Recent Work at the Stanford Engineering Test Facility

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Special thanks to SUS, Calum, Janeen, Caroline, Justin, Tim

Various Activities

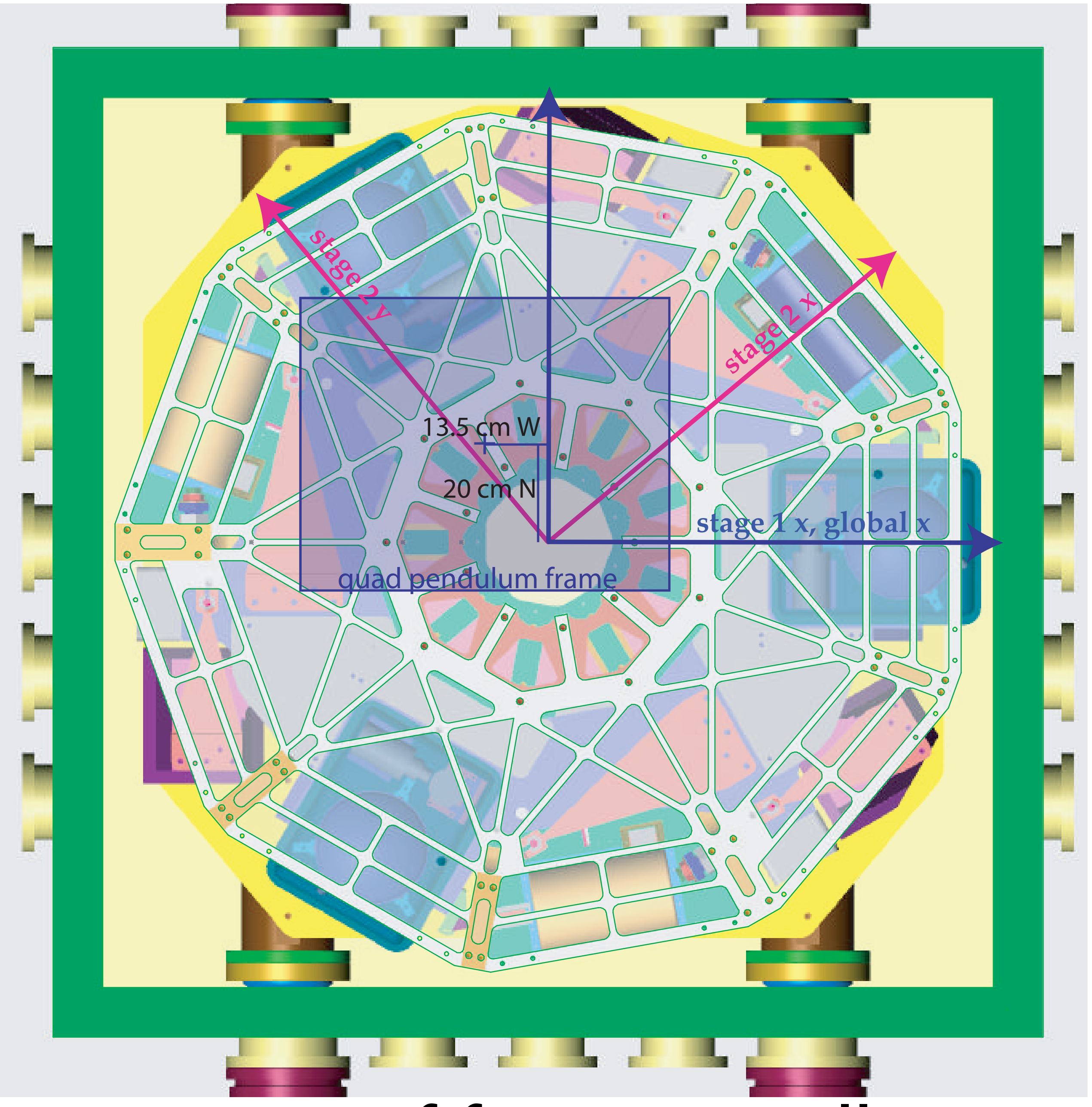
- Low noise GS-13, use a simple op-amp follower circuit
  - Noise is ~6e-12 m/rtHz at 1 Hz, 3e-13 m/rtHz at 10 Hz
- Matt DeGree working on “tickle testing”, automated check of all the sensors and actuators.
- William East measuring thermal behavior of actuators.
  - BSC is OK
  - Large DC offset, measure 32 mDeg of temp rise.
  - Scale to typical ETF operation, get 6e-4 degrees
  - Scale to BSC, softer springs, HEPI input motion: 2e-6 degrees
- Quad pendulum frame interactions (Brian and Tarm)

Quad Pendulum Frame

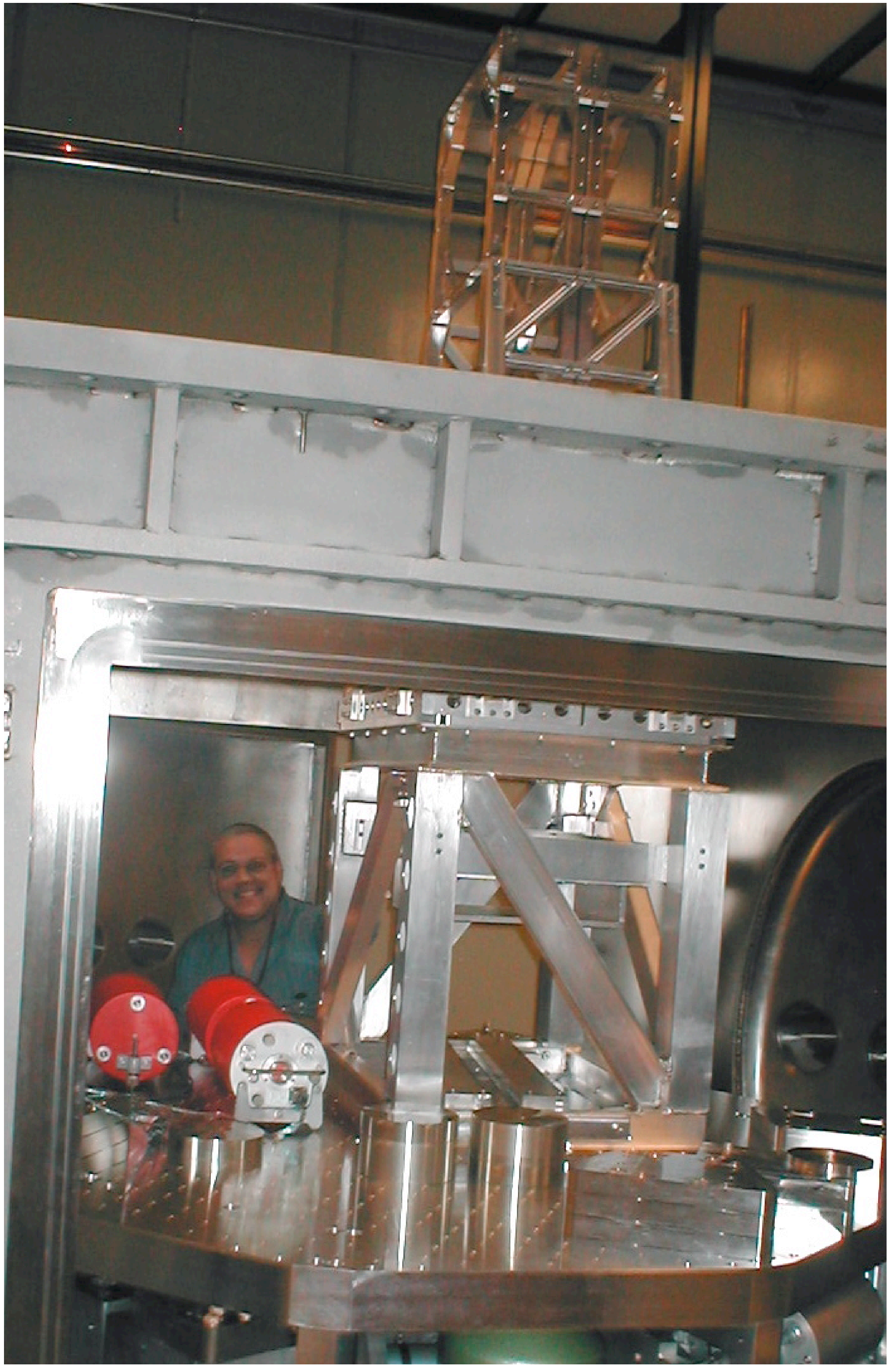
- Received a frame from Caltech
- Install on the Tech Demo
- Study the impact of frame resonances on the system
  - Not so great
- Try to improve the interaction
  - Electronic damping (OK)
  - Passive "Constrained Layer" damping (Great)

