



ELEC 372 - FUNDAMENTALS OF CONTROL SYSTEMS

LABORATORY MANUAL

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**Department of Electrical & Computer Engineering
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**ELEC 372 - FUNDAMENTALS OF
CONTROL SYSTEMS**

LABORATORY MANUAL

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PLEASE READ IMPORTANT INFORMATION REGARDING
EMERGENCY PROCEDURES GIVEN ON THE LAST PAGE!

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1 GENERAL INSTRUCTIONS

1.1 INTRODUCTION

This manual provides the operating instructions in a simplified form and leads ELEC372 students through a prescribed set of experiments aimed at demonstrating the basic principles of feedback control systems.

It is essential that students read these preliminary sections in order to understand the purpose of each experiment. A brief tutorial, pertaining to the work to be done, will also be given by the lab instructor at the start of each lab. In addition, students should prepare ahead for each lab and try to understand each experiment in order to gain maximum benefit from the course.

- To illustrate the material that is the subject matter of ELEC372 course by experiment. Specifically, to acquaint students with a practical control system. An electromechanical angular-position control system is used as an example.
- To familiarize students with practical transient-response and frequency-response testing of a control system, and to investigate various controller configurations.
- To give the students the opportunity to practice engineering report writing and teamwork.
- To train the students to use engineering tool, MATLAB, to create and extend its functions as necessary. MATLAB is an interactive program for numerical computation and data visualization; it is used extensively by control engineers for analysis and design.

1.2 LAB REGULATIONS

- The lab has 8 numbered stations with a maximum of 2 students per station. Each station group must use the same station for the entire sessions.
- Experiments will be performed in five sessions in the sequence given in the Lab schedule sheet which will be distributed to students in class before labs start. Each lab will meet every alternate week. Every group member must participate in performing the experiments.
- Every student must prepare and submit an individual report to the lab instructor at the subsequent lab session. Marked reports will be returned at the subsequent session. The marking guideline is given later in the manual. Late submissions will be penalized. The deadline for the final report (#5), which may be less than a week, will be provided by the lab instructor.
- Reports should be concise, original and meaningful. Every report must carry the signed and dated 'Expectations of Originality' statement: "*I certify that this submission is my original work and meets the Faculty's Expectations of Originality*" required by ENCS regulations. A copy of the ENCS document is provided in the Appendix of the manual. Wherever possible, data calculated or obtained in the lab must be authenticated by the lab instructor's signature/initials. Students are encouraged to use results from various available mathematical and control systems simulation software in their reports.

- Final reports should be reclaimed from the lab instructor at the end of the session.
- Unclaimed reports will be retained only for a period of three months after the end of the session, after which they will not be available.

1.3 RULES OF CONDUCT TO BE OBSERVED IN THE LAB

- Students are expected to treat the lab equipment and the instructor with due respect. Disciplinary action will be taken against any student caught misusing the lab such as making marks on benches or other equipment.
- Students must show seriousness in performing the lab and not be a source of disturbance to neighboring stations. Cell phones must be switched off and students are not allowed to exit the lab to hold cell-phone conversations.
- Water-bottles or other liquid containers are not allowed in the workspace. Eating, drinking, and smoking are strictly forbidden in the lab by university regulations. All clothing, bags, etc. must be put away from the work area. Keep the workspace clean.
- At the end of each session, make sure that all scrap papers, pens, etc. are removed and that the lab equipment is switched off according to procedures given later.
- **Fire or Other Emergencies:** In the event of a fire or other emergency requiring evacuation of the building, students must follow the lab instructor's directives and immediately leave the building via the stairwells. There are two stairwells closed to the lab location and these are indicated on a map found in the lab.

Please also read the emergency procedures given on the last page of this manual.

1.4 MISSED LABS AND MAKEUP PROCEDURE

Only one lab absence* is permitted. If you miss more than one lab, you are not likely to obtain the average of 50% in the lab, which is required to pass the course. A student who misses a lab must attend another lab within the same experimental cycle to make up for the missed experiment **and** must immediately email both her/his lab TA and the Lab coordinator about the substitution. In general, a lab missed due to unavoidable grave circumstance, such as accident or illness, may be disregarded in calculating the average grade provided that an authentic document (police report, doctor's or hospital certificate etc.) is furnished.

***Note:** Expt#1 is a 'familiarization' experiment and should not be missed. No makeup will be given for Expt#1 after its cycle has ended.

1.5 EXPERIMENT OUTLINE

The five experiments to be performed in the laboratory component of the course are given in the following sections. All five experiments are designed to demonstrate the content taught in ELEC372:

- EXPT #1: FAMILIARIZATION WITH EXPERIMENT SYSTEMS
- EXPT #2: SYSTEM IDENTIFICATION

- EXPT #3: IMPROVING SYSTEM PERFORMANCE
- EXPT #4: TRANSIENT AND FREQUENCY RESPONSE
- EXPT #5: IN-LAB PROJECT: CONTROLLER DESIGN

Although the lab experiments are intended to complement the classroom lectures, the limited time available during the semester will certainly cause the subject matter of the experiments to be ahead of the topics being taught in class at any given time. In order to somewhat alleviate this situation, each experiment in this manual is preceded by a short 'tutorial' which attempts to explain the particular topic being investigated. Relevant tutorial material is also given in the introduction part of each experiment.

1.6 MARKING GUIDELINE

The lab marks count for 15 percent in the ELEC372 course grading scheme. The average of the five labs will be reported on a maximum of 10 and the lab test on a maximum of 5.

Lab reports will be graded on a scale of 10 with the approximate percentage weightings shown:

Table 1.1: Marking guideline

1	Participation: Attendance and Lab Performance [Good performance is an indication of Being well- prepared for the experiment to be done]	20%
2	Organization and Presentation: Coherence, Proper Tabulation, Calculations, Simulations, Computer-drawn or neatly hand drawn graphs	30%
3	Discussion and Summary: Technical discussion of obtained results, error calculations, experimental / theoretical correlations, Meaningful conclusion (summary of what was learnt etc.)	50%

1.7 REFERENCE

- Modern Control Systems*, Richard C. Dorf and Robert H. Bishop, 11th Edition, Prentice Hall.
- Manual for ECP Model 220*, Instructor's Edition, ECP Control Systems, 1995
- MATLAB R2014b on-line Help. www.matlab.com

2 LABORATORY EQUIPMENT OVERVIEW

2.1 GENERAL DESCRIPTION

The laboratory equipment used in this Lab is an ECP Model 220 Industrial Emulator which is a rotational motion control system designed for teaching purposes by Educational Control Products (ECP systems) company. The components of the system are shown schematically in Figure 2.1. The system is driven by a digital real-time controller with a digital computer (PC) as an interface. The 'plant' is a rotational-motion assembly consisting of a motor-driven set of two turntables (called 'disks' hereafter) which are coupled by means of selectable toothed belts and pulleys. Additional weights may be symmetrically added to the turntables thereby increasing their effective rotational inertia. Once the mechanical configuration (i.e. belts, pulleys, weights) of the system is selected, the 'plant' consisting of the motor/turntable assembly can be represented by a first-order rotational friction/inertia model described in experiment (1). The two turntables are provided with optical digital-encoders which measure their position, velocity and acceleration. The 'control box' contains all the drive and measurement circuits required for actuating the system. A desktop PC, which contains a digital controller as well as ECP executive program, is used to complete the closed loop system. Controller and control-parameter selection, data entry, and output display selection are all made through the peripherals (keyboard/mouse/monitor) of the PC. Thus, for any given mechanical configuration, the remaining operations are entirely computer-menu-driven with a graphical-user-interface. Although the control signal is implemented through digital means ('sampled data'), it can physically emulate an analog system, which is the mode that is utilized for the purposes of this lab.

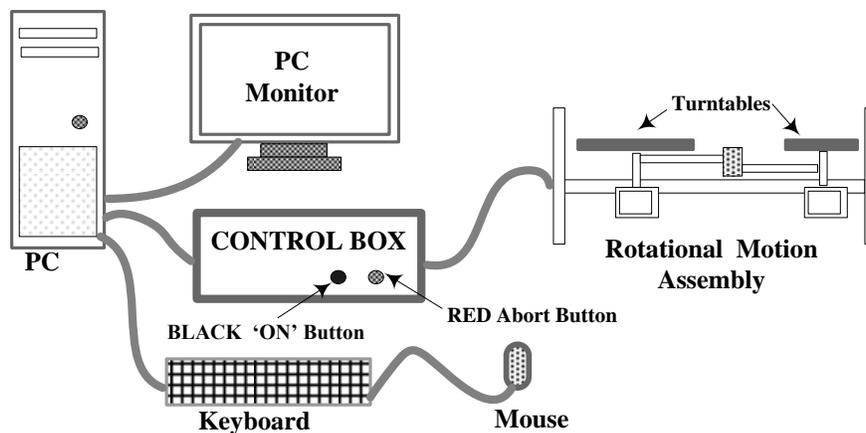


Figure 2.1: Basic system components

2.2 ROTATIONAL-MOTION ASSEMBLY

This unit basically consists of two belt-driven metal turntables (hereafter called 'drive' and 'load' disk) which are shown schematically in Figure 2.1: Basic system components. The two disks are radially slotted, so that two or four symmetrically-spaced, brass weights may be attached in order to change (increase) their rotational inertia. **In the lab setup, the positions of these weights are fixed at the maximum radius of each turntable.** The two disks are coupled using toothed-belts and pulleys through an intermediate 'speed-reduction' (SR) assembly. The SR unit has mechanisms to provide backlash, if

required. **Backlash** (also known as “Dead Zone” or “Deadband”) is a non-linearity which typically occurs in system transmission links such as gear trains and/or ‘rack & pinion’ assemblies. The effect of backlash is seen as a short interval of inactivity (i.e. no output) whenever the direction of motion is reversed. It is a nonlinear effect. Since the experiments in this lab deal with ‘linear’ systems, **the backlash setting facility is not used in the lab setup.**

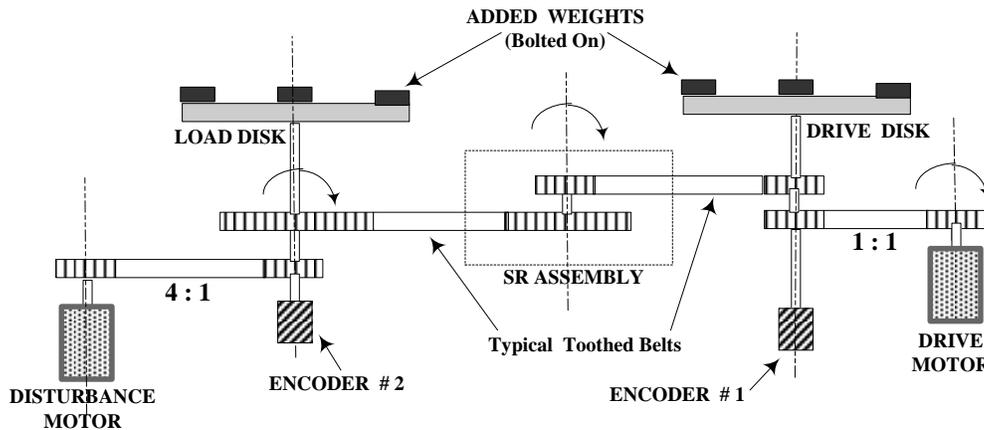


Figure 2.2: Rotational-motion Assembly

Speed reduction ratios can be changed in the system by selecting interchangeable pulleys in the SR assembly. The equipment also permits a flexible belt to be used between the SR assembly and the ‘load’ table, for advanced studies on “flexible-drive control systems”. If the flexible belt is not used and if the backlash set is ‘zero’, then the rotational components are considered to form a rigid (as opposed to flexible) system. The drive disk is driven by a brushless DC drive motor through a 1:1 belt/pulley coupling. Another brushless DC motor, called the ‘disturbance motor’, is coupled to the ‘load’ disk through a 4:1 belt/pulley. Various disturbance signals such as step or sinusoidal (or other user-defined functions) can be introduced into the system through this motor. The disturbance motor also allows an equivalent viscous friction to be introduced at the load disk location.

The experiments described in this manual assume a rigid system with all inertias reflected to the drive disk axis at Encoder#1, with an overall reduction ratio of 4:1 (i.e. 4 revolutions of the drive disc at Encoder#1 result in 1 revolution of the load disk at Encoder#2). The encoder outputs are points of origin of feedback signals, so that a feedback loop may be ‘closed around’ either of the encoders. In the lab experiments, the loop is closed around encoder #1 (at the drive disk), and all inertias and friction is ‘referred’ to the drive-disk side of the rotational assembly. All the above components are mounted within a metal frame which can be oriented horizontally or vertically; in this lab the frame is used with the rotational axes pointing in the vertical direction only, so that gravitational torques will not be present.

The actual arrangement of the motional components is shown in Figure 2.3.

