= -\tau(t), \end{aligned} \quad (1)$$

where t is time, ν is the source voltage, c is the electric current, $\dot{\alpha}$ is the angular speed of the motor, l is the electric inductance, j_m is the inertia moment of the motor, b_m is the damping ratio in the transmission of the torque generated by the motor to drive the coupled mechanical system, k_e is the constant of the motor electromagnetic force, and r is the electrical resistance. Figure 1 shows a sketch of the DC motor. The available torque delivered to the mechanical component, in the z -direction, is represented by τ (see Fig. 1).

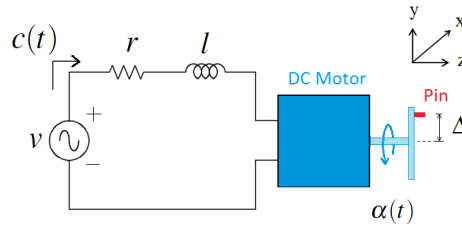


Figure 1 – Sketch of the DC motor.

1.2 Mechanical component: cart and hammer

As described in the introduction, the mechanical component is composed by a cart whose movement is driven by the DC motor, and by a hammer that is embarked into the cart. The motor is coupled to the cart through a pin that slides into a slot machined in an acrylic plate that is attached to the cart, as shown in Fig. 2. The off-center pin is fixed on the disc at distance Δ of the motor shaft, so that the motor rotational motion is transformed into a cart horizontal movement. To model the coupling between the motor and the mechanical system, the motor shaft is assumed to be rigid. Thus, the

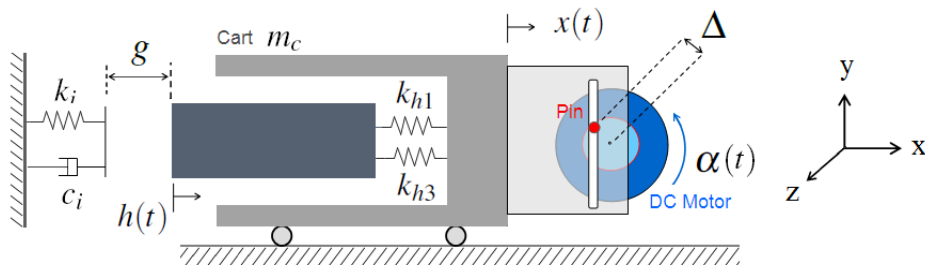


Figure 2 – Vibro-impact electro-mechanical system. The nonlinear component spring is drawn as a linear spring with constant k_{h1} and a nonlinear cubic spring with constant k_{h3} .

available torque vector to the coupled mechanical system, τ , can be written as

$$\tau(t) = \Delta(t) \times \mathbf{f}(t), \quad (2)$$

where $\Delta = (\Delta \cos \alpha(t), \Delta \sin \alpha(t), 0)$ is the vector related to the eccentricity of the pin, and where \mathbf{f} is the coupling force between the DC motor and the cart. Assuming that there is a viscous friction between the pin and the slot, the vector \mathbf{f} has two components: the horizontal force that the DC motor exerts in the cart, f_x , and the vertical force, f_y , induced by the viscous friction. The available torque τ and vertical force f_y are written as

$$\tau(t) = f_y(t) \Delta \cos \alpha(t) - f_x(t) \Delta \sin \alpha(t), \quad (3)$$

$$f_y(t) = c_{pin} \Delta \dot{\alpha}(t) \cos \alpha(t), \quad (4)$$

where c_{pin} is defined in Fig. 2. The embarked hammer is modeled as a rigid body of mass m_h and its relative displacement is h with respect to the cart. In the adopted model, the constitutive equation of the spring component between the hammer and the cart is written as $f_s(t) = k_{h1} h(t) + k_{h3} h(t)^3$. The rate of nonlinearity of the hammer stiffness is defined as $r_h = k_{h3}/k_{h1}$. The horizontal cart displacement is represented by x . Due to constraints, the cart is not allowed to move in the vertical direction. The spring-damper element modeling the medium on which the impacts occur, is constituted of a linear spring with stiffness coefficient k_i and a damper with damping coefficient c_i . The equations of the mechanical component are