Installation

- installed 12/16/05
- Upside down



top view of frame installation

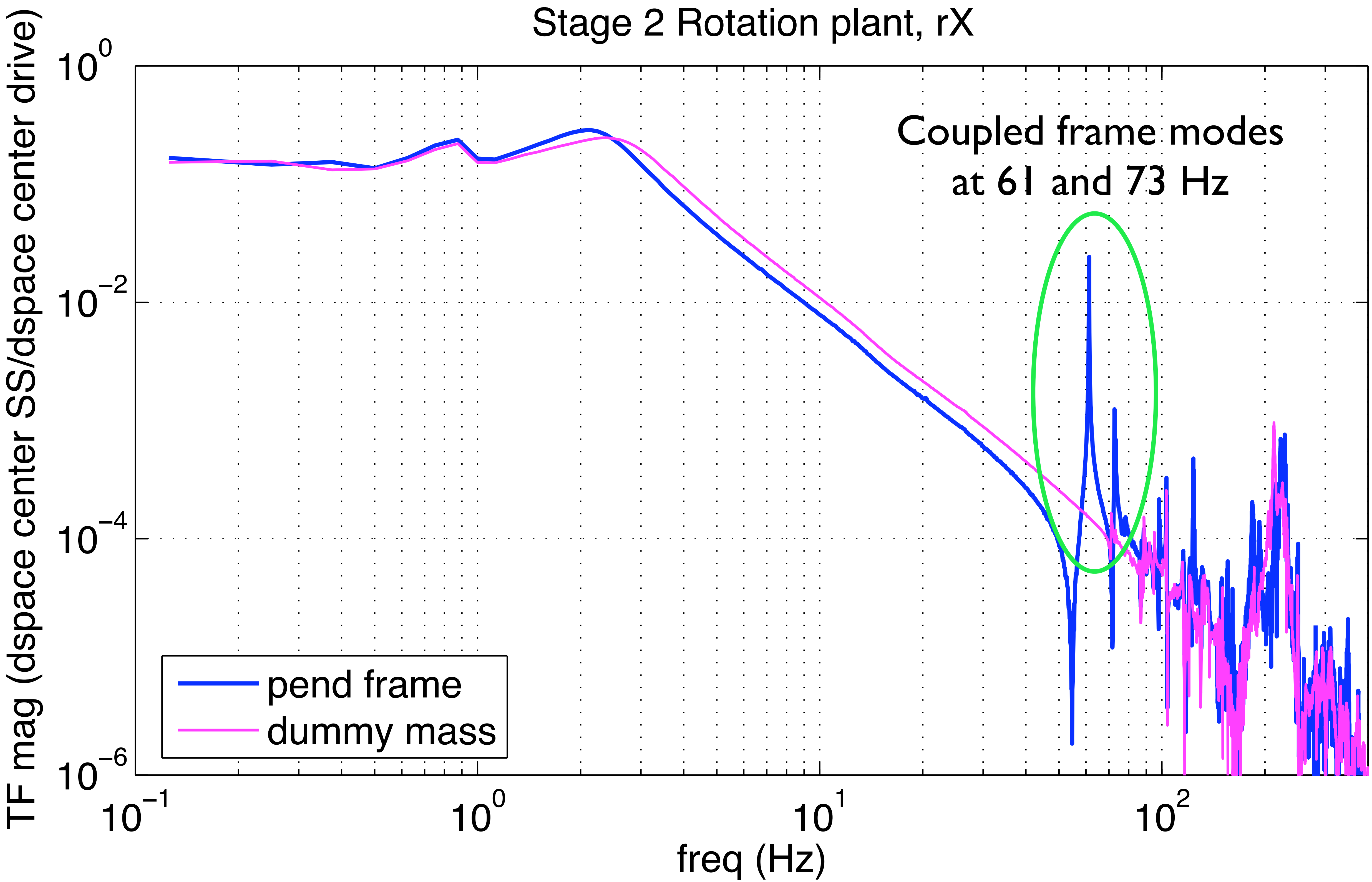


Interaction Performance Tests

- Goal: Try to understand the impact of the frame vibrations on the system performance.
- But: Testing in air makes performance measures difficult.
- So: Predict performance by:
  - Measuring mechanical transfer function of stage, and
  - Multiplying by calculated suppression of the isolation loop.

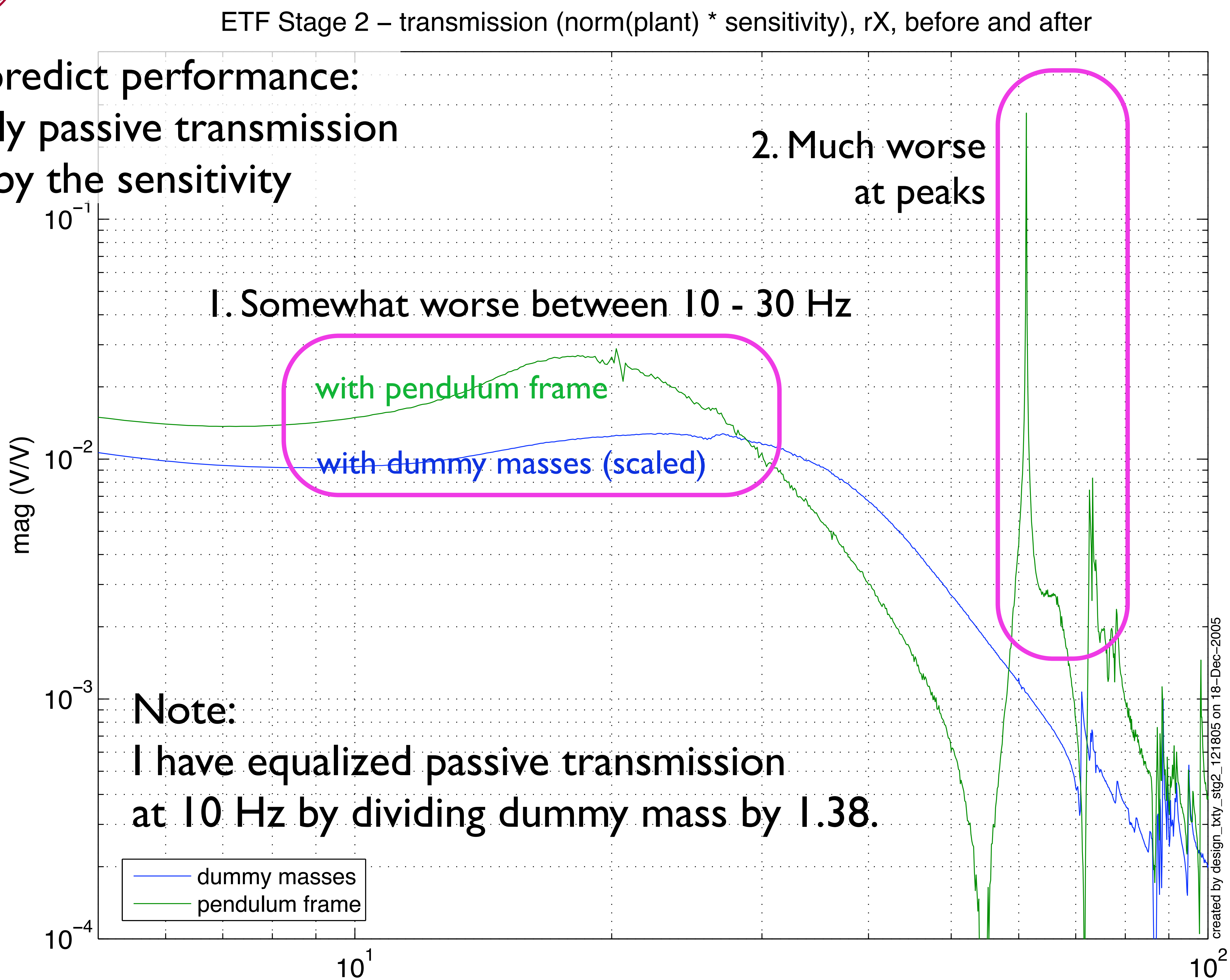
- We see that:
  - Mechanical transfer function is worse.
  - Control loop performance is worse.

Largest Coupling to rX & rY



Performance Impact of resonances

To predict performance:
multiply passive transmission
by the sensitivity



1. Somewhat worse between 10 - 30 Hz

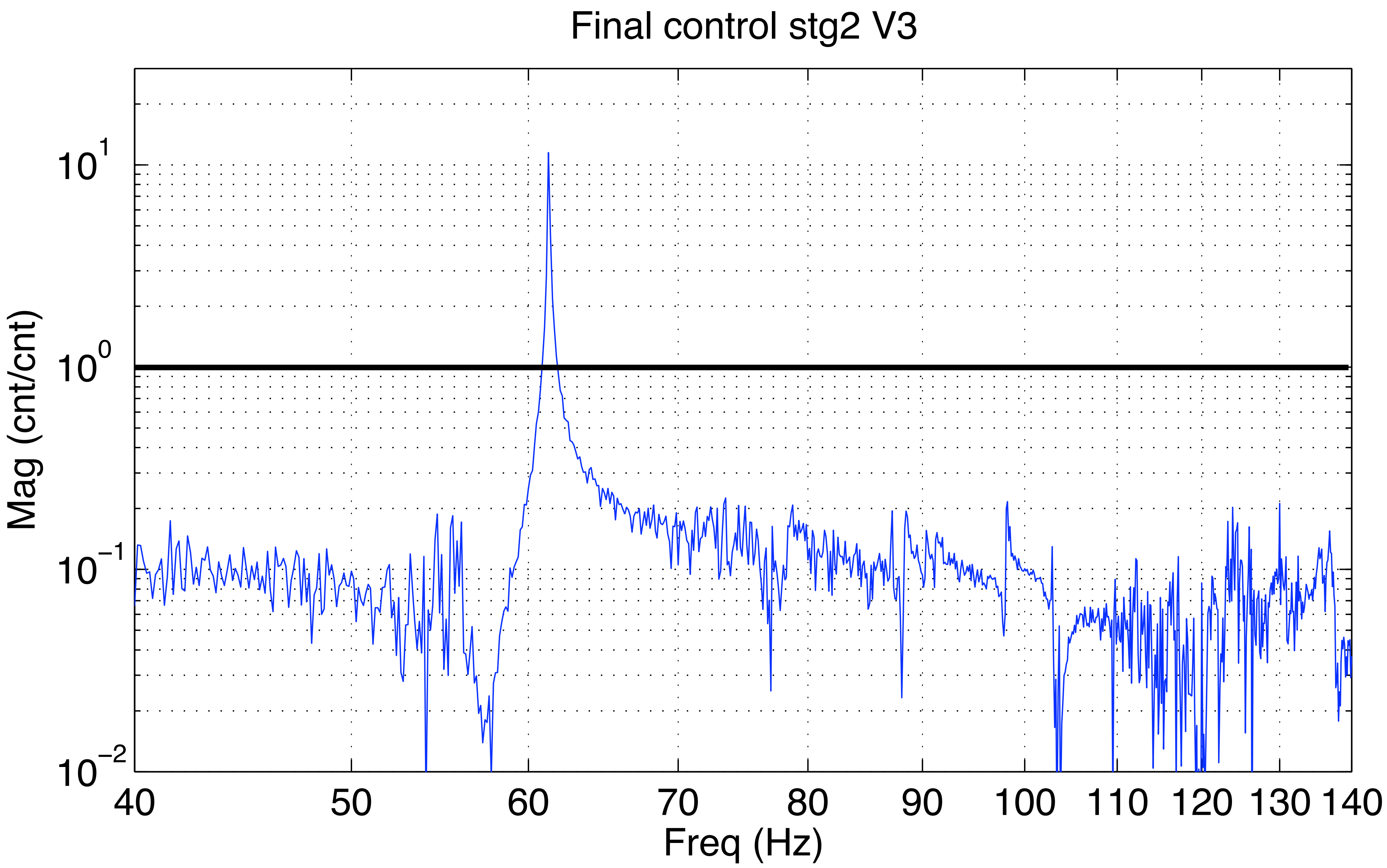
2. Much worse at peaks

Note:
I have equalized passive transmission at 10 Hz by dividing dummy mass by 1.38.