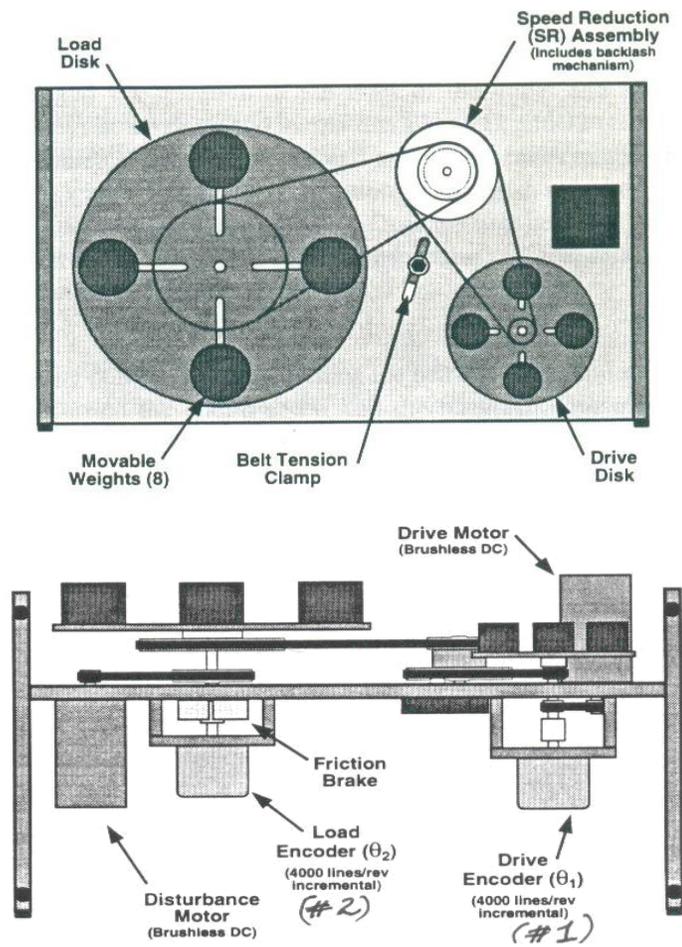


Figure 2.3: Actual arrangement of turntable components

2.3 CONTROL BOX

This unit contains the power supplies, servo amplifiers, interfaces, and other circuits needed to drive the two brushless DC motors and to process the encoder signals. It, also, contains the protection circuits which open the control loop under overload conditions. All circuits in the box communicate with a digital signal processor (DSP) located within the PC.

The front panel of the control box has two push button switches and a power indicator light. The **black** button is the **ON** switch and the red button is the ABORT (**OFF**) button.

2.4 WORKSTATION

The PC system contains DSP hardware and software (i.e. the executive program labeled ECP32) through which the type of controller for the system can be specified. The DSP executes the control 'laws' at sampling rates that are high enough to permit modeling of the system as either a **discrete time** or a **continuous time** system, although actual control is through discrete-time. Various controller configurations (see figure 2.5) can be implemented (either in continuous-time or in discrete-time) and the required parameters are set manually using the keyboard and mouse.

2.4.1 STARTUP SEQUENCE

The following sequence must be followed for startup of the equipment:

- Ensure that the protective plastic cover on the rotational motion assembly is in place and all mechanical parts are secure (not loose).
- Turn on the PC, login by the account given by TAs.
- Turn the control box ON by pressing the black button on it.
- On the desktop, click on ECP32 icon, ignore the pop-up windows for 'User Account Control'.

2.4.2 SHUTDOWN SEQUENCE

The following sequence must be followed for shutdown. Failure to use this sequence may result in error messages such as "Controller not found" at the next startup.

- First delete all your data files after you have recorded them on your USB key. Then click 'Exit' from ECP 'File' menu.
- From the 'Start' menu, choose 'Shut Down'. The entire setup including the control Box will be shut off when the computer shuts down.

If messages such as "Controller not found" or "ECP executive may be already running... continue anyway?" are seen, it is best to exit the program as above and start over.

2.5 ECP EXECUTIVE CONTROL PROGRAM

The background screen shown in Figure 2.4 remains in the background on the desktop during all subsequent operations. It has an **Abort Control** button at the lower right side of the screen, which can be used at any time to disable system activity in the case of an emergency. However, the Red hardware **Abort** button on the controller box is also available to disable the system. The Red Abort button should

be pressed if the mechanism is moving erratically or with dangerously large motions. The background screen has 6 menu options described in the next section.

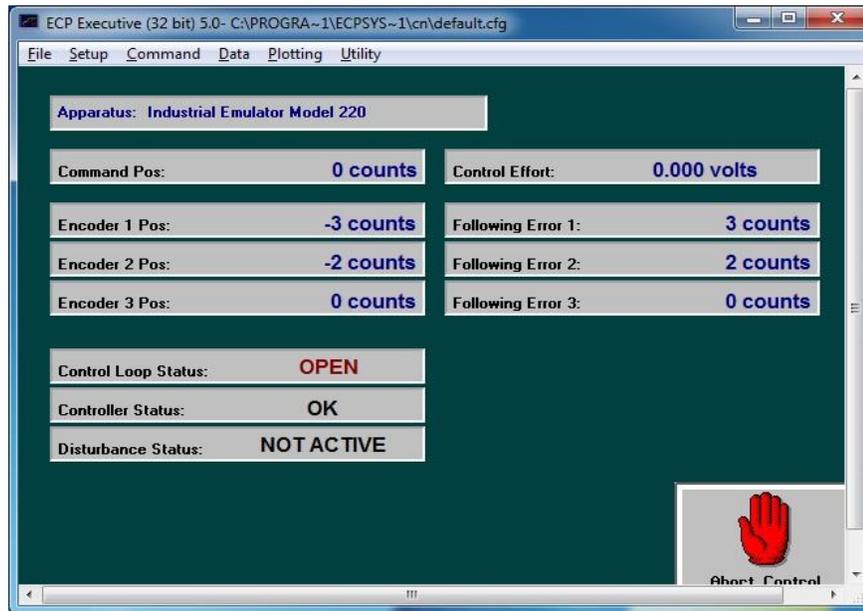


Figure 2.4: ECP Background Screen

The background screen, shown in Figure 2.4, basically displays the control loop status (open/closed) and controller and disturbance encoder status outputs (OK/Limit Exceeded and Active/Not Active, respectively). It also displays the command position, encoder positions and the corresponding errors (in counts, radians or degrees) and the control effort in volts (i.e. the equivalent input to the ‘plant’). The background screen has 6 main menu options as follows: File, Setup, Command, Data, Plotting and Utility. Each of these has sub-menus under which the various operating parameters and commands can be set. Brief explanations of the menu functions are given below. Students should carefully read the descriptions given below and attempt to understand the menu functions.

- (1) The **File** menu allows the saving/loading of any given configuration in the format “*.cfg” and to exit from ECP program.
- (2) **Setup** allows the setting-up a specified control system configuration (under Setup Control Algorithm), either in discrete-time or in continuous-time, *the latter being used in this laboratory*. This menu also allows selections of user units (counts, radians, degrees with 16000 counts corresponding to 360° or 2π radians), and the testing of communications between the DSP board and the PC (the last function being used only at the time of installation of the program). The lab experiments use counts as the ‘user unit’. Setup Algorithm allows one of six basic feedback configurations (PID, PI with Velocity feedback, Dynamic Forward Path, Dynamic Prefilter/Return Path, and State Feedback) to be selected. An additional path, called a Feedforward path, can be added to any of the above six configurations. The actual block diagrams for these configurations, for continuous-time specification, are given in Figure 2.5.

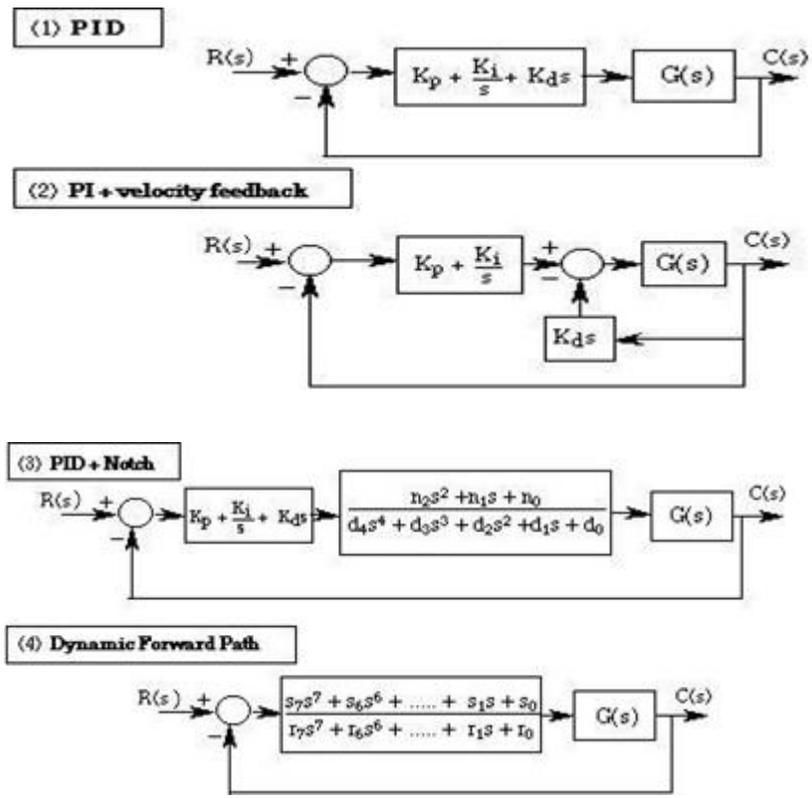


Figure 2.5: Available Closed-Loop System Configurations

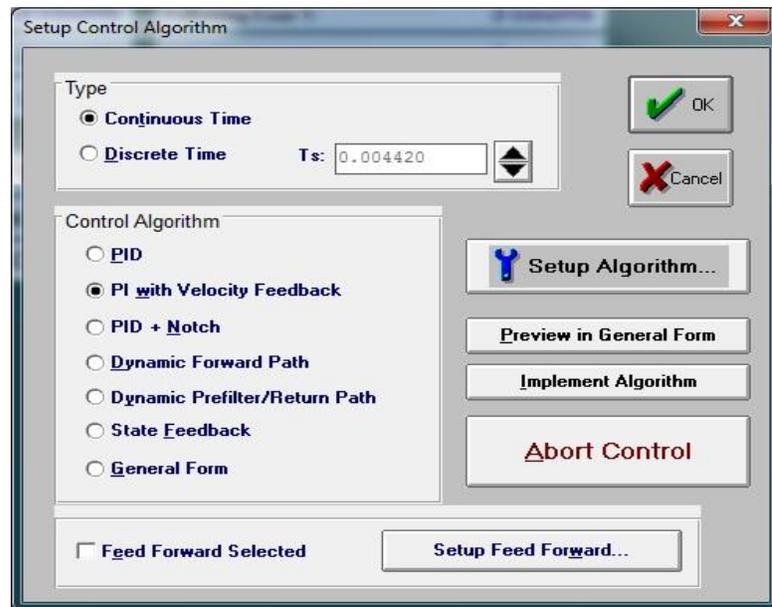


Figure 2.6: Control Algorithm selection screen

The selected configuration appears upon clicking on **Setup Algorithm**. For example the screen for the “PI+Velocity feedback” (default) configuration is shown in Figure 2.7.

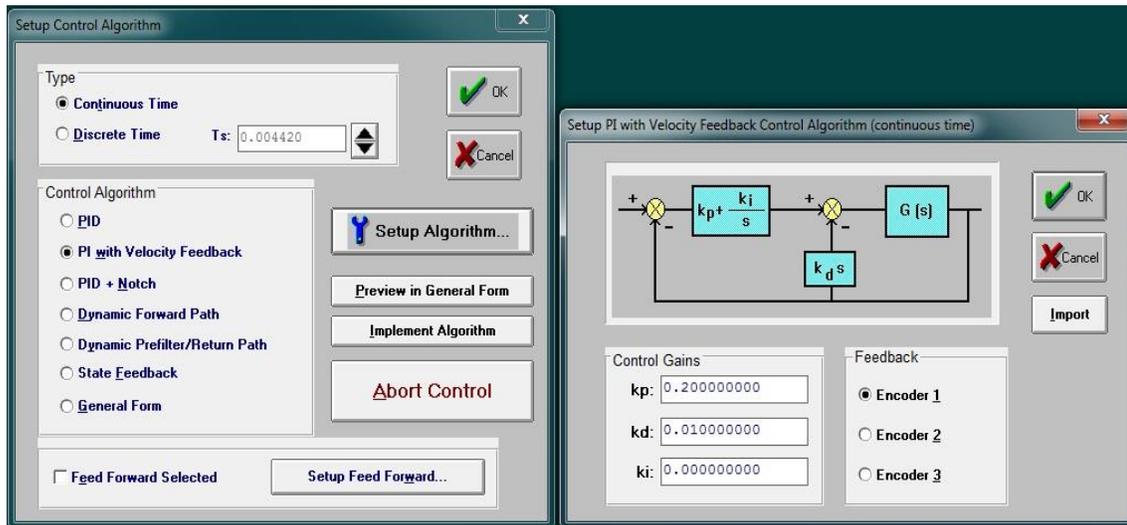


Figure 2.7: Setup an algorithm

After entering the gains (coefficients) in a particular configuration, clicking on **Implement Algorithm** will immediately setup the selected ‘control law’ on the real-time controller. However, although the loop-status indicates “closed”, control action will not start until **Run*** (under the **Command >> Execute** menu) is clicked.

The “Setup Control Algorithm” window also displays the sampling period T_s which is the actual mode used in the Model 220 equipment and is the inverse of the frequency at which data is sampled for discrete control. The minimum value of T_s is 0.000884 sec (corresponding to a maximum sampling frequency of approximately 1.1 kHz). In Lab equipment, the default value of $T_s = 0.00442$ sec (corresponding to ~ 226 Hz) is more than adequate since the maximum system bandwidth is less than about 10 Hz. Before the Run command, input **trajectory** and **data acquisition commands** must be specified. These are explained below.

NOTE: As mentioned earlier, the actual control implementation in the ECP Model 220 equipment is in discrete form. However, an equivalent ‘continuous’ control specification is incorporated in the system so that gain parameters may be entered in the s-domain, in order to be useful to students of classical control (as is the case with the present ELEC372 lab). Since the program has both discrete and continuous parameter setting options, the menu choices are many and mistakes can be made in setting parameters. **THEREFORE, STUDENTS ARE REMINDED TO USE ONLY THE CONTINUOUS DOMAIN SPECIFICATIONS AND PROCEDURES**, ie under ‘SETUP’, all that is needed is to check the “Continuous Time” button and then “Set Up Algorithm”, and then click on “Implement Algorithm” after setting the controller coefficients.