$$\ddot{x}(t) (m_c + m_h) + \ddot{h}(t) m_h + c_{ext} \dot{x}(t) = -f_{imp}(t) + f_x(t), \quad (5)$$

$$\ddot{x}(t) m_h + \ddot{h}(t) m_h + c_{int} \dot{h} + k_{h1} h(t) + k_{h3} h^3(t) = -f_{imp}(t), \quad (6)$$

where, c_{ext} is the viscous friction coefficient between the cart and the rail and $c_{int} = 2\zeta_{int}\sqrt{m_h k_{h1}}$ is the viscous friction coefficient between the cart and the hammer (ζ_{int} is the damping ratio), and where f_{imp} is the impact force between the hammer and the barrier, which is written as

$$f_{imp}(t) = -\phi(t) \left(k_i (x(t) + h(t) + g) + c_i (\dot{x}(t) + \dot{h}(t)) \right), \quad (7)$$

where

$$\phi(t) = \begin{cases} 1, & \text{if } x(t) + h(t) + g < 0 \text{ and } \dot{h}(t) + \dot{x}(t) < 0, \\ 0, & \text{in all other cases,} \end{cases} \quad (8)$$

in which g is defined as the horizontal distance from the hammer (when $\alpha = \pi/2$ rad) to the equilibrium position of the barrier. In the model defined by Eq. (8), an impact starts when $x(t) + h(t)$ is negative and equal to $-g$ and, $\dot{h}(t) - \dot{x}(t) < 0$. During an impact, the action of the barrier on the hammer stops as soon as the total velocity $\dot{h}(t) + \dot{x}(t)$ becomes positive (the return of the hammer).

1.3 Coupled vibro-impact electro-mechanical system

Due to the system geometry, we have the following constraint

$$x(t) = \Delta \cos(\alpha(t)). \quad (9)$$

Substituting Eqs. (3) to (9) into Eq. (1), we obtain the initial value problem for the vibro-impact electro-mechanical system that is written as follows. Given a constant source voltage ν , find (α, c, h) such that, for all $t > 0$,

$$l\dot{c}(t) + rc(t) + k_e \dot{\alpha} = \nu, \quad (10)$$

$$\begin{aligned} & \ddot{\alpha}(t) \left[j_m + (m_c + m_h) \Delta^2 \sin^2(\alpha(t)) \right] - \ddot{h}(t) [m_h \Delta \sin(\alpha(t))] - k_e c(t) \\ & + \dot{\alpha}(t) \left[b_m + \dot{\alpha}(t) (m_c + m_h) \Delta^2 \cos(\alpha(t)) \sin(\alpha(t)) + c_{pin} \Delta^2 \cos^2(\alpha(t)) - c_{ext} \Delta^2 \sin^2(\alpha(t)) \right] \\ & = \phi \left(k_i (\Delta \cos(\alpha(t)) + h + g) + c_i (-\Delta \dot{\alpha}(t) \sin(\alpha(t)) + \dot{h}(t)) \right) \Delta \sin(\alpha(t)), \end{aligned} \quad (11)$$

$$\begin{aligned} & \ddot{h}(t) m_h - \ddot{\alpha}(t) [m_h \Delta \sin(\alpha(t))] - \dot{\alpha}(t) [m_h \Delta \dot{\alpha}(t) \cos(\alpha(t))] + \dot{h}(t) c_{int} + k_{h1} h(t) + k_{h3} h^3(t) \\ & = \phi(t) \left(k_i (\Delta \cos(\alpha(t)) + h + g) + c_i (-\Delta \dot{\alpha}(t) \sin(\alpha(t)) + \dot{h}(t)) \right), \end{aligned} \quad (12)$$

$$\text{where } \phi(t) = \begin{cases} 1, & \text{if } \Delta \cos \alpha(t) + h(t) + g < 0 \text{ and } \dot{h}(t) - \Delta \dot{\alpha}(t) \cos(\alpha(t)) < 0 \\ 0, & \text{in all other cases,} \end{cases} \quad (13)$$

with the initial conditions, $\alpha(0) = 0$, $c(0) = \nu/r$, and $h(0) = 0$.