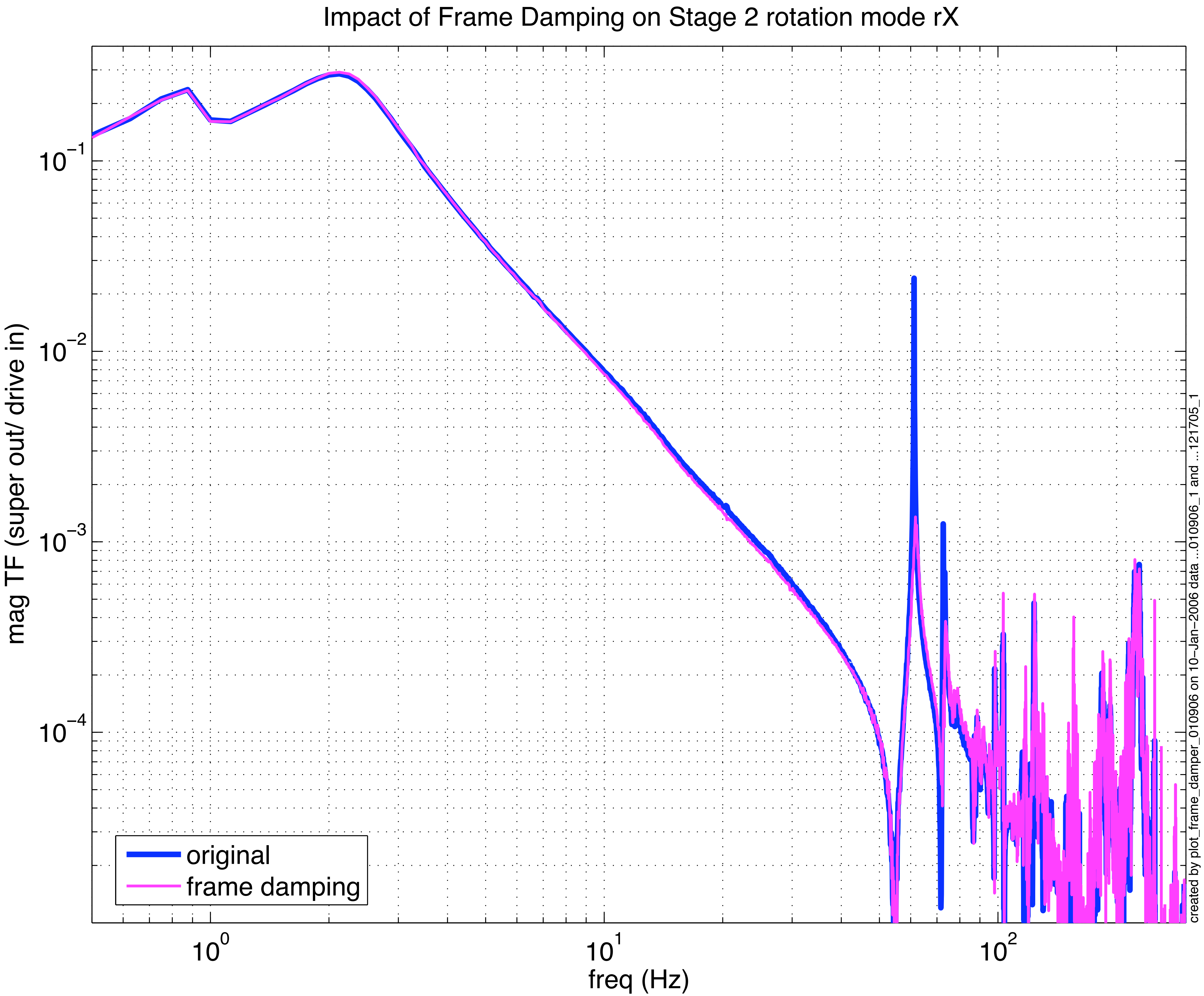
What to do?

- SUS - Working to increase the frequency of the modes
- Damp the modes:
  - Actively, using existing sensors, or using new sensors
  - Passively with constrained layer damping