(3) Command has the pull-down options **Trajectory**, **Disturbance** and **Execute**:

Trajectory allows the specification of the input to be set up. **Counts** are used as the variables instead of radians or degrees. Seven input choices shown in Figure 2.8 are possible, of which only the Step (the default setting), Ramp, Sinusoidal and Sine-Sweep are used in this lab.

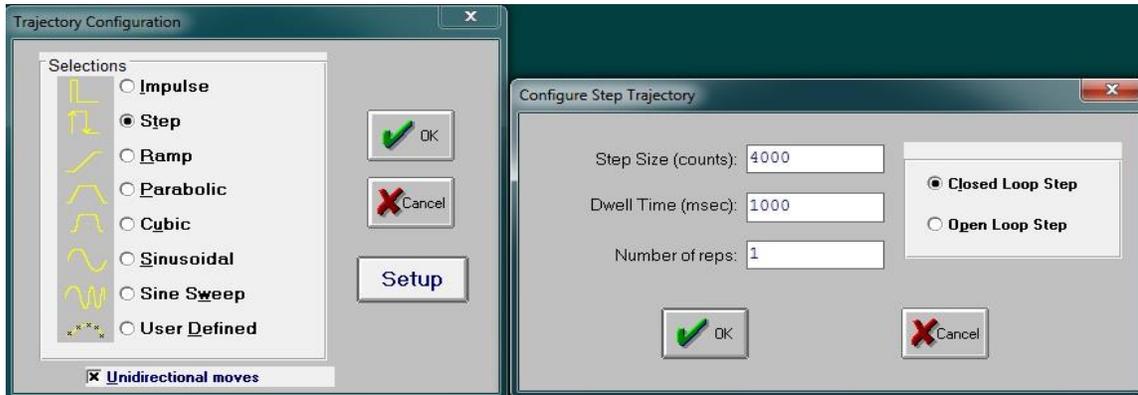


Figure 2.8: Available Trajectory

This menu item also allows the choice of an **open loop** or **closed loop** (default) system. Open loop mode is only available for impulse, step and sinusoidal inputs. If open loop mode is chosen, the input to be set will be in 'volts' and none of the coefficients of the blocks in Figure 2.5 will have any effect on the system response. The open-loop input (or "control effort") is the effective analog input to the amplifier driving the motor.

Disturbance basically allows the introduction of a disturbance signal via the 'disturbance motor' coupled to the load disk. Here, **Viscous Friction**, **Step**, and **Sinusoidal** disturbances are available. In particular, Viscous Friction provides a disturbance signal proportional to load disk angular velocity (sensed by Encoder #2) and its amplitude is entered in units of Volts/radians per second ($1 \text{ Volt/rad/sec} \equiv 0.5 \text{ Amp/rad/sec}$). The motor torque constant is **0.0832 Nm/Amp**. The load disk to disturbance motor coupling ratio is **1:4**.

Therefore, the equivalent viscous friction 'seen' at the load disk location, per 1 Volt/rad/sec input is: $0.0832 (0.5)/(0.25)^2 \text{ Nms/radian} = 0.6656 \text{ Nms/radian}$ of disturbance input. The viscous-friction disturbance can be considered as a part of the plant.

Disturbance 'Sample Data' must be checked if data needs to be plotted, saved or exported. The use of the other two check boxes is clear.

Execute allows the control action to be initiated by clicking on the **Run** button. The window contains three check boxes: **Sample Data**, **Include Viscous Friction** and **Include Step Disturbance**.

(4) Data has the options such as **Setup Data Acquisition**, **Upload Data**, and **Export Raw Data**.

Setup Data Acquisition allows the selection/deletion of commanded position and encoder position outputs (#1 and #2 only for Model220). The data gathering sample period, in terms of 'servo cycles' must also be entered. This period indicates the data sampling intervals as a multiple of the value of T_s set in the Control Algorithm setup.

Upload Data uploads allows any saved data into ECP Executive program.

Export Raw Data allows the currently acquired data to be saved as a text file (*.txt) which can be edited and exported to other programs such as MATLAB™ or Excel™. Note that the 'plot' files (*.plt) cannot be used outside ECP Executive program.

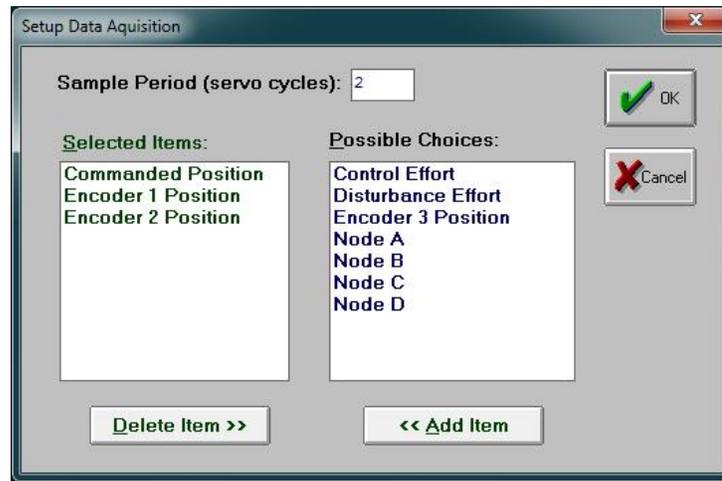


Figure 2.9: Setup Data Acquisition

(5) Plotting has many options related to the plotting of the input/output time functions of the system such as:

Setup Plot allows selecting of up to 4 data variables for plotting as shown in Figure 2.10: Setup Plot.

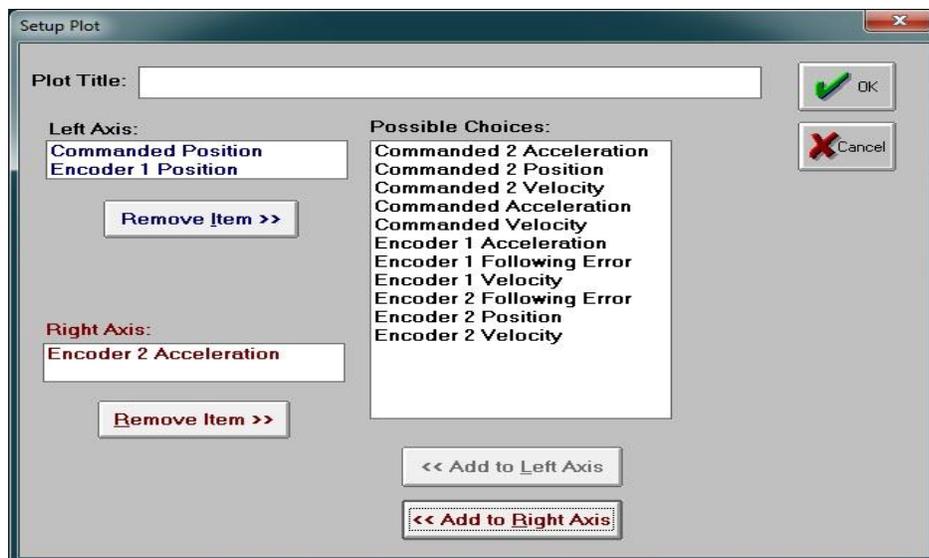


Figure 2.10: Setup Plot

Axis scaling allows the scaling of the selected plots so that parts of a plot may be examined in greater details.

Also, **Print data** loads plot data and prints data to a local printer if connected, and loads a saved plot file into the program, **save plot data** saves a plot data as a *.plt file which can only be internally used in ECP program.

(6) **Utility** has six options of which **Configure Auxiliary DACs** and **Rephrase Motor** are not applicable to the laboratory system. **Download Controller Personality File** is a maintenance/service item which is not to be used. **Jog Position** allows moving the turntables to a different commanded position. **Zero Position** resets the current position to zero. The **Reset Controller** option is very useful since it allows the controller to be reset after the loop has been opened due to an overload.

2.6 DATA FOR LAB REPORTS

2.6.1 PLOT FILE

Although not mentioned in the procedures, the displayed output plots should be included in your reports. Please note that the 'PLOT' files (*.plt) can only be used within ECP32 program. In order to allow students to incorporate the 'onscreen' experimental plots obtained in their reports, you may use the key PrintSc or Alt+PrintSc to capture the displayed screen, then use the tool 'Paint' to trim and save as a *.jpg file, which can be copied to a USB key, for subsequent use in preparing the lab report.

Note that after recording your data, delete all files that you created on the desktop or in the "my documents" folder; do not leave your data files stored on the lab computer.

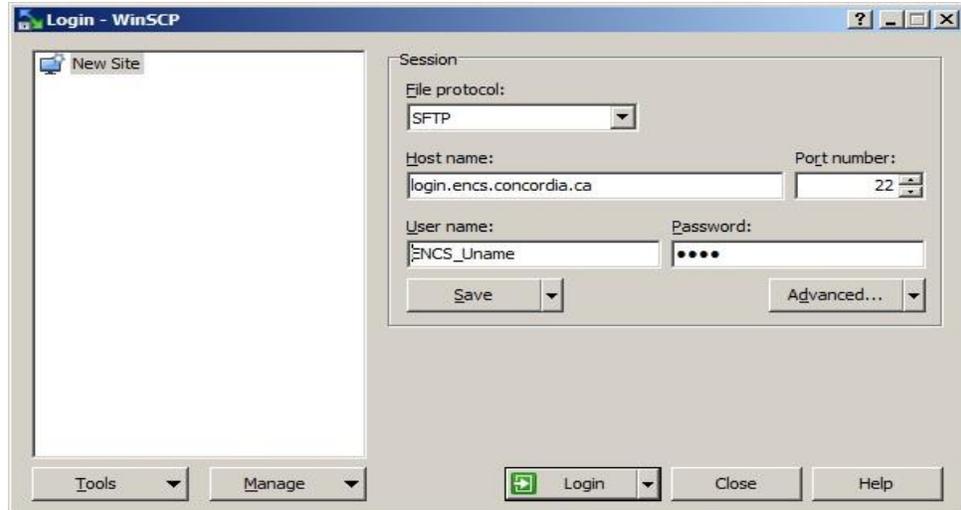
2.6.2 SAVE DATA

- 1) Save data on your own USB key;
- 2) Save data to your ENCS drives.
 - A. Mount ENCS drives. Click the icon of '**Map ENCS Drives**', the system shall run a script to map your ENCS network drives G: and U:. The log-in pop-up window is shown below:



Please use your ENCS account to log-on ENCS servers. For detailed information about these two network drives please refer to [ENCS helpdesk webpage](#).

- B. Use WinSCP directly. Click the icon of "**WinSCP**" on the desktop, input 'login.encs.concordia.ca' with your ENCS username, then click Login. A pop-up window is shown as the followed:



2.7 SAFETY PROCEDURES

The Model ECP220 has the potential of causing physical injury if certain precautions are not followed. It is therefore important to read the regulations and procedures given below and make sure that they are obeyed at all times!

- ✓ Follow the proper startup and shutdown procedures.
- ✓ Never 'run' the system without its plexiglass protective cover in place.
- ✓ Make sure that fingers, hair and loose items of clothes do not come into contact with the belts or with the turntables at all times.
- ✓ If you notice that any of the brass weights and/or belts are loose, report it immediately to the instructor. Do not attempt to make any changes or adjustment to the mechanism.
- ✓ If you see or hear the mechanism straining or making unusual sounds, immediately press the 'red' abort button on the control box and examine your parameter settings.
- ✓ Do not 'run' the mechanism continuously for long periods (i.e. keep the cycling periods small).

3 EXPT #1: FAMILIARIZATION WITH EXPERIMENT SYSTEMS

3.1 OBJECTIVE

- To become familiar with the lab equipment (ECP Model 220 system), software and the procedure to obtain typical system responses.
- To use MATLAB in control system application.

3.2 INTRODUCTION

3.2.1 ECP EXECUTIVE CONTROL PROGRAM

Please read Section 2 – “LABORATORY EQUIPMENT OVERVIEW” for a detailed introduction.

3.2.2 Open-loop and Closed-loop Block Diagrams

In this experiment, you will obtain open-loop and closed-loop responses of the position control system. First, we present the block diagrams and transfer functions of the open-loop and closed-loop systems.

Open-loop Block Diagram

The basic ‘rigid’ plant used in the lab system is equivalent to a rotational mass (total inertia of the turntable/motor system, J (kg.m²)) supported by bearings (assumed as ‘viscous friction’ B , N.ms/radian), driven by a servo DC motor.

