

analysis of the nonlinear integral positive position feedback and integral resonant controllers on vibration suppression of nonlinear oscillatory systems. *Commun. Nonlinear Sci. Numer. Simul.* 22(1-3), 149-166.

- [14] EL-Sayed, A. T., Bauomy, H. S. (2018). Outcome of special vibration controller techniques linked to a cracked beam. *Appl. Math. Model.* 63, 266-287.
- [15] El-Ganaini, W. A., Saeed, N. A., Eissa, M. (2013). Positive position feedback (PPF) controller for suppression of nonlinear system vibration. *Nonlinear Dynamics*, 72(3), 517-537.
- [16] El-Sayed, A. T., Bauomy, H. S. (2016). Nonlinear analysis of vertical conveyor with positive position feedback (PPF) controllers. *Nonlinear Dynamics*, 83(1-2), 919-939.
- [17] Amer, Y. A., EL-Sayed, A. T., N., M. (2022). A Suitable Active Control for Suppression the Vibrations of a Cantilever Beam. *Sound & Vibration*, 56(2), 89-104.
- [18] Bauomy H. S., El-Sayed A. T. and Metwaly T. M. N. (2016). Using negative velocity feedback controller to reduce the vibration of a suspended cable. *Journal of Vibroengineering*, 18(2), (2016), 938-950
- [19] A. M. Elnaggar, A. F. El-Bassiouny, K. M. Khalil and A. M. Omran, Periodic Solutions of a Modified Duffing Equation Subjected to a Bi-Harmonic Parametric and External Excitations, *British Journal of Mathematics & Computer Science* 16(4) (2016)1-12.
- [20] A. M. El-Naggar , K. M. Khalil and A. M. Omran, Subharmonic Solutions of Governed MEMS System Subjected to Parametric and External Excitations, *Asian Research Journal of Mathematics*, 3(3) (2017)1-13.

Appendix

Coefficients of Eqs. (11) and (12)

$$E_1 = \frac{(f_1 A_1 + 6\bar{A}_1 A_1^2 f_1)}{(\omega_1^2 - (\Omega + \omega_1)^2)}, E_2 = \frac{(f_2 A_1 + 6\bar{A}_2 A_1^2 f_2)}{(\omega_1^2 - (2\Omega + \omega_1)^2)},$$

$$E_3 = \frac{(3\alpha A_1^2 - \alpha_1 A_1^2)}{-3\omega_1^2}, E_4 = \frac{(0.5 f_1 + 3A_1 \bar{A}_1 f_1)}{(\omega_1^2 - 4\Omega^2)},$$

$$E_5 = \frac{1.5 A_1^2 f_1}{(\omega_1^2 - (\Omega + 2\omega_1)^2)}, E_6 = \frac{2\bar{A}_1^3 f_2}{(\omega_1^2 - (2\Omega - 3\omega_1)^2)},$$

$$E_7 = \frac{1.5 A_1^2 f_2}{(\omega_1^2 - (2\Omega + 2\omega_1)^2)}, E_8 = \frac{1.5 \bar{A}_1^2 f_2}{(\omega_1^2 - (2\Omega - 2\omega_1)^2)},$$

$$E_9 = \frac{2\bar{A}_1^3 f_1}{(\omega_1^2 - (\Omega - 3\omega_1)^2)}, E_{10} = \frac{2A_1^3 f_1}{(\omega_1^2 - (\Omega + 3\omega_1)^2)},$$

$$E_{11} = \frac{(4\alpha \bar{A}_1^3 - \alpha_1 \bar{A}_1^3)}{-8\omega_1^2}, E_{12} = \frac{2A_1^3 f_2}{(\omega_1^2 - (2\Omega + 3\omega_1)^2)},$$

$$E_{13} = \frac{(f_1 \bar{A}_1 + 6A_1 \bar{A}_1^2 f_1)}{(\omega_1^2 - (\Omega - \omega_1)^2)}, E_{14} = \frac{(3\alpha \bar{A}_1^2 - \alpha_1 \bar{A}_1^2)}{3\omega_1^2},$$

$$E_{15} = \frac{(4\alpha A_1^3 - \alpha_1 A_1^3)}{8\omega_1^2} + E_{16} = \frac{(f_2 \bar{A}_1 + 6A_1 \bar{A}_1^2 f_2)}{(\omega_1^2 - (2\Omega - \omega_1)^2)},$$

$$E_{17} = \frac{(0.5 f_1 + 3A_1 \bar{A}_1 f_1)}{(\omega_1^2 - \Omega^2)}, E_{18} = \frac{2\bar{A}_1^3 f_2}{(\omega_1^2 - (2\Omega - 3\omega_1)^2)}$$

$$E_{19} = \frac{\gamma_2 A_1}{(\omega_2^2 - \omega_1^2)}.$$