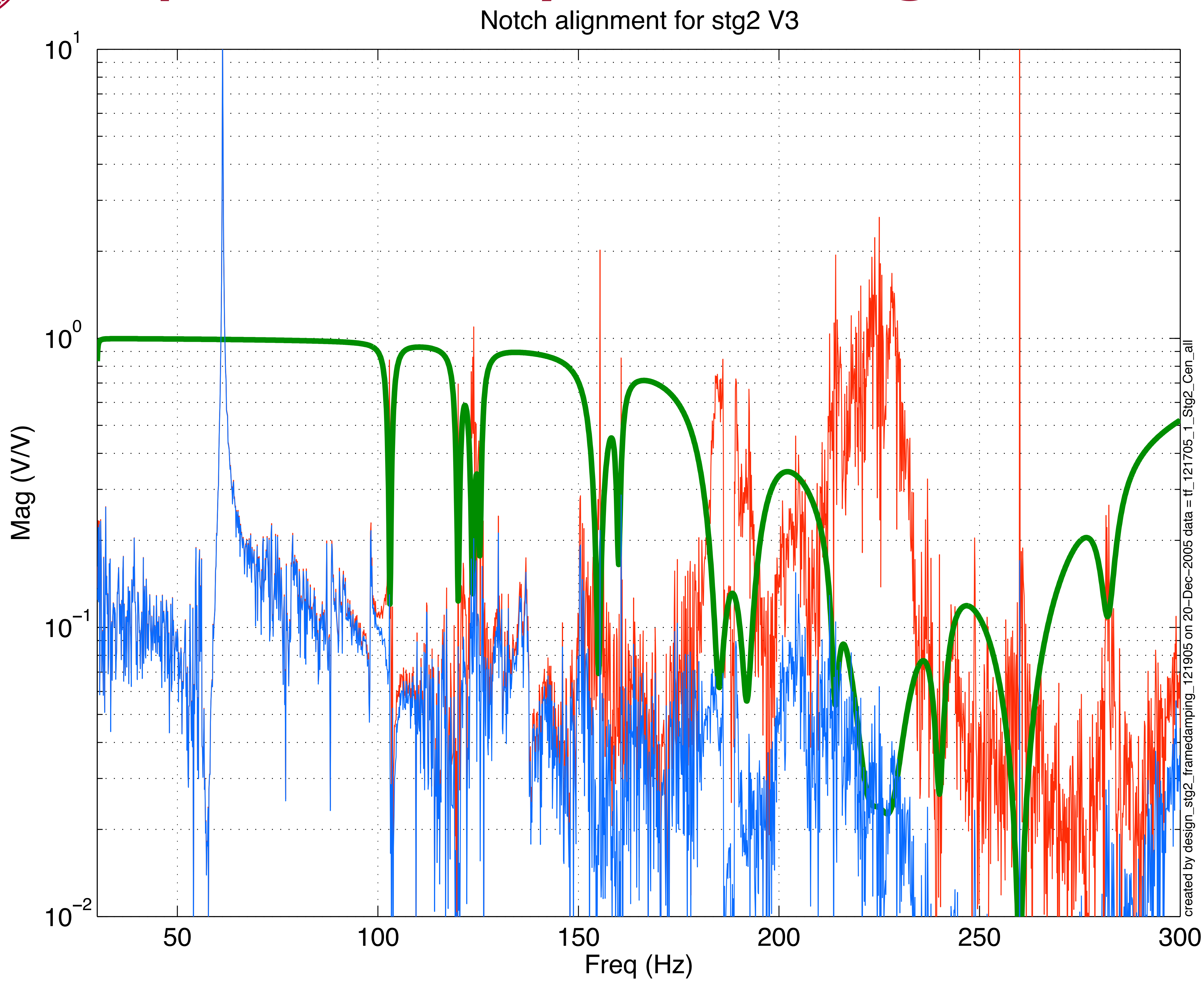
Active damping control loop



Result of active damping



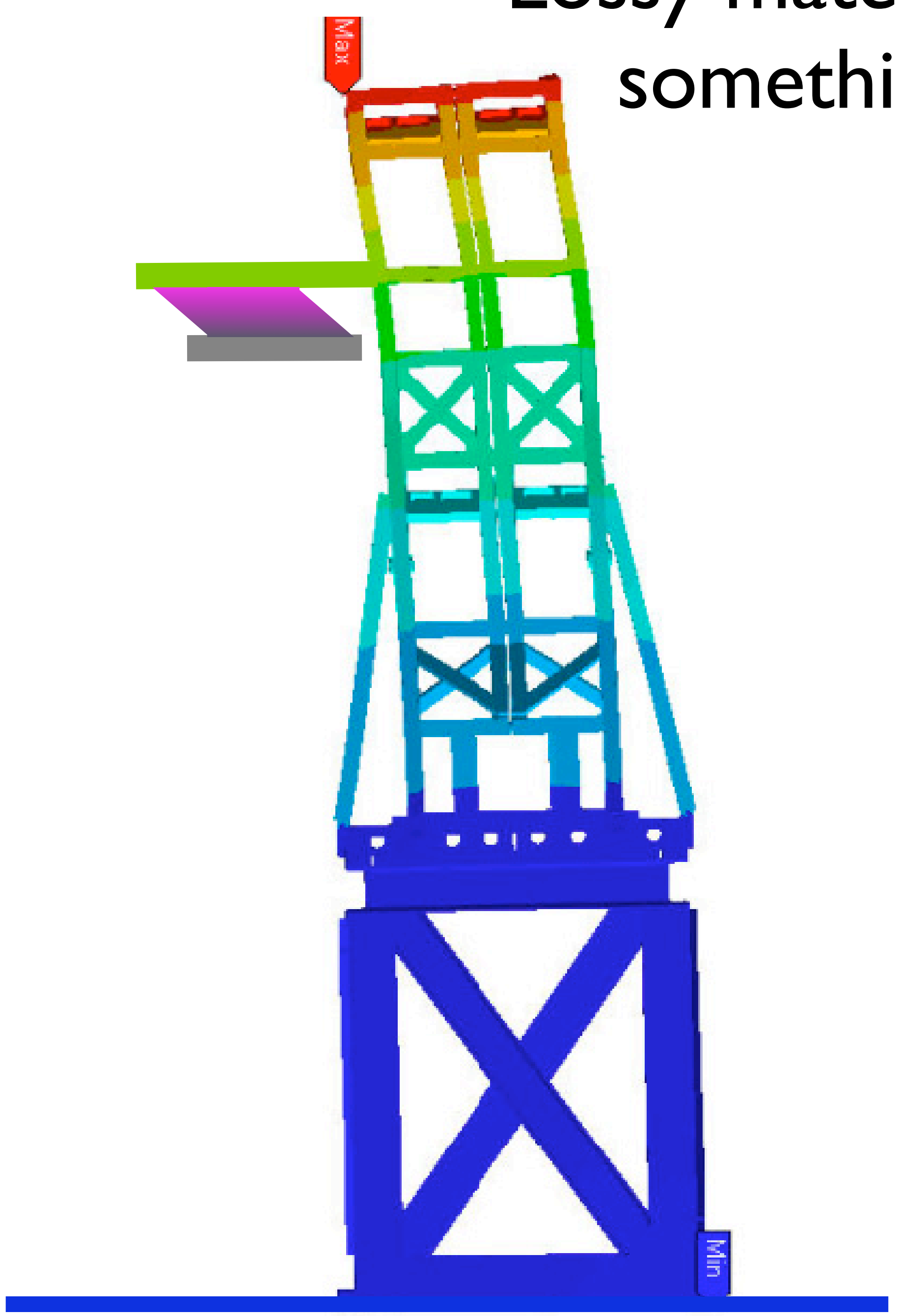
Requires many irritating notches



Passive damping of frame mode

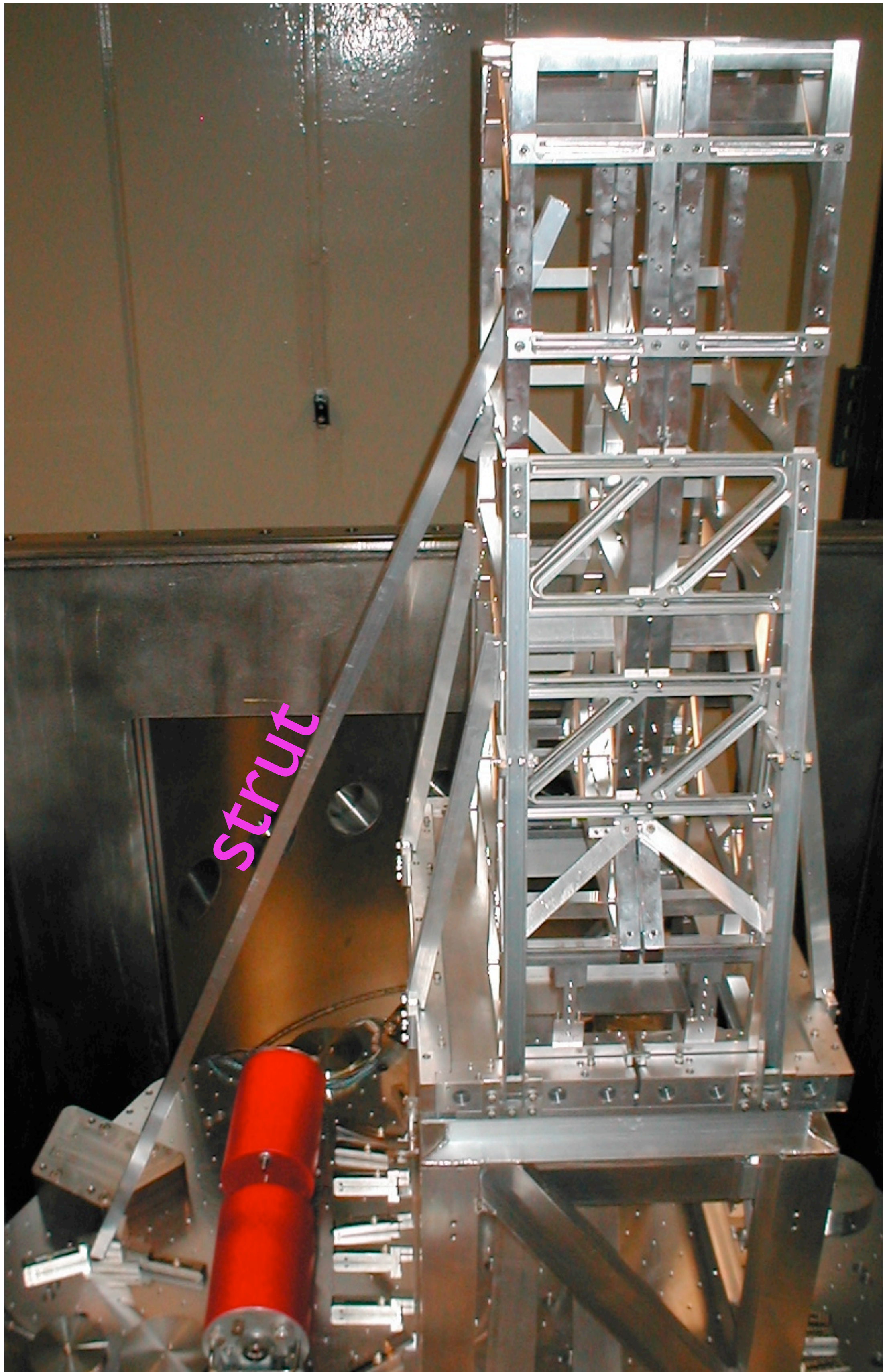
Use vibrational motion to create to create shear in a lossy material (Dyad 601 by SoundCoat)

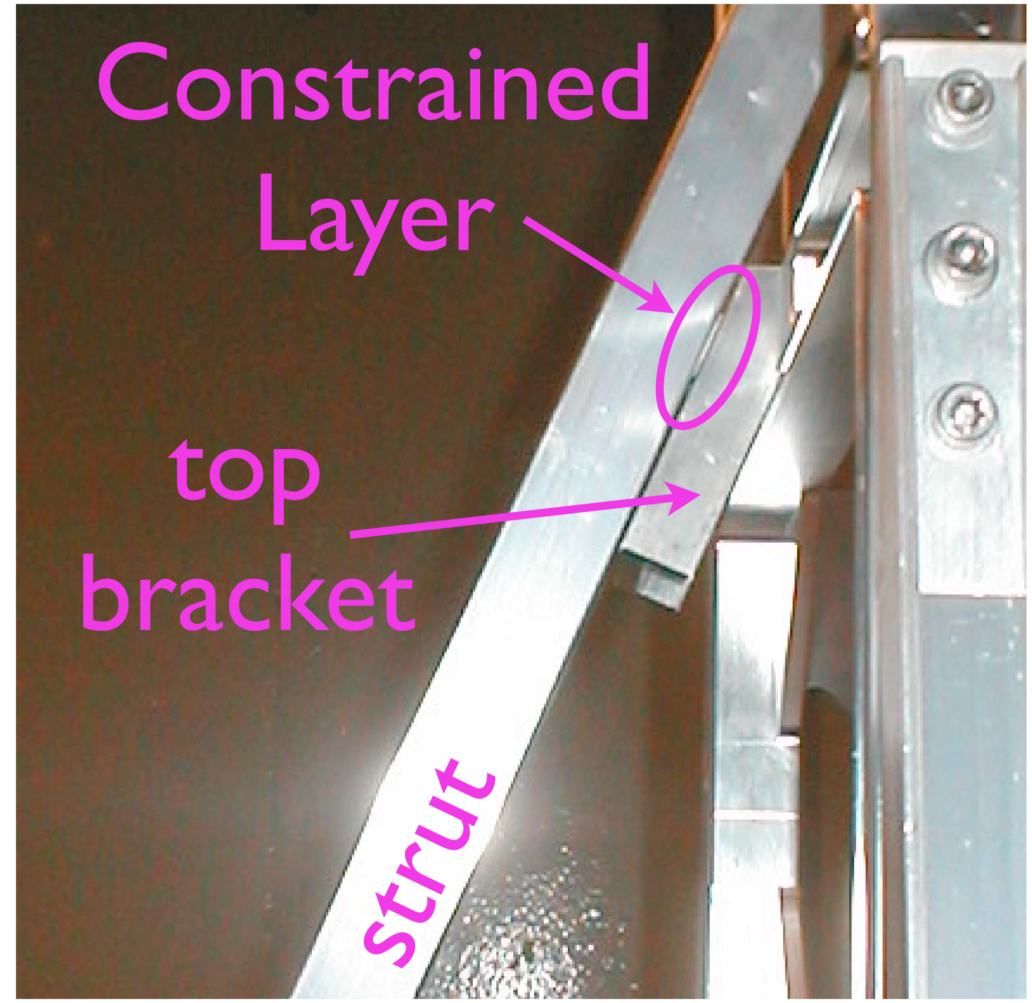
Lossy material placed between frame and something which moves differently.