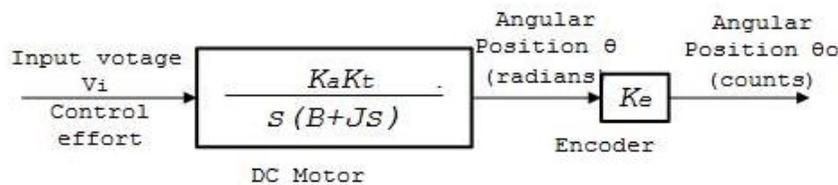


Figure 3.1: DC Motor Open-loop Diagram

$$K_t K_a V_i = J\ddot{\theta} + B\dot{\theta} \quad (3.1)$$

- K_t – torque constant
- K_a – trans-conductance gain
- J – total inertial of turntable system
- B - Viscous friction

From (3.1), the transfer function of the DC motor is:

$$\frac{\theta(s)}{V_i(s)} = \frac{K_a K_t}{s(B + sJ)} = \frac{K_m}{s(B + sJ)} \quad (3.2)$$

The angular position is measured using an encoder with the gain K_e , thus the overall transfer function for open-loop test is

$$G_p(s) = \frac{\theta_o(s)}{V_i(s)} = \frac{K_a K_t K_e}{s(B + sJ)} = \frac{K_m K_e}{s(B + sJ)} = \frac{K_o}{s(1 + \tau s)} \quad (3.3)$$

Where the open-loop gain $K_0 = K_a K_t K_e / B$ (counts/sec per volt) and $\tau = J/B$ (sec). From Equation (3.3), we obtain the angular velocity (counts/sec) as:

$$\omega(s) = \frac{K_0 V_i(s)}{1 + s\tau} \quad (3.4)$$

Closed-loop Block Diagram

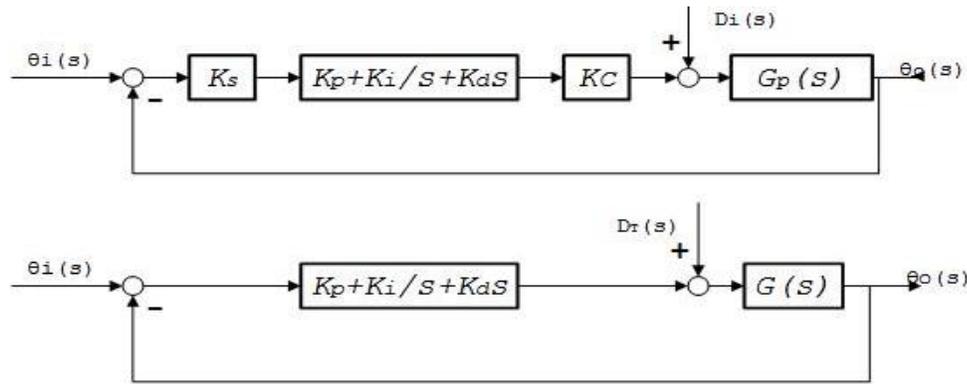


Figure 3.2: ECP 220 System Configuration

The block diagram of the closed-loop system (with a PID controller) is shown in the top diagram in Figure 3.2. In addition to the controller and plant $G_p(s)$, the diagram includes two gains: software gain K_s and D/A converter gain K_c . This block diagram can be redrawn as in the second diagram in Figure 3.2 where

$$G(s) = K_s K_c G_p(s) = \frac{K}{s(B + sJ)}$$

Here the product of the gains K_s and K_c , together with the motor-associated gains K_a and K_t and the encoder gain, are used to define the plant gain: $K = K_s K_c K_e K_a K_t$

The manufacturer-specified nominal values of the constituent factors are as follows:

- Controller Software Gain $K_s = 32$ Controller input counts/Encoder or reference input counts
- D-to-A Converter (DAC) Gain $K_c = 10 \text{ volts}/32,768 \text{ counts} = 3.05(10)^{-4} \text{ volts/count}$
- Encoder Gain $K_e = 16000 \text{ pulses(counts)} / 2\pi \text{ radians} = 2546.5 \text{ counts/radian}$
- Servo-amplifier Gain $K_a \approx 2 \text{ Amps / Volt}$
- Servomotor Torque Constant $K_t \approx 0.1 \text{ N-m / Amp}$

The nominal value of K , in the closed-loop configurations, is therefore:

$$K = K_s K_c K_e K_a K_t = (32) [3.05(10)^{-4}] [2546.5] (2) (0.1) = 4.97 \text{ or } K \approx \underline{5 \text{ Nm/radian}^*}$$

The nominal values of B and J will be discussed in Experiment #2.

3.2.3 MATLAB

1. MATLAB

MATLAB® is a high-level language and interactive environment for numerical computation, visualization, and programming. Using MATLAB, you can analyze data, develop algorithms, and create models and applications. You can use MATLAB for the applications of control systems, testing, and measurement. MATLAB is widely used in control system analysis, design, and simulation.

2. CONTROL TOOLBOX

Control System Toolbox™ provides industry-standard algorithms and apps for systematically analyzing, designing, and tuning linear control systems. You can specify your system as a transfer function, state-space, pole-zero-gain, or frequency-response model. Apps and functions, such as *Step* and *Bode*, let you visualize system behavior in time domain and frequency domain. You can tune compensator parameters using automatic PID controller tuning, Bode loop shaping, root locus method, LQR/LQG design, and other interactive and automated techniques. You can also validate your design by verifying rise time, overshoot, settling time, gain and phase margins, and other requirements.

Useful Functions

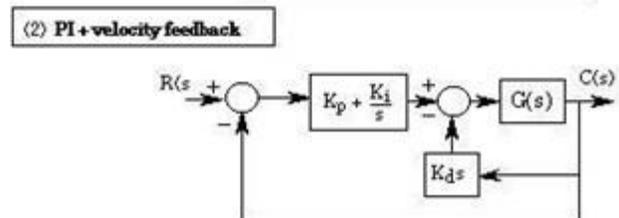
- *tf* - Create transfer function model, convert to transfer function model.
- *pid* - Create PID controller in parallel form, convert to parallel-form PID controller.

References

For more detailed information, please refer to **MATLAB Control System toolbox** website, <http://www.mathworks.com/help/control/index.html>

3.3 ECP MODEL 220 SYSTEM

In this part, basic operational procedures are followed in order to gain familiarity with the features of the ECP Model 220 system. The default closed-loop “PI+Velocity Feedback” configuration #2 will be used to illustrate various measurements. In section 3.5 we will do experiment with open-loop configuration.



1. Initializing and Selecting Units

From the UTILITY menu, select “Reset Controller”. This will set all encoder counts to zero [If “Counts” are not selected, go to USER UNITS under “Setup” and select COUNTS. (16000 Counts = One 360° revolution) Counts will be used in all the experiments. With COUNTS selected, all displayed output magnitudes will be in terms of Counts for position or Counts/sec for velocity.

2. Setup Data Acquisition

From the DATA menu, select the menu “Setup Data Acquisition” and make sure that Commanded Position and Encoder #1 Position are on the list. Select Sample Period = 2 (This implies that data will be collected every second servo cycle, i.e. at intervals of $2T_s$).

3. Setup Control

“Set Up Control Algorithm” window, under which CONTINUOUS TIME, $T_s = 0.00442$ sec and “PI with Velocity Feedback” have already been selected. Click on SETUP ALGORITHM. This will display the relevant control schematic with the preselected gains $K_p = 0.2$, $K_d = 0.01$ and $K_i = 0$. Then click on IMPLEMENT ALGORITHM and OK. This downloads the selected control law to the controller.

Note: ‘Implement’ will always reset the controller unless inconsistent values are set or the loop is opened. The closed-loop system in configuration #2 is now ready for an input command.

4. Choose the system input command

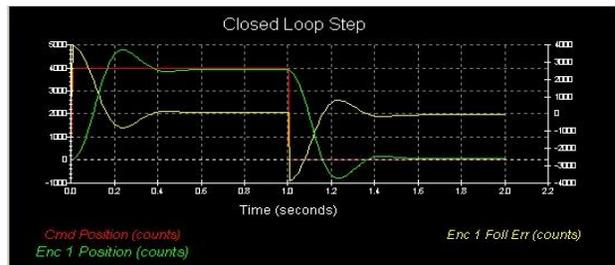
From the COMMAND menu, select “Trajectory” and from the “Trajectory Configuration” window, select STEP (default setting) and then click on “Set Up”. Select CLOSED LOOP. This will display the default Step input parameters: STEP SIZE 4000 Counts, DWELL TIME 1000mS, and Number of Repetitions 1.

5. Execute the command

From the COMMAND menu, select “Execute Trajectory” under which check only NORMAL DATA SAMPLING. Then click on RUN. This will initiate the control action. Wait for the data acquisition to be completed, that is, until the (“Upload Successful 100%”) message appears. Then click OK.

6. Plot the input and output of the step response

From the PLOTTING menu, select “Setup Plot”. Choose for the Left Axis, the variables Commanded Position and Encoder #1 Position. Choose Encoder #1 Following Error for the right axis. Then click on the PLOT DATA button at the lower right hand side of the window. A plot similar to the one shown below should appear.



RESULTS & QUESTIONS

Note how the error varies in the opposite direction of the output and approaches zero in the steady state.

7. Save a copy of the plot for your report

First maximize the display to ‘full screen’ by clicking the ‘maximize’ icon at top right. Press the key of PrintSC or Alt+PrintSC, then paste the image to Paint to save the image as a *.jpg file, on the desktop, after giving it a name. (This image file can be manipulated using Windows Paint™ for your report. Among other manipulations, it is most useful to ‘invert colors’, so that the image is saved and printed using a white background, which will not consume large amounts of printer toner or ink). This

procedure for saving plots for your report must be used in all subsequent examples in this experiment as well as in the remaining experiments.

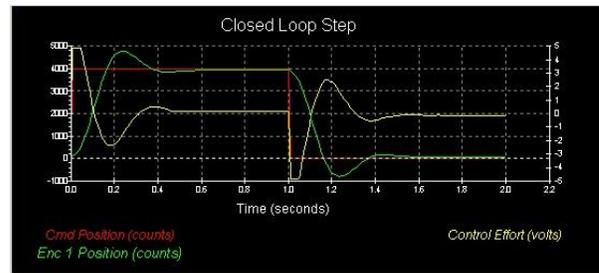
8. Scale the plot for better readability

From the PLOTTING menu -> axis scaling, change the scale of the plots using left/right axis range and horizontal axis.

9. Display the 'Control Effort'

Repeat Step 2 above to add 'Control Effort' (CE) to the list of available variables. Then **repeat** Step 6 above with the 'Control Effort' chosen as the Right Axis variable, instead of the Encoder #1 Error. Then RUN the system with the default step input and then click on the PLOT DATA button.

A plot similar to the one shown below should appear.



RESULTS & QUESTIONS

Note how the CE, which is the input to the servomotor, varies in a manner similar to that of the error, but anticipates the output variation with an observable lead time. The CE is the input whenever the system is operated in the open-loop mode.

3.4 PLOT DATA WITH MATLAB

3.4.1 EXPORT RAW DATA

ECP software can export raw data, it allows the currently acquired data to be saved as a text file (*.txt), which can be edited and exported to MATLAB™.

To get raw data, after collecting data:

- Choose 'Export Raw Data' from the Data menu.
- Save your data as a text file in the MATLAB bin folder. Give it a name pertaining to your data, like "sinesweep220".
- Using Windows Explorer, change the extension on your file from '.txt' to '.m'. Moreover, to change from '.txt' to '.m' you may rename the file and change '.txt' to '.m'.
- Open your m-file in MATLAB for editing.

Change the top and bottom of your file like the example below:

```

% Sample Time Commanded Pos Encoder 1 Pos Encoder 2 Pos
Comment out this line.
Add this.
data=[ 0 0.009 0.000 0 0 20 20 6; 6;
1 0.009 0.000 0 0 20 20 6; 6;
2 0.018 0.000 0 0 20 20 6; 6;
3 0.027 0.000 0 0 20 20 6; 6;
.
.
.
3332 29.502 -500 61 37;
3333 29.511 -373 -10 15;
3334 29.520 -96 -70 -12;
3335 29.529 216 -88 -37];
Don't forget the semi-colon here!

```

The following is a sample code to plot the data. You can copy the sample code into an m-file.

```

time = data(:,2); %read Time
y=data(:,4); %set Encodel Pos as y
For u=data(:,6); % Control Effort as input
plot(time, y); %Plot data

```

`u=data(:,6)`, based on the obtained raw data, you have to change the value 6. For example, you could change it to 4 or 5. Compare the plots in Matlab with the screenshot on ECP Executive, try to adjust the parameters of the function 'plot' to make its output close to ECP format.

3.5 OPEN-LOOP TEST AND SIMULATION

In this section we obtain the step response of the open-loop DC motor, first using Matlab simulation then using lab test on the motor. Then we will compare the result.

3.5.1 Matlab Simulation

As an example, set the physical constants as:

```

K = 5.0; % Plant gain
B = 0.002; % Viscous friction (N.m.s/rad)
J = 0.0043; % kg.m^2
s = tf('s');
dcm_s = K/(J*s+B); % Speed (counts/s)
dcm_p = dcm_s/s; % Position (counts)

```

To see the transfer function:

```

>>dcm_s
>>dcm_p

```

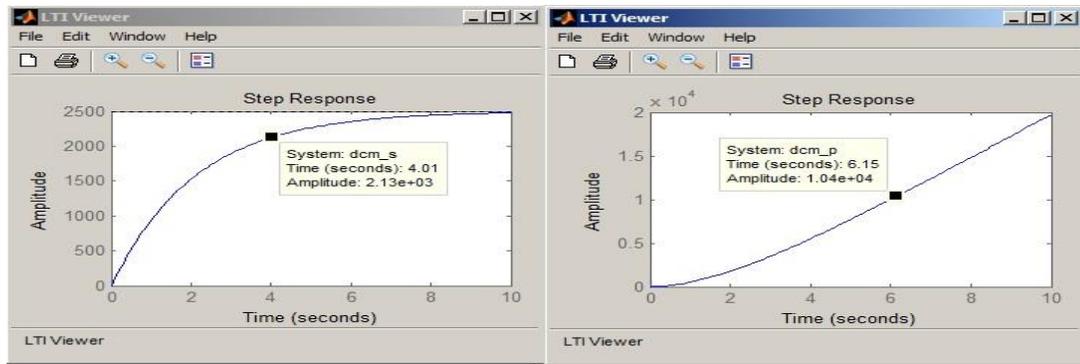
To see the step response (speed and position) to step voltage input use:

```

ltiview('step',dcm_s, 0:0.1:10);
ltiview('step',dcm_p, 0:0.1:10);

```

Then you can see a similar display as follows:



Also, with right-click on the plot, click "Plot Types", you can change the input types.