2 POWERS OF THE SYSTEM

The average of the electric power consumed in an interval $[0, T]$ is written as

$$\pi_{\text{elec}} = \frac{1}{T} \int_0^T \nu c(t) dt. \quad (14)$$

Let t_b^j and t_e^j be the instants of begin and end of the j -th impact, such that for all t belonging to $[t_b^j, t_e^j]$, we have $\dot{x}(t) + \dot{h}(t) < 0$. At time t , the impact power, $\pi_{\text{imp}}^j(t)$, is then written as

$$\pi_{\text{imp}}^j(t) = k_i (x(t) + h(t)) (\dot{x}(t) + \dot{h}(t)), \quad t_b^j \leq t \leq t_e^j. \quad (15)$$

The time average of the impact power during the j -th impact, $\bar{\pi}_{\text{imp}}^j$, is written as

$$\bar{\pi}_{\text{imp}}^j = \frac{1}{t_e^j - t_b^j} \int_{t_b^j}^{t_e^j} \pi_{\text{imp}}^j(t) dt. \quad (16)$$

Let N_{imp} be the total number of impacts that occur during time interval $[0, T]$. The sum of the averages of the impact power is

$$\pi_{\text{imp}} = \sum_{j=1}^{N_{\text{imp}}} \bar{\pi}_{\text{imp}}^j. \quad (17)$$

The variables π_{imp} and π_{elec} are considered for measuring the system performance. More π_{imp} is large and smaller is π_{elec} , better will be the system performance.

3 ROBUST DESIGN OPTIMIZATION PROBLEM

The three parameters that are assumed to be uncertain are kh_1 , k_i and c_i , which are modeled by the independent random variables K_{h1} , K_i and C_i . The probability distribution of each one is constructed using the maximum entropy principle. In order to formulate the robust design problem, the set of all the system parameters are divided into three subsets. The first one is the family of the fixed parameters that are represented by the vector $\mathbf{p}_{\text{fix}} = \{ \nu, l, r, j_m, k_e, b_m, c_{pin}, c_{ext}, s_{int}, r_h, m_c, m_h, \Delta \}$. The second one is the family of the design parameters that are represented by the vector $\mathbf{p}_{\text{des}} = \{ \underline{K}_{h1}/m_h, g \}$. The third one is the family of the uncertain parameters that are represented by the random vector $\mathbf{P}_{\text{unc}} = \{ K_i, C_i, K_{h1} \}$. Since \mathbf{P}_{unc} is a random vector, the outputs of the electro-mechanical system are stochastic processes, and consequently, $\pi_{\text{imp}}(\mathbf{p}_{\text{des}}, \mathbf{P}_{\text{unc}})$ and $\pi_{\text{elec}}(\mathbf{p}_{\text{des}}, \mathbf{P}_{\text{unc}})$, become random variables $\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}) = \pi_{\text{imp}}(\mathbf{p}_{\text{des}}, \mathbf{P}_{\text{unc}})$ and $\Pi_{\text{elec}}(\mathbf{p}_{\text{des}}) = \pi_{\text{elec}}(\mathbf{p}_{\text{des}}, \mathbf{P}_{\text{unc}})$. The cost function of the robust design optimization problem is defined by

$$J(\mathbf{p}_{\text{des}}) = E\{\Pi_{\text{imp}}(\mathbf{p}_{\text{des}})\}. \quad (18)$$

The robust design optimization problem is written as

$$\mathbf{p}_{\text{des}}^{\text{opt}} = \arg \max_{\mathbf{p}_{\text{des}} \in C_{ad}} J(\mathbf{p}_{\text{des}}), \quad (19)$$

in which $C_{ad} = \{ \mathbf{p}_{\text{des}} \in \mathcal{P}_{\text{des}}; E\{\Pi_{\text{elec}}(\mathbf{p}_{\text{des}})\} \leq c_{\text{elec}} \}$, where \mathcal{P}_{des} is the admissible set of the values of \mathbf{p}_{des} , and where c_{elec} is an upper bound.