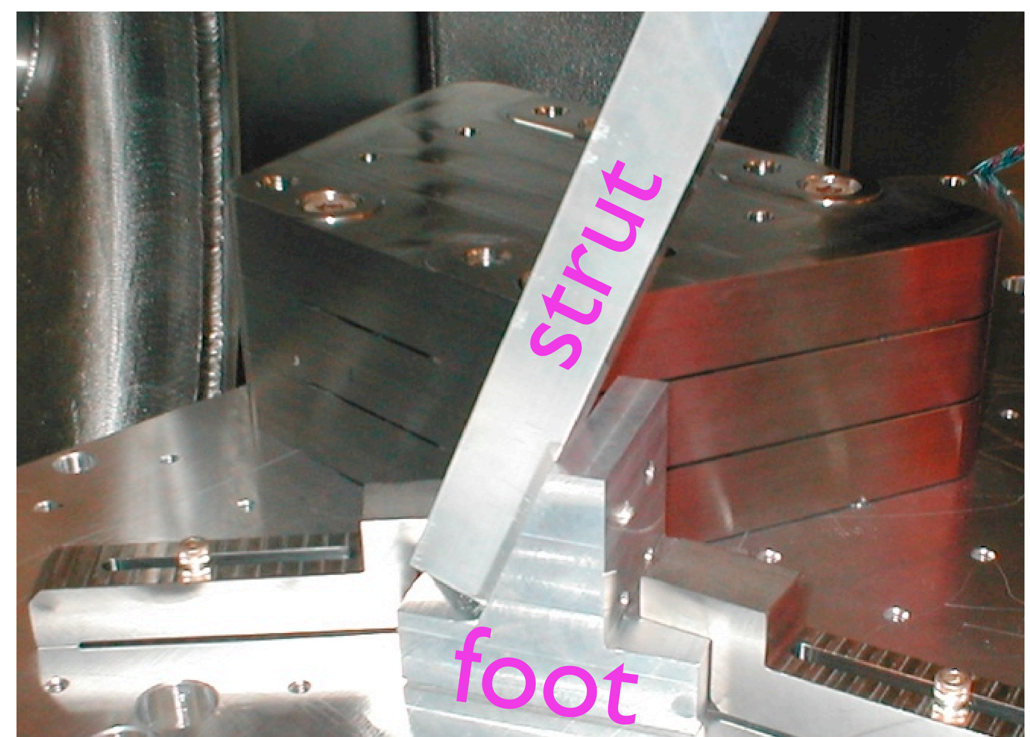


FEA modeling courtesy of Tim Haylor at Rutherford Labs

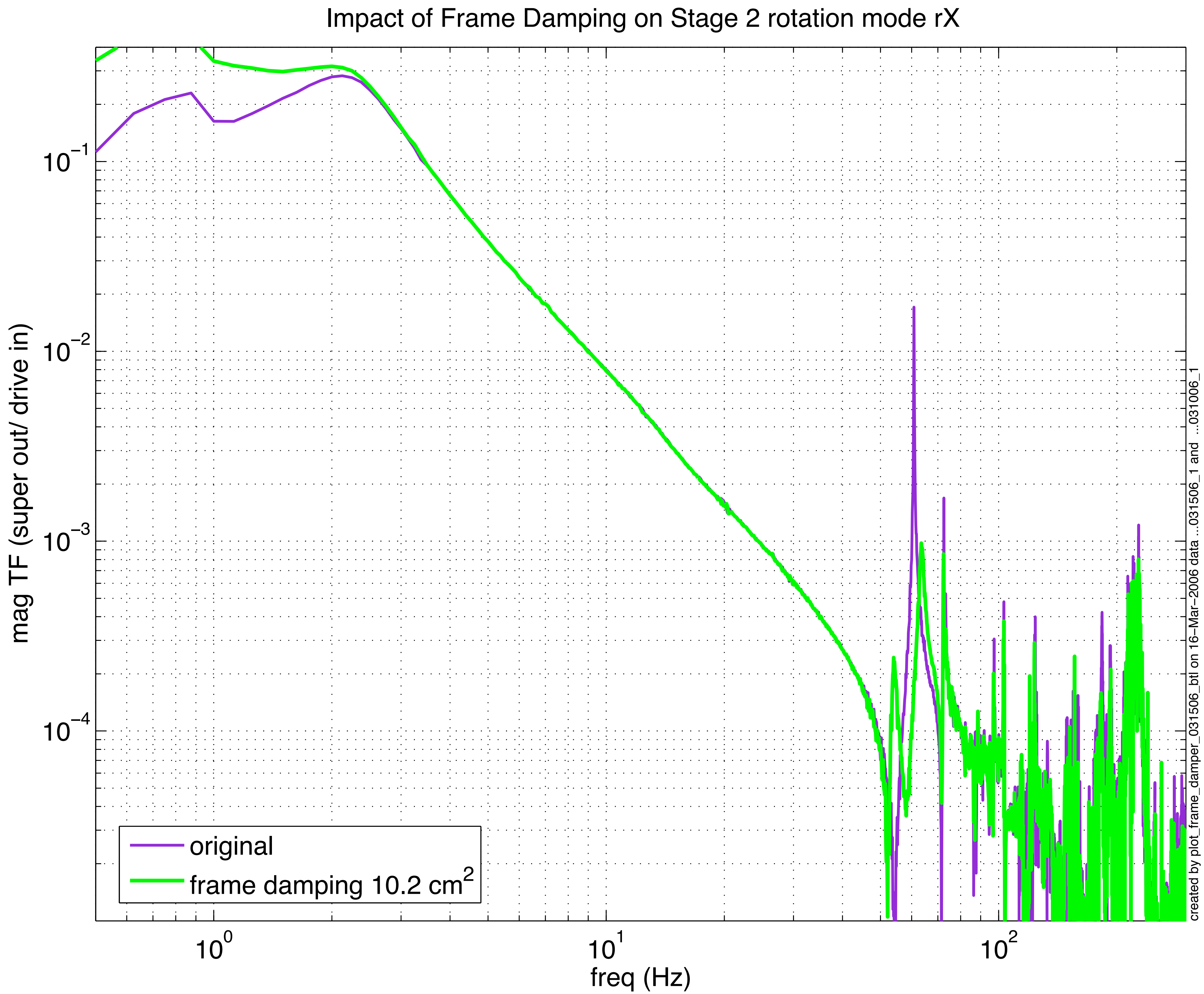
Test setup



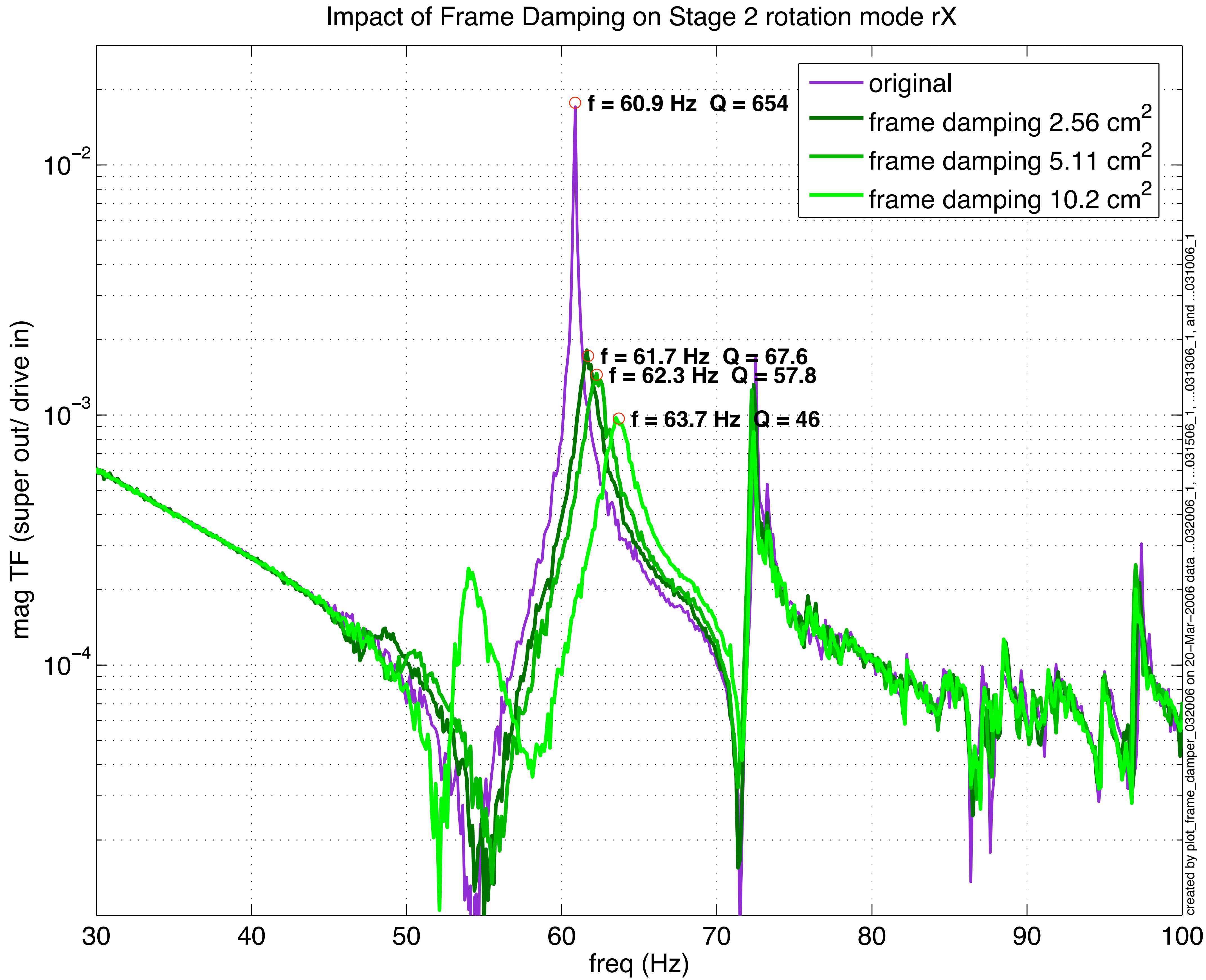




Damping strut performance



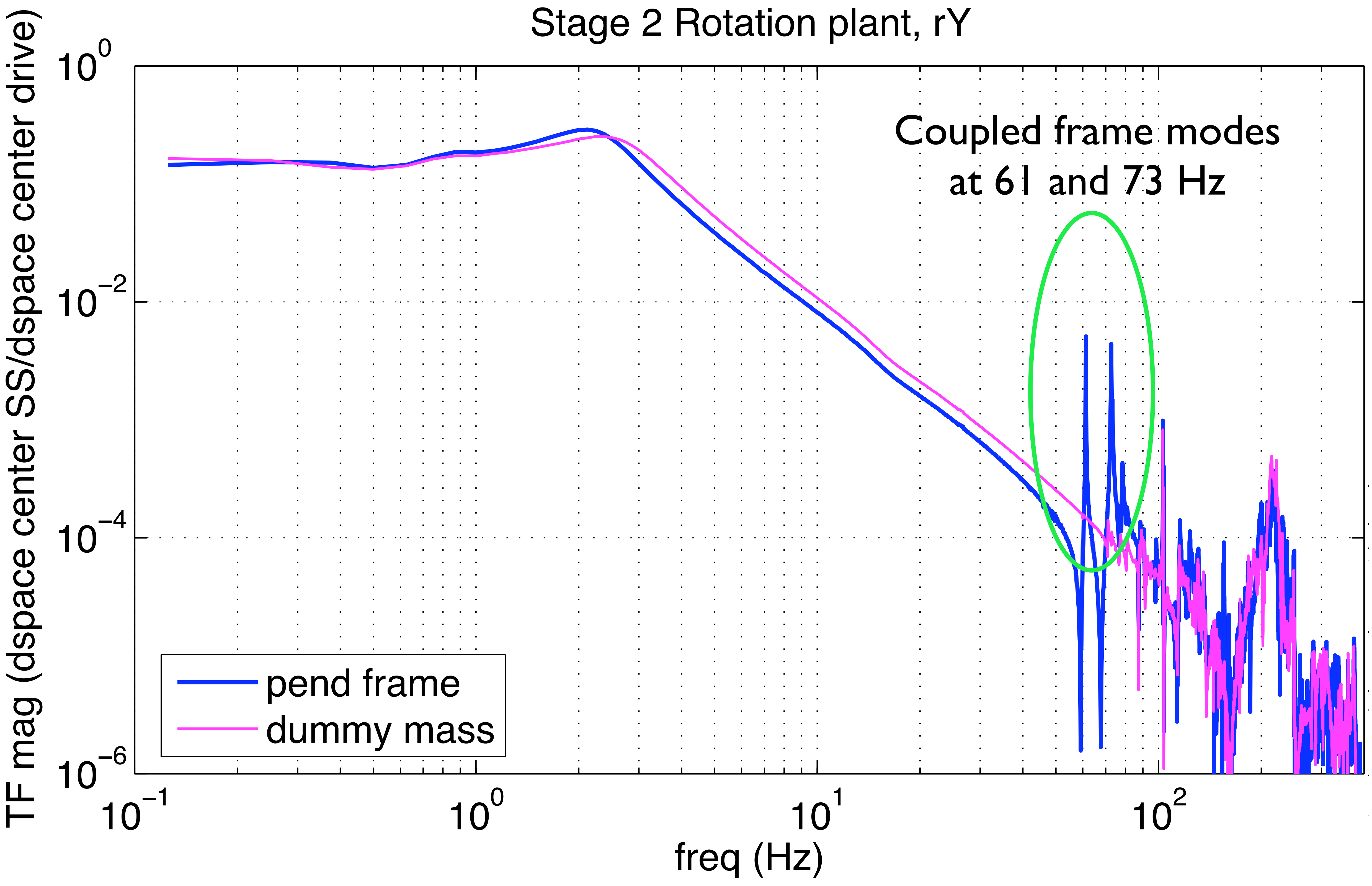
Optimizing the layer



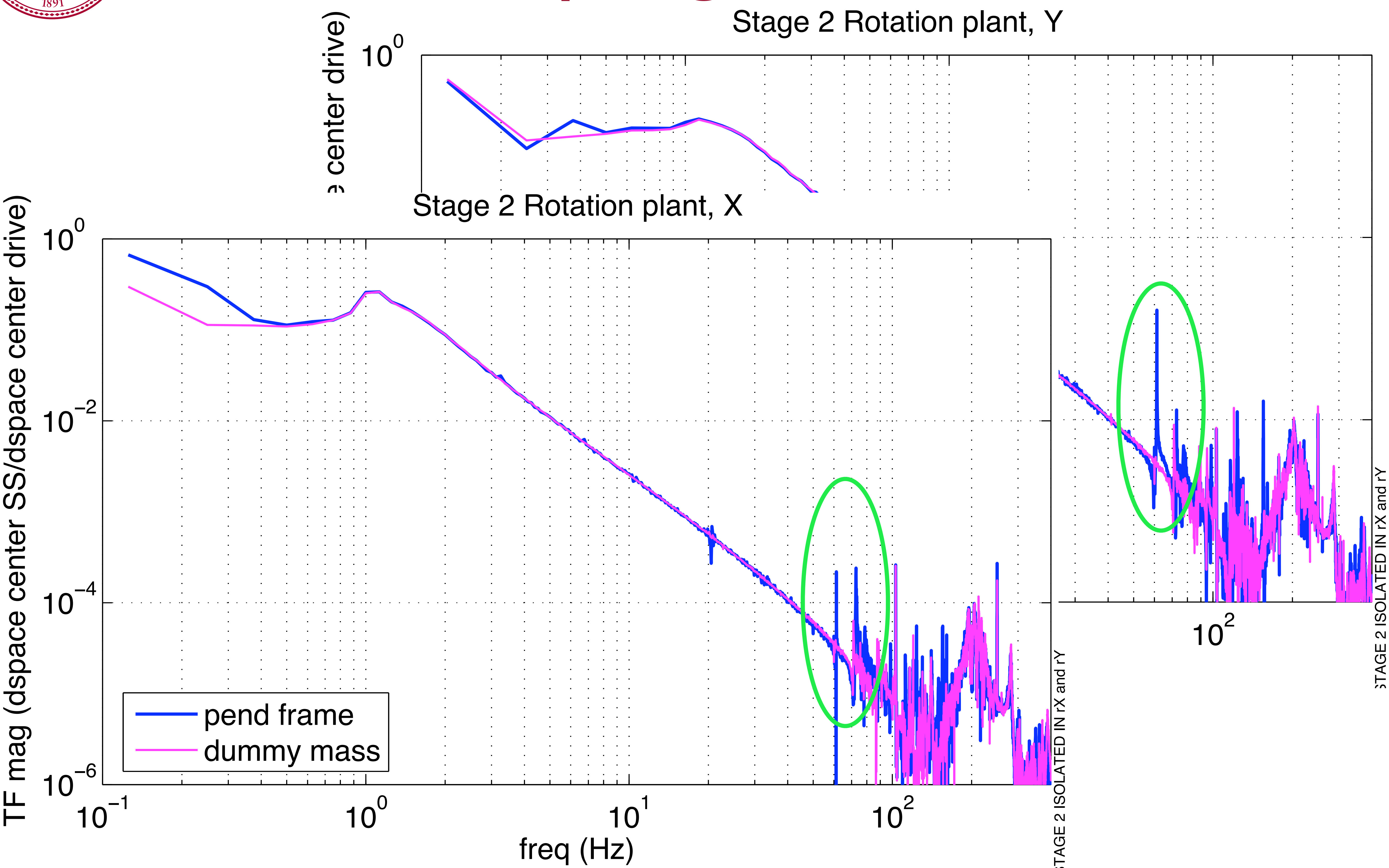
Conclusions

- System works with the quad pendulum frame.
- It will work better if the peaks are smaller amplitude and higher frequency.
- Demonstrated 2 ways to improve the damping.
- We prefer the constrained layer: much easier for Advance LIGO operations.
  Eager to help the SUS team get it working in vacuum.
- Making good progress dealing with the issues identified at the last set of reviews.