3.5.2 VERIFICATION ON THE EQUIPMENT

Now we obtain the step response of the open-loop system.

1. Run ECP program. Under 'Data Acquisition' menu, make sure that Control Effort (CE) has been added to the list. Set up the 'plot' to display the Encoder #1 Position on the left axis and the CE on the right axis.

2. Reset the controller from the Utility menu. From the Control Algorithm menu, implement the PID with the following settings:

$$T_s = 0.00442 \text{ sec}, \quad K_p = 1 \quad K_i = 0 \text{ and } K_d = 0.0$$

3. Obtain the **open-loop** step response. From the COMMAND menu, select "Trajectory" and from the "Trajectory Configuration" window, select STEP (default setting) and then click on "Set Up". Select OPEN LOOP: Step Size of 0.4v, Dwell Time of 5000 ms, and number of Repetitions 1.

4. Go to 'Execute' to run the test, and display the plot. Use axis-scaling to display only the section of the response within the dwell period of 5 seconds to make the display appear as a 'step response'. Note that instead of unit step input 1.0v used in simulation, we used 0.4v input to avoid exceeding the motor speed safety limits.

5. To see the velocity response, set up the 'plot' one more time to display the Encoder #1 Velocity on the left axis and the CE on the right axis. Then plot the data.



5. Compare the obtained results with the one from 3.5.1.

4 EXPT #2: SYSTEM IDENTIFICATION

4.1 OBJECTIVE

- To determine the parameters (J, B and K) of a mechanical first-order system and calculate the system model.
- To illustrate the basic principles of system identification using open-loop and closed-loop response.
- To verify the system modeling by using MATLAB functions.

4.2 INTRODUCTION

4.2.1 SYSTEM PARAMETERS

ECP 220 system has the general block diagram shown in Figure 4.1 again, in which, the PI+V controller has been chosen as an example.

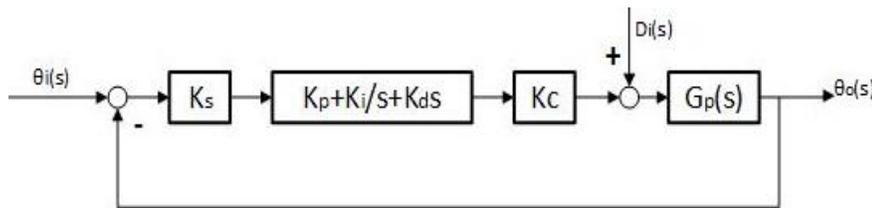


Figure 4.1: A closed-loop configuration

In the above closed-loop configurations, the nominal value of closed-loop forward-path gain K is discussed in Experiment #1:

$$K = K_s K_c K_e K_a K_t = (32) [3.05(10)^{-4}] (2) (0.1) [2546.5] \approx \underline{5 \text{ Nm/radian}^*} \quad (4.1)$$

***Notes:** The values of K_a and K_t vary from unit to unit and the variation in the actual value of K is $\pm 20\%$

The actual values of J and K specific to each unit will be found in this Experiment. The “PI + velocity feedback” configuration (see Figure 4.1 above), which is also the ‘default’ configuration, will be used since it allows good control of closed-loop system parameters.

4.2.2 THEORETICAL ESTIMATION OF ROTATIONAL INERTIA J

Since the feedback loop is closed around Encoder #1 in the laboratory system, the J and B in the system equations must be values ‘reflected’ to the location of encoder #1. The arrangement of the belt and pulley coupling between the disks and the drive motor (shown earlier in this manual) is shown schematically in Figure 4.2: Plan Rotation Inertia. Assuming ‘ideal coupler’ or ‘transformer’ relations, it can be shown that for gears or for toothed-belt and pulleys, the coupling ratio is $\mathbf{n} = \omega_p/\omega_s = \theta_p/\theta_s = N_s/N_p$ where N is the number of teeth and ‘p’ and ‘s’ refer to primary (driving side) and secondary (driven side). Thus, in following Figure 4.2, the overall coupling-ratio is $\mathbf{n} = \omega_1/\omega_2 = \theta_1/\theta_2 = \mathbf{n}_1 \mathbf{n}_2 = [N_{\text{bottom}}/N_D] [N_L/N_{\text{top}}] = (24/12) (72/36) = (2)(2) = 4$. Furthermore, an inertia J or friction B on the secondary side will appear to the primary-side as being multiplied by $(1/\mathbf{n}^2)$. Thus, the total effective inertia at the Encoder#1 location can be expressed as:

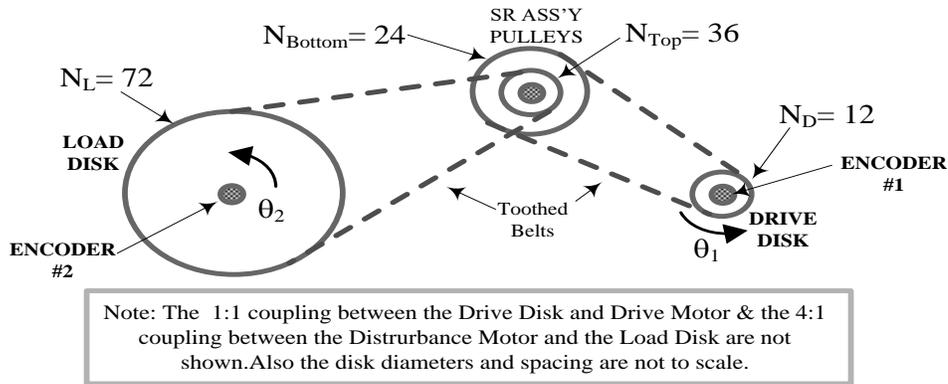


Figure 4.2: Plan Rotation Inertia

$$J = (J_D + J_{WD}) + \frac{J_{SR}}{(n_1)^2} + \frac{J_L + J_{WL}}{(n_1 n_2)^2} \quad (4.2)$$

where the subscripts D, L and SR refer to the drive, the load and the SR disks and the additional subscript w refers to the additional inertia provide by the weights fixed to the drive and load disks. The inertias J_D , J_L , and J_{SR} are specified by the manufacturer as:

- Inertia of the bare drive disk $J_D = 4(10)^{-4} \text{ kgm}^2$
- Inertia of the bare load disk $J_L = 65(10)^{-4} \text{ kgm}^2$
- Inertia of the SR assembly $J_{SR} = 78(10)^{-6} \text{ kgm}^2$

(Including top and bottom pulleys, backlash device and screws)

The inertias J_{wD} and J_{wL} must now be calculated: The nominal mass (m) values of the small and larger [diameters 32mm and 50mm respectively] brass weights are 200gm and 500gm respectively. When symmetrically located at a radius R on the disks, their moment of inertia can be calculated as $J_w = mR^2$ at the appropriate location. It is assumed that the small and large weights will be used on the drive and load disks respectively. Further, it is assumed that four identical weights will be used symmetrically on each disk. Since the nominal radii of the drive and load disks are 67mm and 128mm respectively, the radius can be deduced with reasonable accuracy when the masses are moved outwards so that their outside edges are flush with the outside edges of the disks, as seen in *Figure 2.2: Rotational-motion Assembly* of this manual. With the weights permanently bolted at the extremes as explained, the inertia values J_{wD} and J_{wL} are:

$$J_{wD} = 4 (0.2) [0.067 - 0.016]^2 = 2.08(10)^{-3} \text{ kgm}^2$$

and

$$J_{wL} = 4 (0.5) [0.128 - 0.025]^2 = 2.122(10)^{-2} \text{ kgm}^2$$

Equation (3.5) can now be used to calculate the total effective inertia J at the Encoder#1 location as:

$$\begin{aligned} J &= (J_D + J_{wD}) + J_{SR}/(n_1)^2 + (J_L + J_{wL})/(n_1 n_2)^2 \\ &= 4(10)^{-4} + 2.08(10)^{-3} + (78/4)(10)^{-6} + [65(10)^{-4} + 2.122(10)^{-2}]/16 \\ &= \underline{\underline{4.23(10)^{-3} \text{ kgm}^2}}. \end{aligned}$$

Note that the largest contribution to J is made by the added brass weights. Also note that the value of J will vary somewhat from unit to unit.

4.2.3 MATLAB IDENTIFICATION TOOLBOX

System Identification Toolbox™ provides MATLAB® functions, Simulink® blocks, and an app for constructing mathematical models of dynamic systems from measured input-output data. It lets you create and use models of dynamic systems not easily modeled from first principles or specifications. You can use time-domain and frequency-domain input-output data to identify continuous-time and discrete-time transfer functions, process models, and state-space models. More information, please visit its [website](#).

Useful Function [tfest](#) - Transfer function estimation and the System Identification Tool GUI - [ident](#).

4.3 PLANT PARAMETER AND SYSTEM MODELING

In this experiment, open-loop tests are performed on the DC motor (plant) to obtain parameters of its transfer function, since the transfer function of the plant is required for analysis of the closed-loop system.

4.3.1 EVALUATION OF J AND K USING OPEN-LOOP VELOCITY OUTPUT

PRELIMINARY

In this experiment, the acceleration α_1 developed in response to a step voltage V_i is measured. Next, the inertia is increased by a known amount ΔJ and the acceleration α_2 developed in response to the same step voltage is measured. The step magnitude is selected to provide rapid observable acceleration so that the friction torque may be neglected and the torque equation $T \approx J \alpha$ may be used. Since only the partial gain product $K_a K_t K_e$ is involved, we have:

$$(V_i) \{ K_a K_t K_e \} = J \alpha_1 = (J + \Delta J) \alpha_2 \quad (4.3)$$

Where the acceleration α is expressed in counts/sec² and $\alpha_1 > \alpha_2$. If ΔJ is known (as it is, see Step 4 in the Procedure below), J can be determined from the equation

$$J = \left(\frac{\alpha_2}{\alpha_1 - \alpha_2} \right) \Delta J \text{ kgm}^2 \quad (4.4)$$

PROCEDURE:

- 1) Reset the controller from the UTILITY menu. Set up the 'plot' to display Encoder #1 Velocity only on the left axis. Under 'Data Acquisition' menu, set the sampling period to 5 (ie data to be collected every 5th cycle, = 5 (4.42 ms) \approx 22ms which is done to reduce the noise inherent in acquiring the velocity signal).
- 2) From the COMMAND menu, select 'Trajectory', STEP and then click on 'Setup'. Then select OPEN LOOP, Step Size 2 volts, Dwell time 500 ms, and number of Repetitions 1. Next, go to Execute and RUN the test. After the data has been acquired, plot the output. The trace will be similar to the one shown below. (The initial linear part of the curve denotes constant acceleration). Overload occurs

at approximately 0.5 sec when the step reverses and the 'overload' circuit will disable the system at this point.

- 3) Determine* the slope of the initial linear part of the velocity plot, without using any axis scaling. This is the acceleration α_1 in Counts /sec² which results in response to the step input voltage $V_i = 2$ volts.

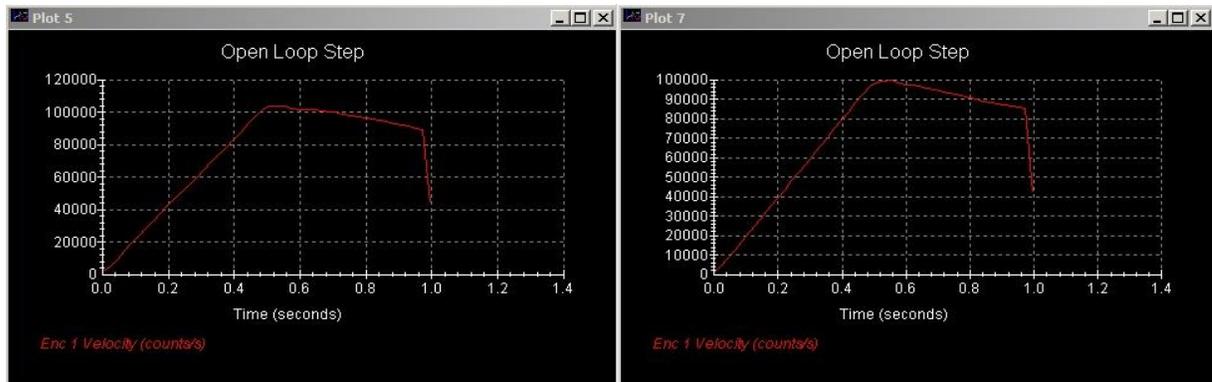
(*Read the note at the beginning of the experiment about making preliminary calculations)

- 4) Making sure that the system is still disabled, loosen the cover screws and lift off the plexiglass cover. Carefully insert the additional 69mm diameter brass weight (supplied) in between the four fixed 0.2 kg weights on the drive disk so that it fits in snugly. Make sure that the pins on the weight fit into the radial slots on the disk, and then carefully replace the plexiglass cover.

(**Note:** The extra weight added has been calculated to increase the net inertia effective at the drive disk axis by the amount $\Delta J \approx 0.000494$ kg.m² for all stations)

- 5) Repeat Steps 1, 2, and 3 above with the extra weight installed. Determine the acceleration obtained with the added weight in place, as α_2 (Note that $\alpha_2 < \alpha_1$). Finally, switch off the controller box, remove the added weight, replace the cover and lightly re-tighten the cover screws.

Two typical open-loop velocity responses obtained, without and with the added weight are seen in the photograph shown below, in 'background' and 'foreground' traces respectively.