4 RESULTS OF THE ROBUST OPTIMIZATION PROBLEM

The hyperparameters δ_{K_i} , δ_{C_i} and $\delta_{k_{h1}}$, which control the level of uncertainties for K_i , C_i and K_{h1} are fixed to 0.1. The optimization problem is also considered without uncertainties in the systems parameters, that is, the deterministic case ($\delta_{K_{h1}} = \delta_{K_i} = \delta_{C_i} = 0$). For $\mathbf{p}_{\text{des}} \in C_{ad}$, the cost function is estimated by the Monte Carlo simulation method using 100 independent realizations of random vector \mathbf{P}_{unc} following its probability distribution. The optimization problem (defined by Eq. (19)) is solved using the trial method for which the admissible set C_{ad} is meshed as follows: for \underline{K}_{h1}/m_h , 13 values are non-uniformly selected in the interval $[703, 3, 830]$, and for g , 20 nonuniform values in $[0, 0.038]$. For computation, the initial value problem defined by Eqs. (10) to (13) has been rewritten in a dimensionless form. Duration is chosen as $T = 10.0$ s. The 4th-order Runge-Kutta method is used for the time integration scheme for which we have implemented a varying time-step. The time-step is adapted to the state of the dynamical system according to the occurrence or the not occurrence of impacts. When the hammer is not impacting the barrier, the time step used is 10^{-4} s, but when the hammer is approaching the barrier and when it is impacting it, the time step is chosen as the value 10^{-5} s. The values used for the motor parameters, were obtained from the specifications of the motor Maxon DC brushless number 411, 678. The others elements of \mathbf{p}_{fix} are: $\nu = 2.4$ V, $m_c = 0.30$ Kg, $m_h = 0.50$ Kg, $r_h = 0.30$ 1/m², $c_{pin} = c_{ext} = 5.00$ Ns/m, $s_{int} = 0.05$, and $\Delta = 0.01$ m. Upper bound c_{elec} is 6.00 W. For the deterministic case, the components of the optimal solution $\mathbf{p}_{\text{des}}^{\text{opt}}$

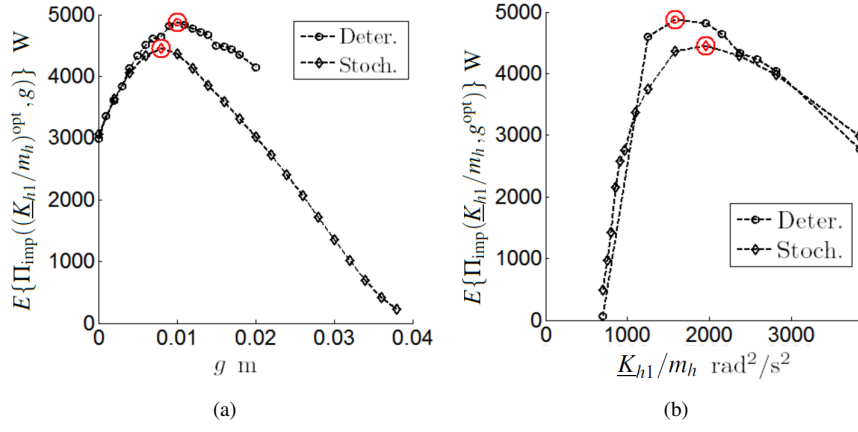


Figure 3 – (a) Cost function as function of g with $(\underline{K}_{h1}/m_h)^{\text{opt}}$. (b) Cost function as function of \underline{K}_{h1}/m_h with g^{opt} . In both graphs, the $E\{\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}^{\text{opt}})\}$ is highlighted for the deterministic and stochastic cases with markers .