Largest Coupling to rX & rY

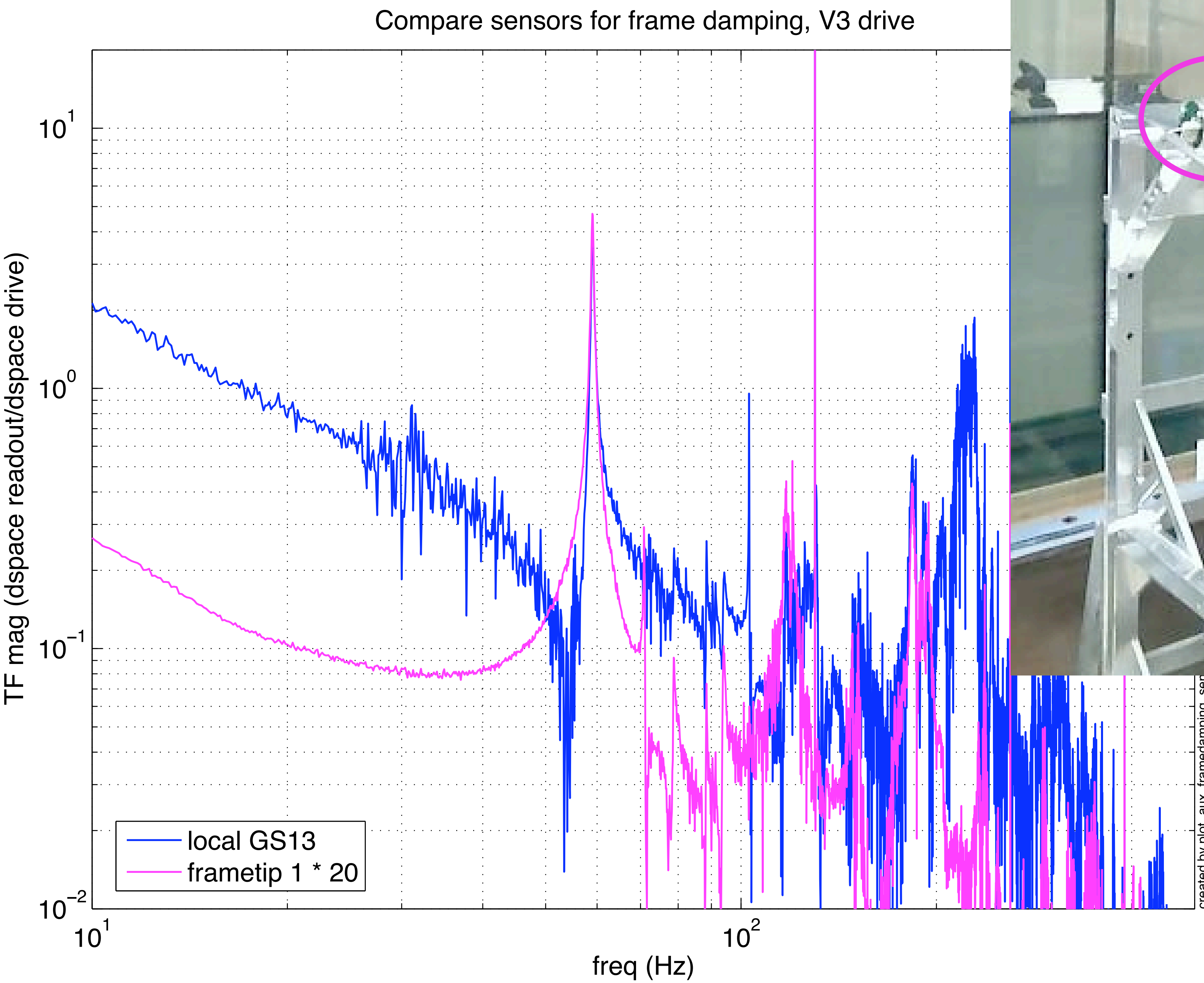


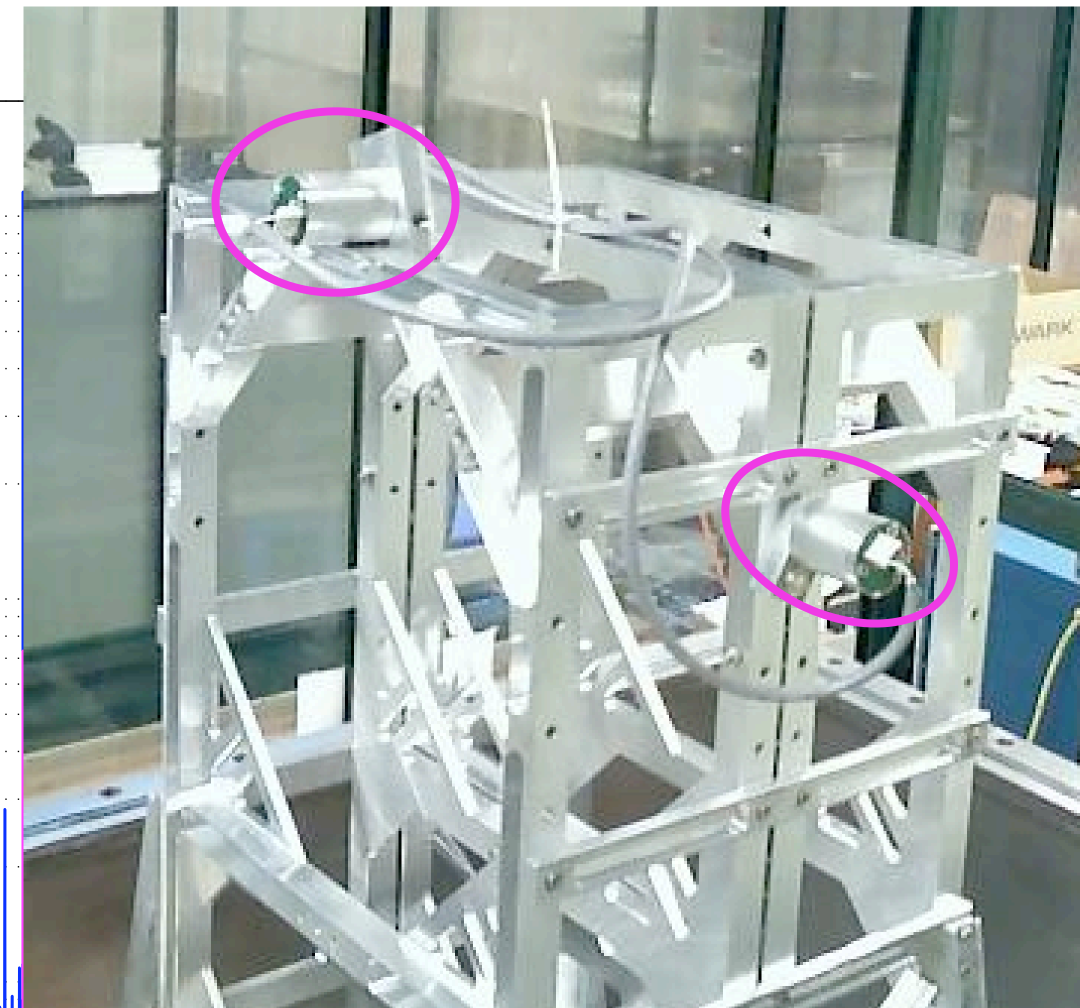
Smaller coupling in other DOF



Improved Active Damping

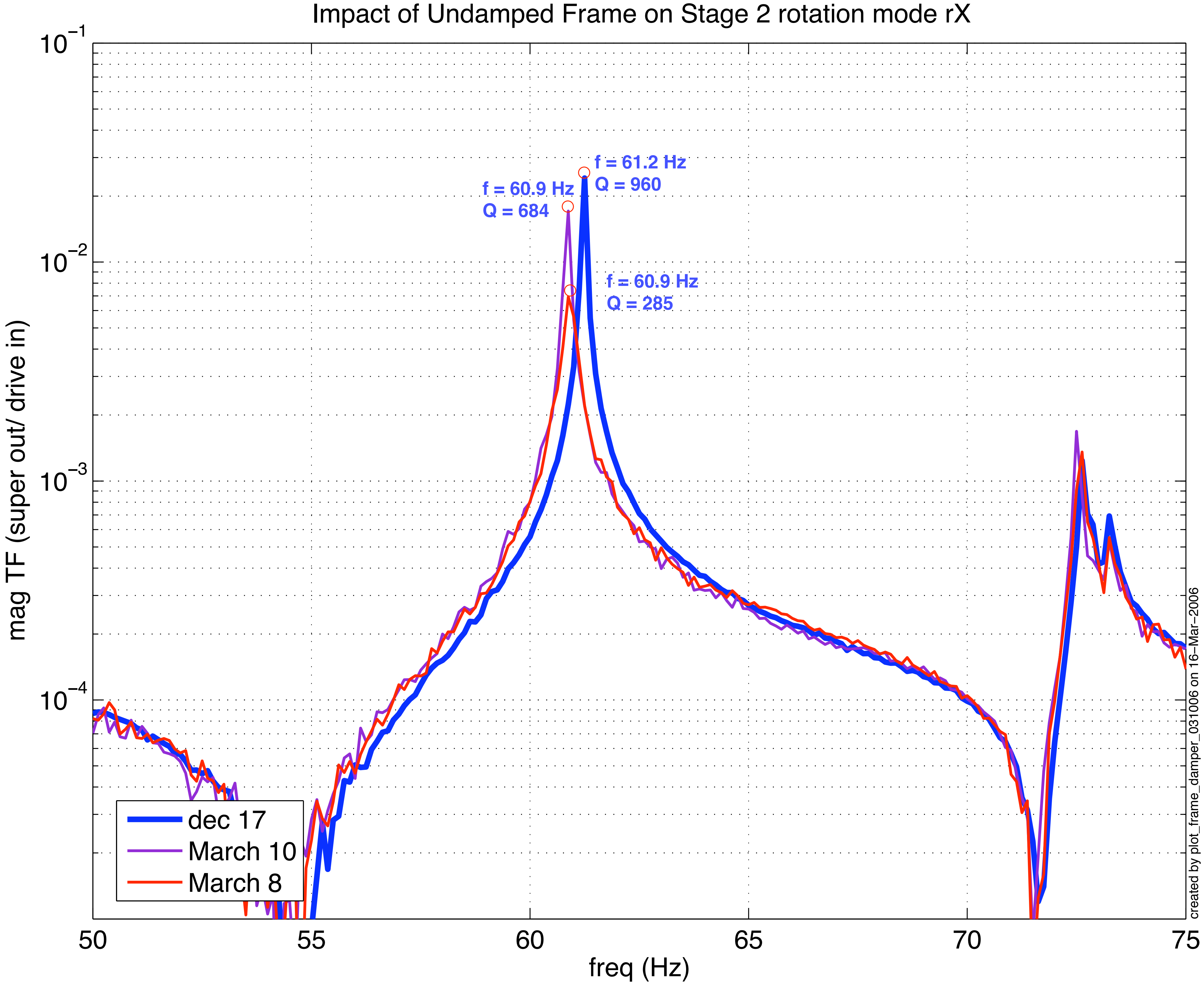
Sensors on the frame tip give better signal for active frame damping