RESULTS

Using Equation (4.4), determine the value of J and compare the value obtained with the calculated nominal value given in sections (4.2.1) and (4.2.2) and find the % error.

Using the determined value of J , find $K_a K_t K_e$ from the equation $2K_a K_t K_e = J\alpha_1$, Equation (4.3). Multiply this value by $K_s K_c$ to obtain K (see section 4.2.1) for the equipment at your lab station.

From data given in introduction,

$$K_s K_c = (10/32768) (32) \approx 0.009766 \text{ Volts/count.}$$

Record the determined values of **J** and **K** found in this part of the experiment.

4.3.2 EVALUATION OF J AND K USING OPEN-LOOP POSITION OUTPUT

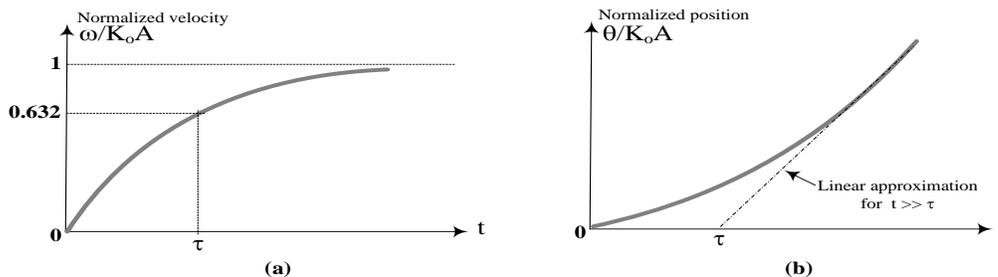
PRELIMINARY

The time responses, $\omega(t)$, and $\theta(t)$ of the system are readily obtained by finding the inverse Laplace transforms of $\omega(s)$ and $\theta_o(s)$, respectively, for any given $V_i(s)$. For an input step voltage magnitude of A volts, $V_i(s) = A/s$, after performing the inverse transformation we obtain:

$$\omega(t) = \mathcal{L}^{-1}\{K_o A/s(1+s\tau)\} = K_o A[1 - e^{-t/\tau}]$$

and
$$\theta_o(t) = \mathcal{L}^{-1}\{K_o A / s^2(1+s\tau)\} = K_o A [t - \tau + \tau e^{-t/\tau}] \quad (4.5)$$

where the open-loop gain $K_o = K_a K_t / B$. These two step responses are shown below, in *normalized* form, $(\omega/K_o A)$ and $(\theta_o / K_o A)$ in following figures (a) and (b) respectively.



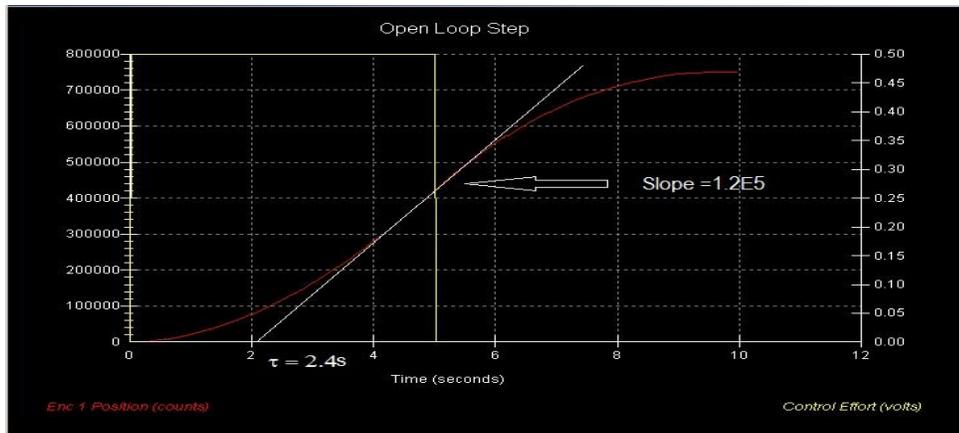
For the angular velocity output, the response is of the classic 'rising exponential type with $\omega(t)$ approaching $K_o A$ for large t and the response reaching $0.632 K_o A$ at $t = \tau$. For the angular position output in equation (4.5), a linear approximation may be made by drawing a tangent to the curve for large t : This tangent will intersect the time axis ($\theta = 0$) at $t = \tau$. The slope of the tangent is $K_o A$ (radians/sec). The latter response will be used in Experiment #2 to evaluate the 'plant' parameters in the laboratory system.

In this test, a smaller step voltage V_i is used as input and the position output is measured. Attempting to use an input that appears as a 'step', however, will trigger the built-in 'overload' circuit which will automatically 'abort' the test. Therefore, a small magnitude 'bounded' step is used which will tend to make the output 'converge' to a finite value, and half of the response time period can then be taken to correspond to Equation (3.8). It is easily seen that a linear approximation of the above response has a slope S given by $K_o V_i$ (i.e. $= K_a K_t K_e V_i / B$) and the straight-line describing this linear approximation will intercept the x-axis (time-axis) at $t = \tau = J/B$. Thus, measurement of the slope S and the time-axis intercept τ may be used to find both J and B .

PROCEDURE

- 1) Under 'Data Acquisition' menu, make sure that Control Effort (CE) has been added to the list. Reset the controller from the UTILITY menu. Set up the 'plot' to display the Encoder #1 Position on the left axis and the CE on the right axis.
- 2) From the COMMAND menu, select 'Trajectory', STEP and then click on 'Set Up'. Then select OPEN LOOP, Step Size **0.5** volts, Dwell time 5000 ms, and number of repetitions 1. Next, go to "Execute" and RUN the test. After the data has been acquired, plot the output. The trace will be similar to the one shown below. (The first half of the response, 0 to 5 sec, is due to the positive step). Of course, the slope and intercept values will have some variation depending upon the station equipment.

The straight-line approximation (the line is tangential to the S-shaped curve at midpoint, approx. 5sec.) has been inserted in the plot shown below. Determine* the slope S of the line (in Counts/sec) and the time-axis intercept τ (sec).



RESULTS:

From the displayed slope S (in counts/sec), determine*

$$S \text{ (radians/sec)} = S \text{ (counts/sec)} / K_e$$

$$= S \text{ (counts/sec)} / 2546.5 = 3.927(10)^{-4} S \text{ (counts/sec)}$$

Since $V_i = 0.5$ volt, $S \text{ (radians/sec)} = K_a K_t V_i / B = (2) (0.1) (0.5) / B$

Hence, determine

$$B \text{ (Nms/radian)} = \frac{0.1}{S \text{ (radians/sec)}} = \frac{256.65}{S \text{ (counts/sec)}}$$

From the displayed time-axis intercept, determine the time-constant $\tau = J/B$ from x-axis intercept. Finally determine J :

$$J \text{ (kg.m}^2\text{)} = B\tau$$

Record the determined values of J and B found in this part of the experiment. Compare the value of J found with the value determined in section 4.3.1 and obtain the average value. Compare the average value of J with the calculated nominal value given in section 4.2.2 and find the percentage error.

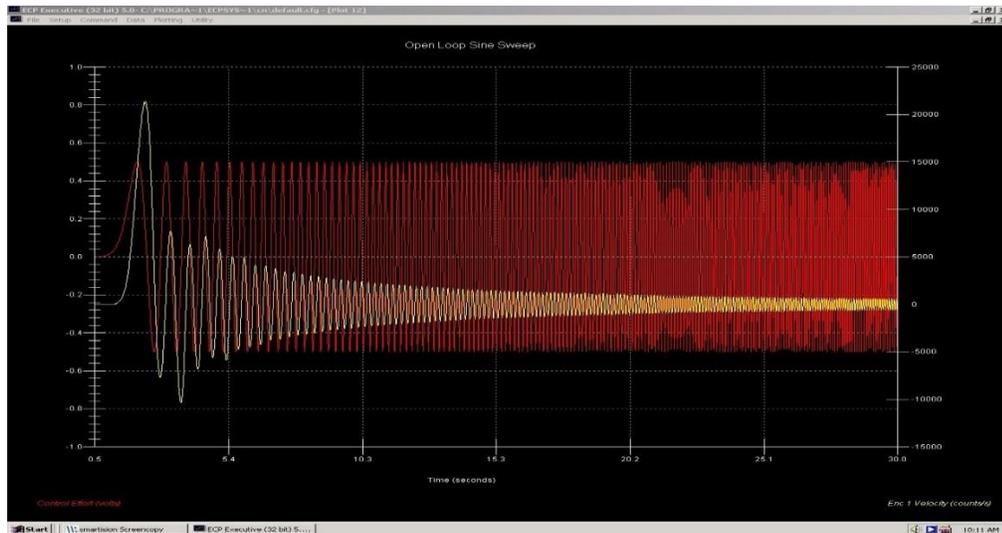
Record the average value of J , and the values of B and K obtained, these values are to be used in subsequent lab work.

4.3.3 SYSTEM IDENTIFICATION VIA THE OPEN-LOOP RESPONSE TO A SINE SWEEP INPUT

The system position output $\theta_o(s)$ is given by Equation (4.5), shown the Figure 4.3. As mentioned in the description of the system, selecting 'open loop' under the Trajectory Setup menu allows a voltage input to be applied to the plant. Among the inputs, the step and sinusoidal inputs are available for open-loop tests.

Here sinusoidal signal is chosen to evaluate the system parameters.

- 1) Set up the controller. Under the Set-up menu, set $T_s=0.00442\text{sec}$ and select Continuous Time Control. Select PI With Velocity Feedback and Set-up Algorithm. Enter the $k_p = 1$ and $k_d = 0$, $k_i = 0$ and select Implement Algorithm, then OK.
- 2) Under Setup Plot, choose the Control effort (CE) to be displayed on the Left axis and Encoder#1 Velocity to be displayed on the Right axis (If the CE is not available, it should be added to the list using the Data Acquisition setup menu).
- 3) From Trajectory, choose sinusoidal linear sweep input of 0.1 to 10 Hz, 0.5 volt, and sweep time of 20 sec, and choose Open Loop mode, choose Open Loop mode. Then RUN the system. A plot similar to the one seen below should result.



- 4) Export raw data to a file. From the menu DATA, choose "Export Raw Data", name the data file, e.g. *raw_data_freq.txt*, and then you can transfer data file to MATLAB. More details to see part 2.6.2. Modify the raw data file *raw_data_freq.txt* to a MATLAB m-file separately.
- 5) Load it into MATLAB workspace. Try to use the functions, e.g. 'iddata', 'tfest' of MATLAB System Identification Toolbox, to obtain DC motor first order and second-order transform functions.

RESULTS

Compare the results from MATLAB and the model obtained from experiment.

```
>> time = data(:,2); %read Time
>> y=data(:,4);      %set Encoder1 Pos as y
>> u=data(:,6);      % Control Effort as input
>> dy= diff(y);      %We need speed as Output
>> dy(end+1) = dy(end); %restore sector size to N
>> zf = iddata(dy,u,0.00884); %set Object iddata
>> tf1 = tfest(zf,1,0) ; %for First order
```

4.3.4 SYSTEM IDENTIFICATION VIA CLOSED-LOOP SYSTEM RESPONSE

PRELIMINARY

In the Figure 4.1, $G(s) = \frac{K}{s(B+Js)}$, set $K_i=0$, then the closed-loop transfer function (CLTF) will be:

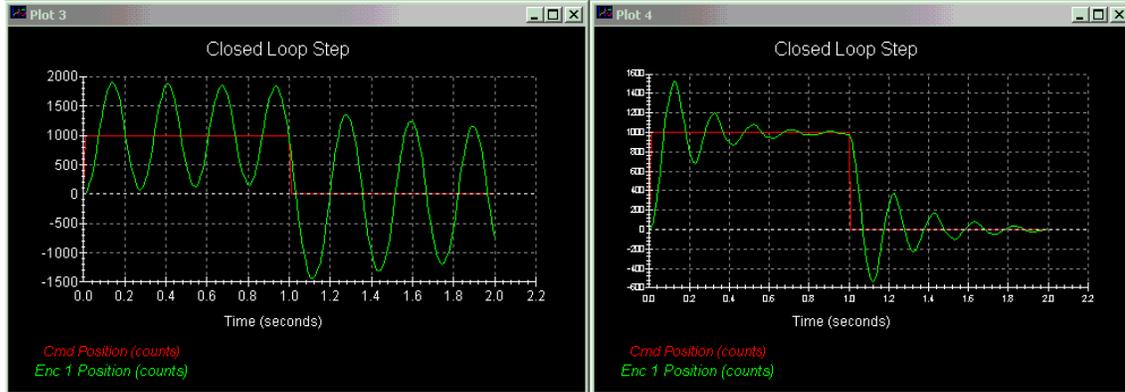
$$T(s) = \frac{KK_p}{Js^2 + (B + KK_d)s + KK_p} \quad (4.6)$$

When set $K_p=1.0$ and $K_d=0$, the system output will be highly oscillatory. In this case, set a value, e.g. $K_d=0.01$, just after data acquisition is complete. Click on Plot and view the waveform. If the waveform is good, the raw-data could be save into a file for MATLAB analysis.