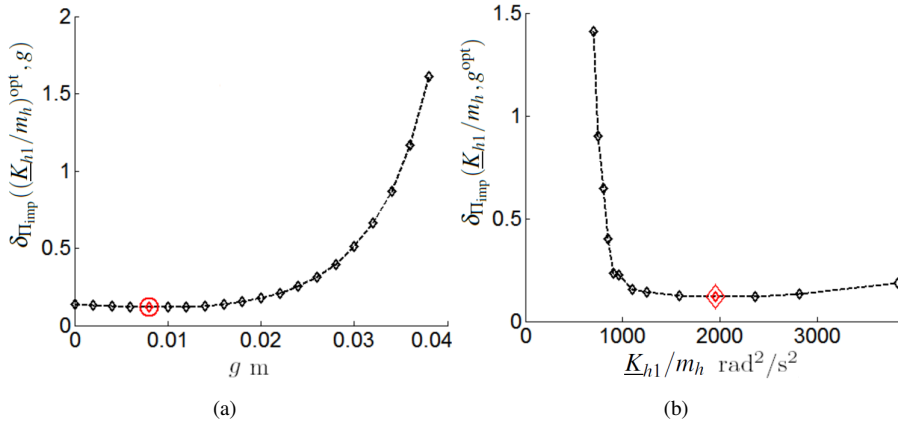


Figure 4 – (a) Coefficient variation of Π_{imp} as function of g with $(\underline{K}_{h1}/m_h)^{\text{opt}}$ (b) Coefficient variation of Π_{imp} as function of \underline{K}_{h1}/m_h with g^{opt} . In both graphs, the $\delta_{\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}^{\text{opt}})}$ is highlighted with markers.

are $(\underline{K}_{h1}/m_h)^{\text{opt}} = 1,580 \text{ rad}^2/\text{s}^2$ and $g^{\text{opt}} = 0.011 \text{ m}$. For case with uncertainties, it is $\underline{K}_{h1}/m_h = 1,950 \text{ rad}^2/\text{s}^2$ and $g = 0.008 \text{ m}$. The role played by uncertainties on the optimal values of the design parameters can be analyzed through Fig. 3, which display the graphs $g \mapsto E\{\Pi_{\text{imp}}((\underline{K}_{h1}/m_h)^{\text{opt}}, g)\}$, and $\underline{K}_{h1}/m_h \mapsto E\{\Pi_{\text{imp}}(\underline{K}_{h1}/m_h, g^{\text{opt}})\}$. The robustness of the optimal design point, $\mathbf{p}_{\text{des}}^{\text{opt}}$, can be analyzed in studying the evolution of the coefficient variation, $\delta_{\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}^{\text{opt}})}$, of random variable $\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}^{\text{opt}})$ as a function of the uncertainty level. However, in order to better analyze the sensitivity of the responses with respect to the uncertainty level, we have constructed Fig. 4 that displays the graphs $g \mapsto \delta_{\Pi_{\text{imp}}((\underline{K}_{h1}/m_h)^{\text{opt}}, g)}$ and $\underline{K}_{h1}/m_h \mapsto \delta_{\Pi_{\text{imp}}(\underline{K}_{h1}/m_h, g^{\text{opt}})}$. It can be seen that the value $\delta_{\Pi_{\text{imp}}(\mathbf{p}_{\text{des}}^{\text{opt}})}$ occurs in a region for which the two following functions $g \mapsto \delta_{\Pi_{\text{imp}}((\underline{K}_{h1}/m_h)^{\text{opt}}, g)}$ and $\underline{K}_{h1}/m_h \mapsto \delta_{\Pi_{\text{imp}}(\underline{K}_{h1}/m_h, g^{\text{opt}})}$ are minima. This means the optimal design point is robust with respect to uncertainties.