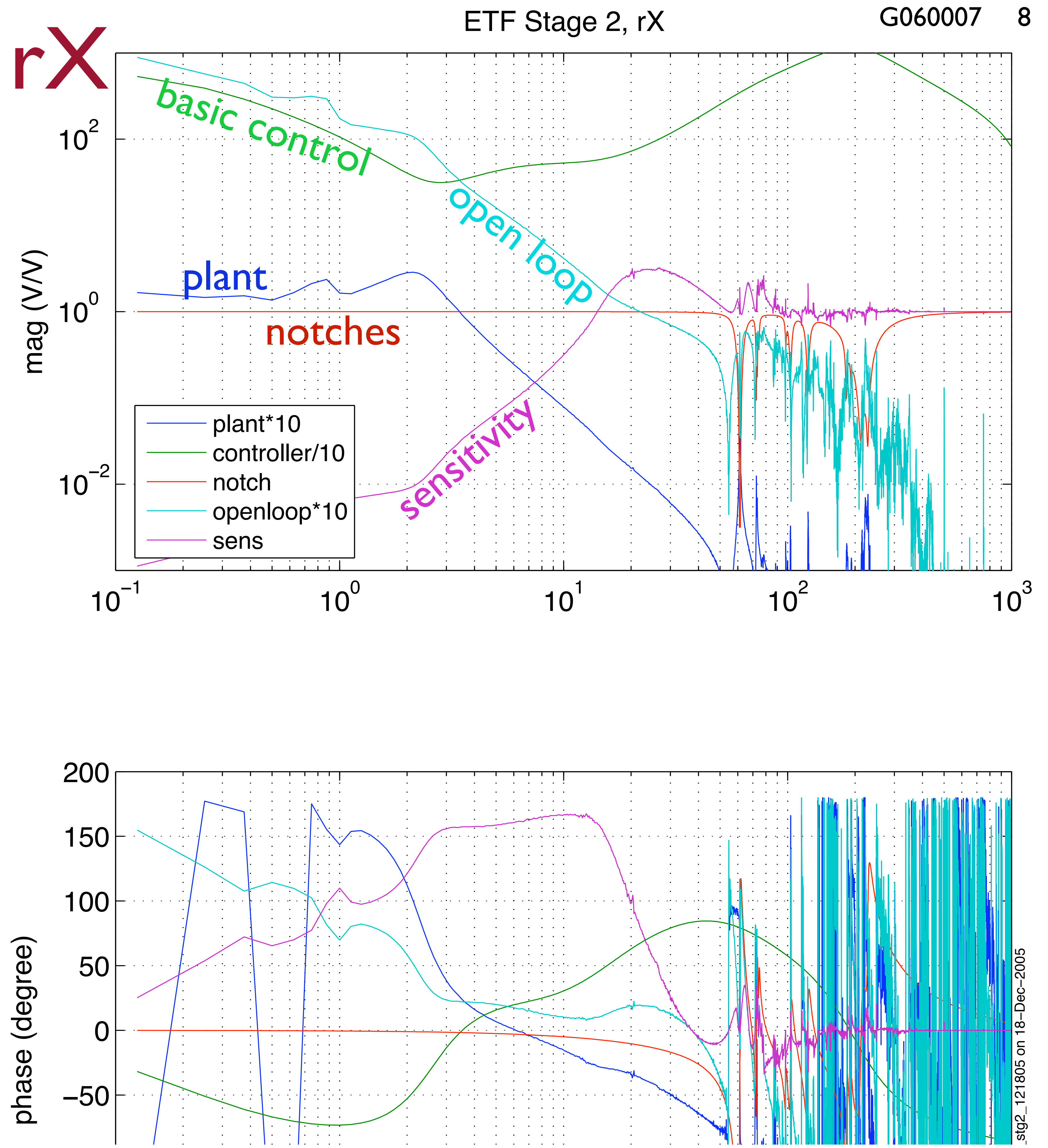


250 grams + preamp +cable + mount + can

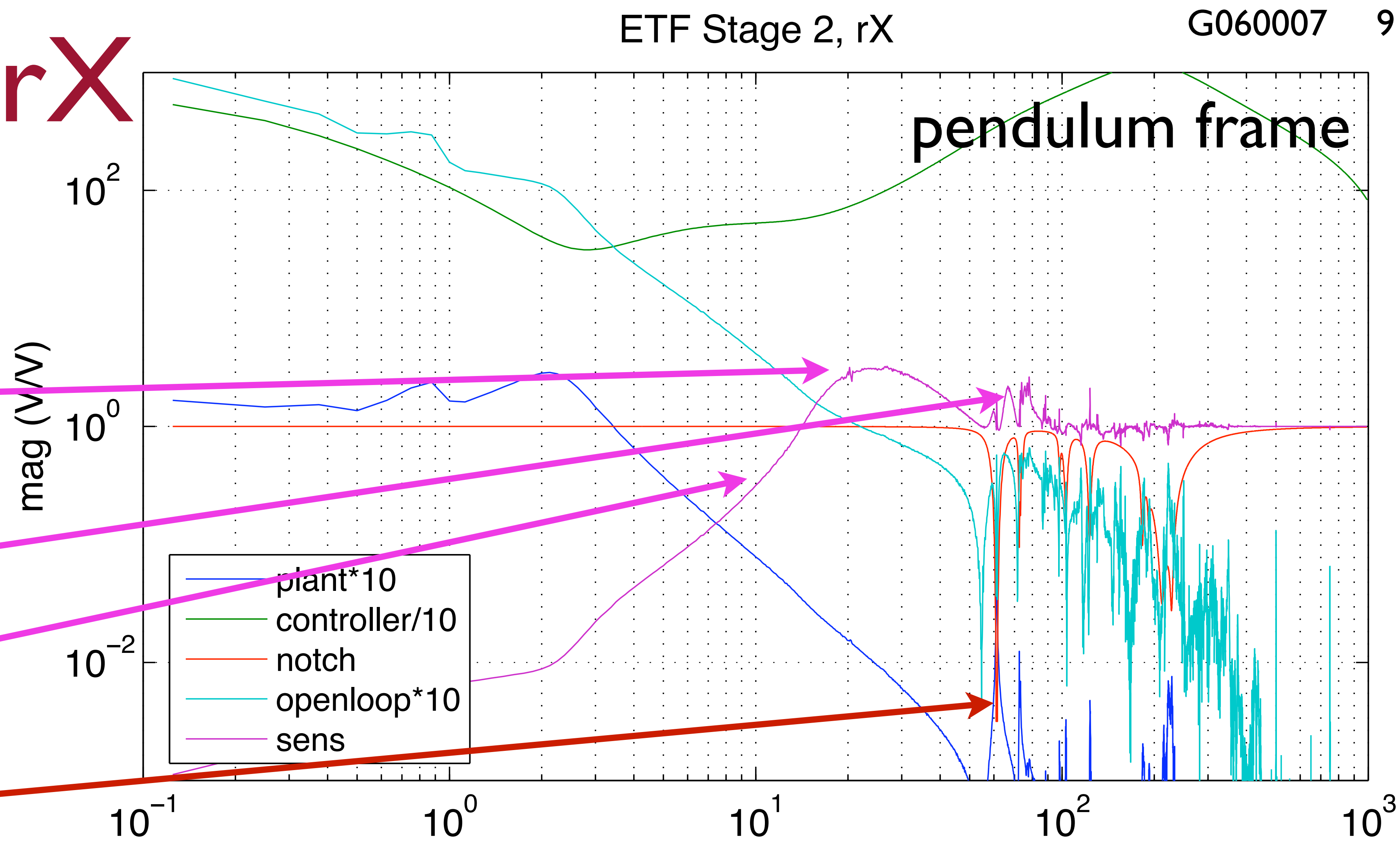
Changing the undamped Frame



Servo for rX

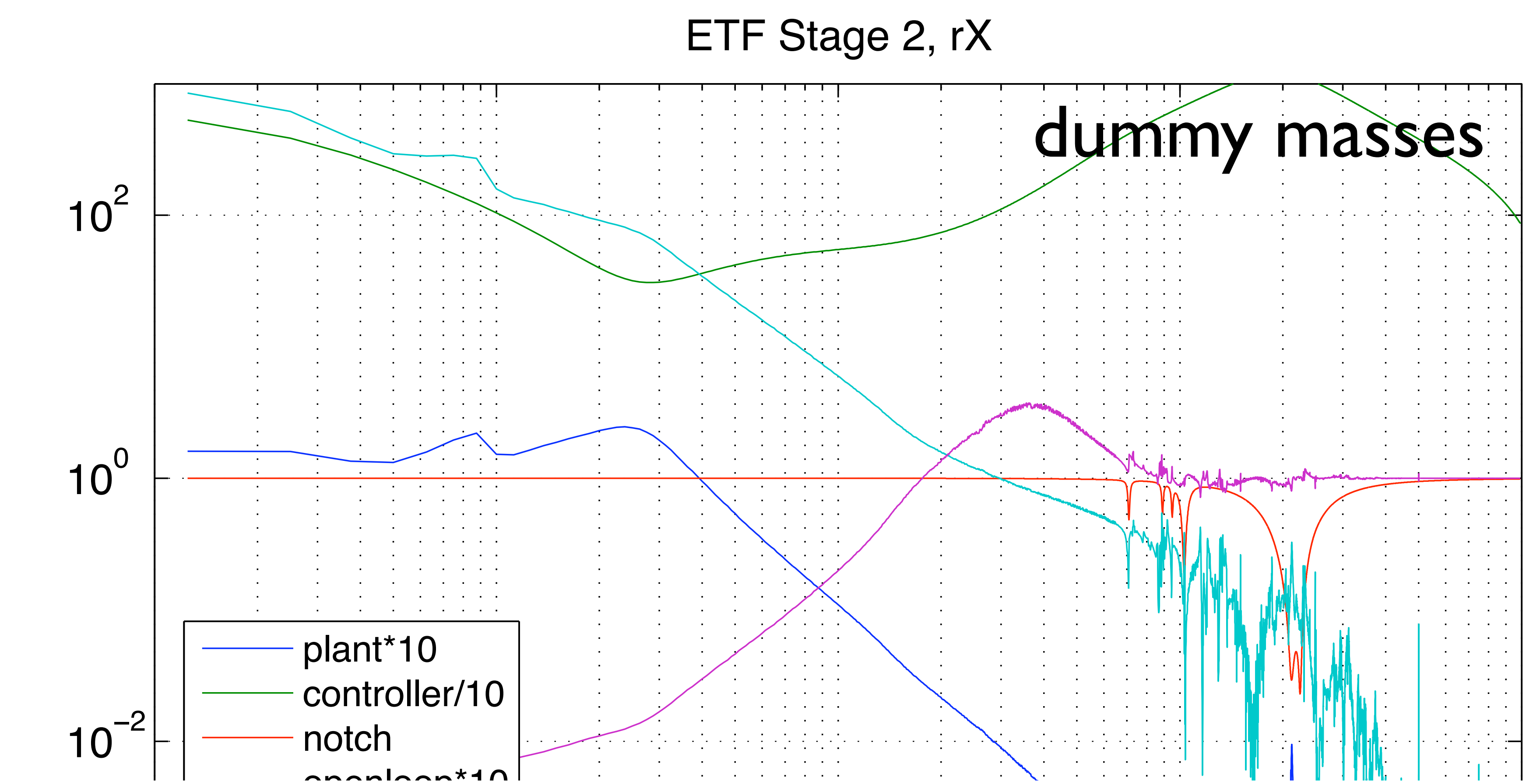

ETF Stage 2, rX
basic control
open loop
plant
notches
sensitivity
mag (V/V)
plant*10
controller/10
notch
openloop*10
sens
phase (degree)
stg2_121805 on 18-Dec-2005

Servo for rX



To notice:

1. Servo amplifies above 13 Hz.
2. 'Hair' about 70 Hz
3. 10 Hz attenuation is modest:
4. Big notches
5. It works.



Dummy mass loop is:

1. Better performance.
2. More robust.
3. Easier to design.