Procedure:

- 1) Set up the controller. Under the Set-up menu and set $T_s=0.00442$ s and select Continuous Time Control. Select PI With Velocity Feedback and Set-up Algorithm. Enter $K_p=1$, $K_d=0$, and $K_i=0$ and select Implement Algorithm, then OK.
- 2) Go to Set up Data Acquisition in the Data menu and select encoder #1, Commanded Position as data to acquire and specify data sampling every 2 servo cycles. Select Zero Position from the Utility menu to zero the encoder positions.
- 3) Under Setup Plot, choose both Commanded Position and Encoder#1 Position to be displayed on the left axis.
- 4) Enter the Command menu, go to Trajectory and select Step. Select Closed Loop Step and input a step size of 1000 counts, duration of 2000ms and 1 repetition. Select Execute from the Command menu and select Run. The drive disk will step, oscillate, and attenuate, then return. Encoder data is collected to record this response. Select OK after data is uploaded.
- 5) Click on Plot and view the waveform. If the data is not satisfactory, repeat the above steps or modify K_p and K_d if necessary.
- 6) Export raw data to a file. From the menu DATA, choose "Export Raw Data", name the data file, e.g. *raw_data_cl_step1.txt*, then you can transfer data file to MATLAB. See the section 2.6.2 for details.
- 7) Enter the Control Algorithm box, enter the $K_p = 1$ and $K_d = 0.01$, $K_i = 0$ and run steps 4-6 again, save another data file.
- 8) Convert the raw data files, *raw_data_cl_step1.txt* and *raw_data_step2.txt*, to a MATLAB m-files.
- 9) Load it into MATLAB workspace. Try to use the functions of MATLAB System Identification Toolbox, such as '*iddata*', '*tfest*', to obtain the second-order transfer functions of the closed-loop system
- 10) Then calculate the DC motor first-order transfer function $G(s)$ (K , J and B).

```
>> time = data(:,2); %read Time
>> y=data(:,4);      %set Encode1 Pos as y
>> u=data(:,3);      % Control Position as input
>> zf = iddata(y,u,0.00884); %set Object iddata
>> Tfd2 = tfest(zf,2,0); % for second order
```



RESULTS

- 1) Calculate system the open-loop transfer function (OLTF) with the determined values of K, J and B from open-loop tests in section 4.3.2 and 4.3.3.
- 2) Obtain the OLTF in MATLAB by the data of the closed-loop test., then calculate K, B and J.
- 3) Compare these models.
- 4) Write a brief summary about how the lab equipment might facilitate a better understanding of control systems.

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5 EXPT #3: IMPROVING SYSTEM PERFORMANCE

5.1 OBJECTIVE

- To study how to improve the system performance by PD, PI and PID control.
- To learn how to eliminate the steady state error caused by a disturbance input.

5.2 INTRODUCTION

5.2.1 PID-CONTROL

In the first part of this experiment, improvement in the steady state response by means of proportional-integral (or PI) feedback is investigated, together with the subsequent extension to Proportional-Integral-Derivative (PID) control. The effectiveness of PI control in reducing or eliminating the output-offsetting effect of a 'disturbance' signal is also demonstrated. And finally, a PID-control configuration exhibiting an 'optimum' performance selected by the student is set up.

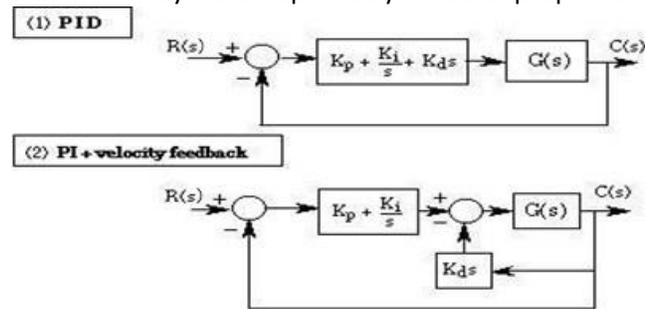


Figure 5.1: Closed-loop Configuration

The principle behind proportional-integral feedback is to increase the control effort (CE) with the objective of reducing or eliminating the steady state output offset, the added effort being obtained by *integrating* the error signal $E(s)$. In the configurations #1 and #2 of above Figure, this integration is effective when a non-zero value for K_i is chosen. For stability considerations, integral control is always *added* to proportional control, resulting in the designation "PI-control".

In terms of 'error coefficients' adding an integral operation in the forward path is equivalent to increasing the system type number, thereby improving steady state error performance. In this experiment, the effects of adding integral feedback will be studied using the control scheme of #1 of Figure 5.1. The PI controller is implemented by selecting $K_d=0$ and non-zero values for K_p and K_i . Making the above selection is equivalent to introducing a transfer function:

$$G_c(s) = K_p + \frac{K_i}{s} = \frac{K_p(s + \frac{K_i}{K_p})}{s}$$

in cascade with the plant which has the transfer function:

$$G(s) = \frac{K}{s(B + Js)}$$

In terms of the root-locus diagram, it can be seen that PI control adds a pole at the origin (increasing system 'type') and a zero at $s = -K_i/K_p$. If the added zero is close enough to the added pole, the effect on the transient response can be minimal, while still providing improvement in steady state performance due the increase in the 'type' number. It must be noted that the OL gain is multiplied by

K_p and a gain adjustment may be necessary. Considering the **unity feedback system** (UFS) OLTF of $G_c G_p$, however, it can be seen that the addition of integral control will also increase the system order. The increase in system order has the tendency of degrading the relative stability of the system which may be observed, for example, as an increase in the overshoot. This disadvantage can be overcome by introducing 'derivative control', thereby leading to what is known as "PID-control" (or "Three-Mode" control). For a PID controller, the transfer function is

$$G_C(s) = K_p + \frac{K_i}{s} + K_d s = K_d \frac{[s^2 + s \frac{K_p}{K_d} + \frac{K_i}{K_d}]}{s}$$

In terms of the root-locus diagram, a pole is introduced at the origin increasing the system 'type number' as before, and two finite zeros are introduced. The two zeros may be located on the real axis or may be complex conjugates in the 'left-half-plane'. (It can be shown that the latter condition will result if $K_p < 2\sqrt{K_i K_d}$). While the increase in system type improves the steady state error performance, the attendant degradation in relative stability is counteracted by the presence of the finite zeros in the 'left-half-plane'. PID control is commonly used in industrial control systems, the adjustment process for the three coefficients being called a "tuning" operation. Rather than determining the required settings analytically, various semi-empirical and well-established tuning procedures (such as the "Ziegler-Nichols tuning rules") are used in practice (See your course textbook for further information about this topic).

STEADY STATE ERROR

The 'error' $e(t)$ is defined as the difference between the command input $r(t)$ and the output $c(t)$; i.e. $e(t) = r(t) - c(t)$. The steady state or 'static' error (e_{ss}) is the final value of $e(t)$ that is reached as time t approaches infinity, i.e. $e(\infty)$. In the frequency domain, the "Final Value Theorem" (FVT) can be used to obtain e_{ss} :

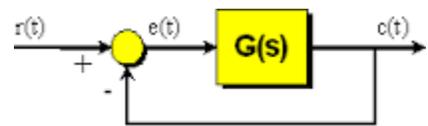


Figure 5.2: Unity Feedback System

$$e_{ss} = e(\infty) = \lim_{s \rightarrow 0} sE(s)$$

For a unity feedback system (UFS) in Figure 5.2, assuming it is stable, we have

$$E(s) = R(s) - R(s)T(s) = R(s) \left(1 - \frac{G(s)}{1+G(s)}\right) = R(s) \left(\frac{1}{1+G(s)}\right) \quad (5.1)$$

where $G(s)$ the transfer is function of the system and $R(s)$ is the input. e_{ss} can result in values of zero, a finite number, or ∞ . For a given input, e_{ss} depends on the form of $G(s)$, especially on the presence and number of s terms in the denominator of $G(s)$ (i.e. the poles of $G(s)$ at the origin). For this reason, systems are classified in terms of the number of poles of the OLTF at the origin, which is called the system "Type number" (N). Thus, e_{ss} depends on both N and $R(s)$.

For example, consider the UFS OLTF $G(s) = 10/s(s+2)$. The system Type is 1 since there is one s term in the denominator of the OLTF. However, the order of this system is 2 since it has two poles. Now consider unit step ($R(s) = 1/s$) and unit ramp ($R(s) = 1/s^2$) inputs to the closed-loop system which has this OLTF.

For the step input,

$$e_{ss} = \lim_{s \rightarrow 0} s \left(\frac{1}{s} \right) \left(\frac{1}{1 + \frac{10}{s(s+2)}} \right) = \frac{1}{1+\infty} = 0 \quad (\text{i.e. zero error})$$

For the ramp input,

$$e_{ss} = \lim_{s \rightarrow 0} s \left(\frac{1}{s^2} \right) \left(\frac{1}{1 + \frac{10}{s(s+2)}} \right) = \lim_{s \rightarrow 0} \left(\frac{(s+2)}{s(s+2)+10} \right) = \frac{2}{10} = 0.2 \quad (\text{i.e. a finite error})$$

If the input is extended to a unit parabolic function $r(t) = t^2/2$ ($R(s) = 1/s^3$) and the application of the FVT as above will yield a $e_{ss} = \infty$ i.e. a Type 1 system will have zero error for step inputs, a finite error for ramp inputs and infinite error for parabolic inputs. Static error analyses, such as the above, can be standardized by expressing e_{ss} in terms of “error coefficients” (or error constants) k_j defined as follows:

$$(\text{General}) \text{ Error coefficient } k_j = \lim_{s \rightarrow 0} s^j G(s) \quad \text{where } j = 0, 1, 2, \dots \quad (5.2)$$

Following historical terminology used for early positional servomechanisms, the error coefficients corresponding to $j = 0, 1$, and 2 are called the *positional*, *velocity* and *acceleration* error coefficients respectively. These are designated in this manual as k_{pos} , k_{vel} , and k_{acc} respectively, in order to avoid possible confusion with variables such as k_p used elsewhere in the manual. The three constants could alternatively be called the *step*, *ramp* and *parabolic* error coefficients. Thus

$$\begin{aligned} k_{pos} &= \lim_{s \rightarrow 0} s^0 G(s) = G(0) \quad \text{and} \quad e_{ss}(\text{step}) = \frac{1}{1+k_{pos}} \\ k_{vel} &= \lim_{s \rightarrow 0} s^1 G(s) \quad \text{and} \quad e_{ss}(\text{ramp}) = \frac{1}{k_{vel}} \\ k_{acc} &= \lim_{s \rightarrow 0} s^2 G(s) \quad \text{and} \quad e_{ss}(\text{parabolic}) = \frac{1}{k_{acc}} \end{aligned} \quad (5.3)$$

The error shown is for a unit input and must be multiplied by the magnitude A of the actual input used. Steady state error can be expressed as the absolute value or as a percent of the input magnitude. In the latter case, the unit magnitude given by Equations (5.2) is in fact the decimal value of the percent figure. A table giving e_{ss} for the three different inputs as a function of system Type N is shown in table 5.1.

The above results indicate that:

- (1)** to follow a step input with finite error, at least a Type 0 system is required
- (2)** to follow a ramp input with finite error, at least a Type 1 system is required
- (3)** to follow a parabolic input with finite error, at least a Type 2 system is required

Also, it is worth mentioning that whenever a finite error results, its value will depend on k_j which in turn is dependent upon the system parameters such as the gain. In many cases, an attempt towards extreme minimization of e_{ss} by increasing gain, for example, may fail because the system becomes unstable at the selected gain.

Table 5.1. Steady state error for specified input and type number

Unit Input $r(t)$ \ Type Number N	0	1	2
Unit Step $u(t)$	$\frac{1}{1+K_{pos}}$	0	0
Unit Ramp $t u(t)$	∞	$\frac{1}{K_{vel}}$	0
Unit Parabolic $[\frac{t^2}{2}]u(t)$	∞	∞	$\frac{1}{K_{acc}}$

5.2.2 DISTUTBANCE CONTROL

In regulatory systems, the error introduced by a disturbance input $d(t)$ can be reduced to zero by PI control.

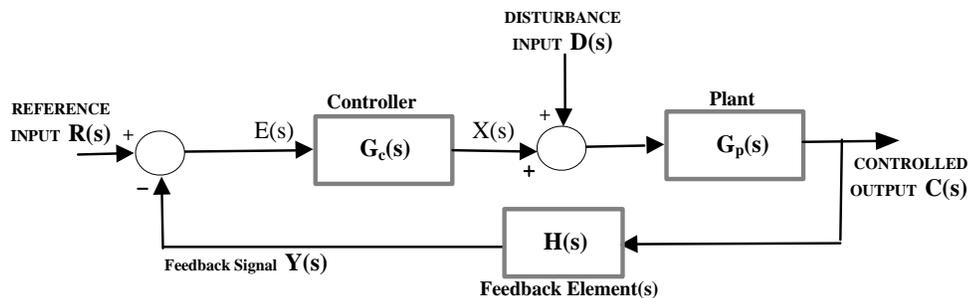


Figure 5.3: Disturbance control

The response of the closed-loop system to a disturbance $D(s)$ can be investigated by considering $D(s)$ as the input with $R(s)$ set to zero. With $R(s)=0$, the effective ‘disturbance transfer function’ being given by

$$T_D(s) = \frac{C(s)}{D(s)} = G_p / (1 + G_p G_c H) = \frac{G_p(s)}{1 + G(s)H(s)}$$

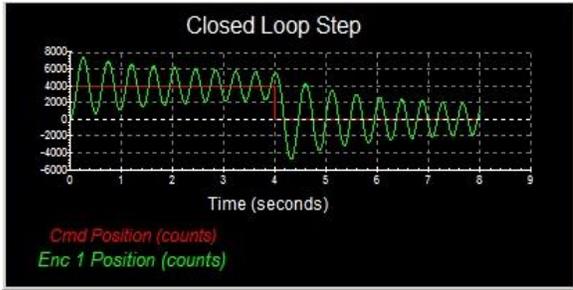
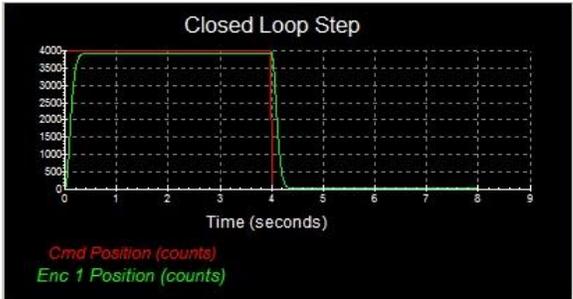
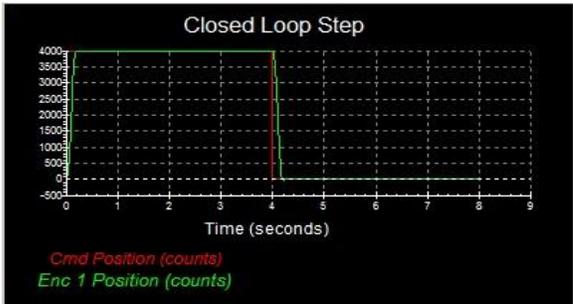
where $G(s)=G_p(s)G_c(s)$. It is seen that a high ‘loop gain’ $G(s)H(s)$ will reduce the effect of the disturbance $D(s)$.