5 CONCLUSIONS

In this paper, the formulation and the solution of a robust design optimization problem have been presented for a nonlinear vibro-impact electro-mechanical system in presence of uncertainties in the computational model. Since this nonlinear electro-mechanical system is devoted to the vibro-impact optimization, the time responses exhibit numerous shocks that have to be identified with accuracy, and consequently, a very small time step is required. We have thus chosen an explicit time-integration scheme and not an implicit one. Nevertheless, due to the presence of low-frequency contributions in the time responses, a long time duration is required, which will imply a huge number of integration time step if the time step were chosen constant. This is the reason why we have implemented an adaptive integration time step. It was one of the difficulties encountered for the solver implementation. The design optimization problem of the dynamical system without uncertainties yields an optimal design point that differs from the nominal values, and which can not be determined, *a priori*, without solving the design optimization problem. In addition, the robust analysis that has been presented demonstrates the interest that there is to take into account the uncertainties in the computational model. The optimal design point that has been identified in the robust design framework significantly differs from design point

obtained with the computational model without uncertainties. For this electro-mechanical system, it has been seen that, the minimum value of the dispersion of the random output occurs in the region of the optimal design parameters, which means that the optimal design point is robust with respect to uncertainties.

ACKNOWLEDGMENTS

This work was supported by the Brazilian Agencies CNPQ, CAPES and FAPERJ.

REFERENCES

- Cartmell, M., 1990, *Introduction to Linear, Parametric and Nonlinear Vibrations*, Ed. Springer, 260 p.
- Ibrahim, R., 2009, *Vibro-Impact Dynamics: Modeling, Mapping and Applications*, Springer.
- Karnopp, D.; Margolis, D.; Rosenberg, R., 2006, *System Dynamics: Modeling and Simulation of Mechatronic Systems*, John Wiley and Sons, 4th edition, New-York, USA.
- Lee, H.; Incheon, I.; Cho, C.; Chang, S., 2006, Design and analysis of electromechanical characteristics of micromachined stainless steel pressure sensor, in: *Proc. of the 5th IEEE Sensors Conference, IEEE Sensors, IEEE, Daegu, South Korea*, pp. 659674.
- Lima, R.; Sampaio, R., 2012, Stochastic analysis of an electromechanical coupled system with embarked mass, *Mecânica Computacional XXXI*, pp. 27092733, <http://www.cimec.org.ar/ojs/index.php/mc/article/view/4216/4142>.
- Luo, G.; Zhang, Y.; Xie, J.; Zhang, J., 2008, Periodic-impact motions and bifurcations of vibro-impact systems near 1:4 strong resonance point, *Communications in Nonlinear Science and Numerical Simulation*, Vol. 13, pp. 10021014.
- Ostasevicius, V.; Gaidys, R.; Dauksevicius, R., 2009, Numerical analysis of dynamic effects of a nonlinear vibro-impact process for enhancing the reliability of contact-type mems devices, *Sensors Vol.9*, pp. 1020110216.
- Sadeghian, H.; Rezazadeh, G., 2009, Comparison of generalized differential quadrature and Galerkin methods for the analysis of micro-electro-mechanical coupled systems, *Communications in Nonlinear Science and Numerical Simulation*, Vol. 14, pp. 2807–2816.
- Yue, X.; Xu, W.; Wang, L., 2013, Global analysis of boundary and interior crises in an elastic impact oscillator, *Communications in Nonlinear Science and Numerical Simulation*, Vol. 18, pp. 35673574.
- Zhankui, S.; Sun, K., 2013, Nonlinear and chaos control of a micro-electro-mechanical system by using second-order fast terminal sliding mode control, *Communications in Nonlinear Science and Numerical Simulation*, Vol. 18, pp. 2540–2548.

RESPONSIBILITY NOTICE

The authors are the only responsible for the printed material included in this paper.