REMINDER: to use only the continuous domain specifications and procedures, ie under ‘SETUP’, all that is needed is to check the “Continuous Time” button and then “Set Up Algorithm”, and then click on “Implement Algorithm” after setting the controller coefficients.

5.3 PID CONTROL

5.3.1 PI - CONTROL

The step response of a system with proportional controller is obtained first by setting $K_i = K_d = 0$ and K_p to some specific value. Viscous friction (input disturbance) is then introduced through the disturbance motor and its value is increased resulting in steady-state error in step response. Integral feedback is then introduced and its effect of reducing the steady state error is seen.

- 1) Reset the controller from the Utility menu. From the Set Up Control Algorithm implement the PID configuration (#1 in Figure 2.5) with $K_i = K_d = 0$ and with $K_p = 0.2$. Set up a closed-loop step response input using a step size of 4000 Counts, dwell time of 8000 ms. number of repetitions 1. RUN the step test and use axis scaling. A response similar to that shown below will be obtained. Determine* values for the overshoot (using suitable axis scaling of the plot) as well as the damped natural frequency ω_d .
- 
- The plot titled "Closed Loop Step" shows the response of the system to a step input. The y-axis is labeled "Cmd Position (counts)" and "Enc 1 Position (counts)" with a scale from -6000 to 8000. The x-axis is labeled "Time (seconds)" from 0 to 9. A red line represents the command position, which steps up to 4000 counts at approximately 0.5 seconds and remains constant. A green line represents the encoder position, which rises to a peak of about 6000 counts (overshoot) and then oscillates around the 4000 count level with a period of approximately 1.5 seconds.
- 2) Next, from the 'Command' menu, select 'Disturbance configuration', 'Viscous Friction' and set it to 4 volt-sec/radian. Then, after checking 'Implement' and OK, RUN the step test again. Make sure to check the "Include Viscous friction" box as well before clicking on 'RUN'. A step response, similar to the one shown below, should result. The response shows better damping but a finite offset in the steady state. Measure the offset error.
- 
- The plot titled "Closed Loop Step" shows the response of the system with viscous friction. The y-axis is labeled "Cmd Position (counts)" and "Enc 1 Position (counts)" with a scale from 0 to 4000. The x-axis is labeled "Time (seconds)" from 0 to 9. A red line represents the command position, which steps up to 4000 counts at approximately 0.5 seconds and remains constant. A green line represents the encoder position, which rises to 4000 counts, then drops sharply to about 1000 counts at 4 seconds, and then slowly recovers back towards 4000 counts, showing significant damping and a steady-state offset.
- 3) Re-implement the controller with K_i set to successive values from 0.02 to 0.1 in steps of 0.02 (you need to do it five times. For example 0.02, 0.04, 0.06, 0.08, and 0.1) and RUN the step test at each value. Select and note* the value of K_i which will minimize the steady state error to some acceptable value within 5%. Record* your observations. A typical response with $K_p = 0.2$, VF = 4 Volt-sec/radian and $K_i = 0.03$ is shown below.
- 
- The plot titled "Closed Loop Step" shows the response of the system with $K_i = 0.03$. The y-axis is labeled "Cmd Position (counts)" and "Enc 1 Position (counts)" with a scale from -500 to 4000. The x-axis is labeled "Time (seconds)" from 0 to 9. A red line represents the command position, which steps up to 4000 counts at approximately 0.5 seconds and remains constant. A green line represents the encoder position, which rises to 4000 counts, then drops sharply to about 1000 counts at 4 seconds, and then slowly recovers back towards 4000 counts, showing minimal steady-state error.

RESULTS

- 1) Describe the effect of increase in K_i on the offset error and on the overshoot.
- 2) Derive the CLTF for the PID system (#1 in Figure 5.1) and obtain the relation between coefficients required for stability (Note that for a cubic equation

$$D_T(s) = a s^3 + b s^2 + c s + d = 0,$$

no root will have a positive real part if the condition $b \times c > a \times d$ is satisfied)

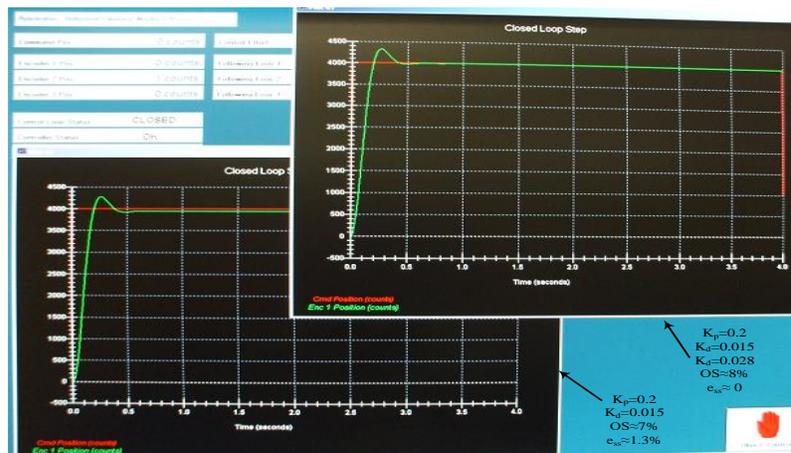
5.3.2 PID-CONTROL

- 1) From the Utility menu, reset the controller. Next, from the "Command" menu, remove the viscous friction and the disturbance input. Implement the PID controller with $K_p = 0.2$, and $K_i = K_d = 0$. Obtain the closed-loop step response using a step size of 4000 Counts, dwell time of 4000 ms, number of Repetitions 1. Display the response within the dwell period and reduce the display for later comparison. A typical plot that results from this step is shown below.

- 2) Successively increase the value of K_d in a small enough step, e.g. 0.002, and set its value so that a desirable overshoot (in your opinion) is obtained. To find the best value of K_d , you could increase it up to 0.015. This value may vary around 0.015. Overshoot values in the 5~10% range are generally considered acceptable. An offset error will be noticed. Record the chosen value of K_d , the overshoot (OS) and the steady state error.
- 3) Next, successively increase the value of K_i in steps of 0.01 until the offset in the step response is almost reduced to zero. Record the chosen value of K_i . Typical displays that result from above Steps and the current one (after setting a suitable values) are shown below.

Results

Tabulate your choice of controller coefficients for PID control.

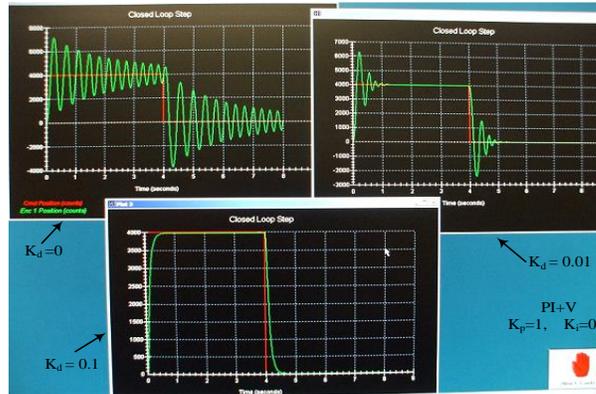


5.4 STEADY STATE ERROR ANALYSIS

5.4.1 USE STEP SIGNAL WITH PD

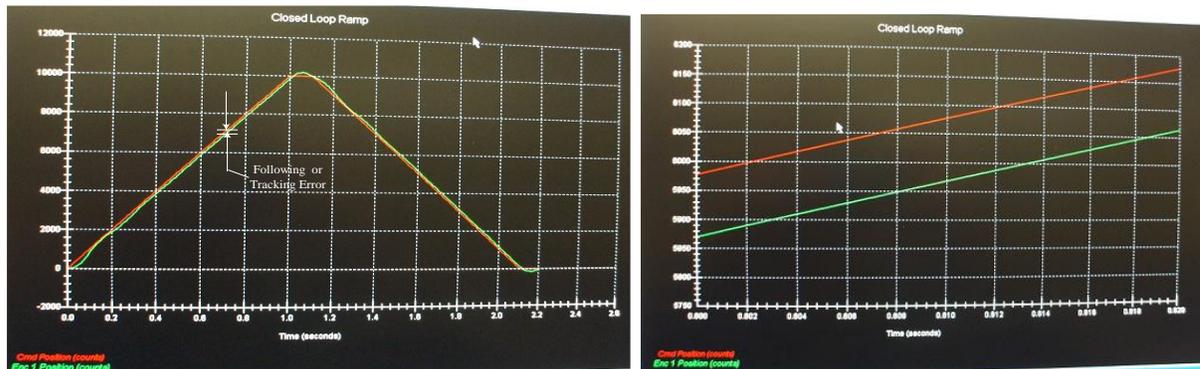
- 1) Reset the controller from the Utility menu. From the Set Up Control Algorithm menu implement the "PI + velocity feedback" with the following settings: $T_s = 0.00442s$, $K_p = 1$, $K_i = 0$ and $K_d = 0.01$ with Continuous Time type .
- 2) Perform a closed-loop step test using a Step Size of 4000 Counts, Dwell Time of 4000 ms and Number of Repetitions 1.
- 3) Observe the output which is highly oscillatory.
- 4) Click on Plot and view the waveform. Using axis scaling, obtain* the steady state step error (tracking error) in counts using the increasing part of the response.
- 5) Repeat above steps with K_p equals 0.5 and 0.2. Keep K_i and K_d unchanged. It will be seen that the system is now stable and an underdamped step response results. Obtain* the percent overshoot (PO) and the damped natural frequency ω_d using suitable axis scaling. Increase K_d to 0.1 and observe the effect on the step response.

Typical results show the stabilizing effect of increasing K_d are seen in the screen below.



5.4.2 USE RAMP SIGNAL

- 1) Reset the controller from the Utility menu. From the Set Up Control Algorithm menu implement the “PI + velocity feedback” with the following settings: $T_s = 0.00442s$, $K_p = 1$, $K_i = 0$ and $K_d = 0$ with Continuous Time type.
- 2) Set up and perform a RAMP test with a Ramp Size of 10000 counts, Velocity 10000 Counts/sec, Dwell Time of 100 ms, number of Repetitions 1 (these are the default values).
- 3) Observe the output which is highly oscillatory.
- 4) Click on Plot and view the waveform. Using axis scaling, obtain* the steady state Step error (tracking error) in counts using the increasing part of the response.



Expanded display using Axis Scaling to find the tracking error

e_{ss} can be readily found from the y-axis intercepts.

- 5) Repeat Steps 2-4 above using the same gains ($K_p = 1$, $K_i = 0$, and $K_d = 0.01$) but with the “PID” controller (#1 of Figure 2.5) implemented instead of the “PI +Velocity feedback” configuration. Note that in this case, there is no minor loop.

RESULTS

- Tabulate the results of the step and ramp tests for the two different controller implementations. Is there any change in the step response between the two cases? What is the difference in the ramp response between the two cases?

- The equivalent UFS OLTF and the CLTF for the “PI+Velocity feedback” system were already given. for both the systems. Derive the corresponding transfer functions for the system using the “PID” controller with $K_i=0$. Show that in both cases, the system Type number is 1.

Calculate the ‘velocity-error’ coefficients K_{vel} for the two cases.

The steady state ramp error is given by: $e_{ss}(\text{ramp}) = \text{Ramp magnitude} / K_{vel}$

Hence, for a ramp input of 10,000 Counts/sec,

$$K_{vel} = 10000 / e_{ss}(\text{Counts/sec})$$

Show that the velocity error-coefficients for the configurations #1 (PID) and #2 (PI+V) of Figure 5.1 with $K_i=0$ are respectively

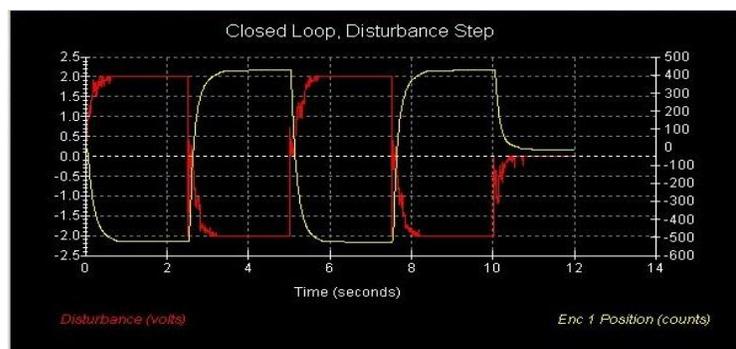
$$K_{vel(PID)} = KK_p/B \quad \text{and} \quad K_{vel(PI+V)} = KK_p/[B+KK_d].$$

Note that $K_{vel(PID)} > K_{vel(PI+V)}$ and hence the corresponding steady state ramp error for the PID controller will be the smaller of the two.

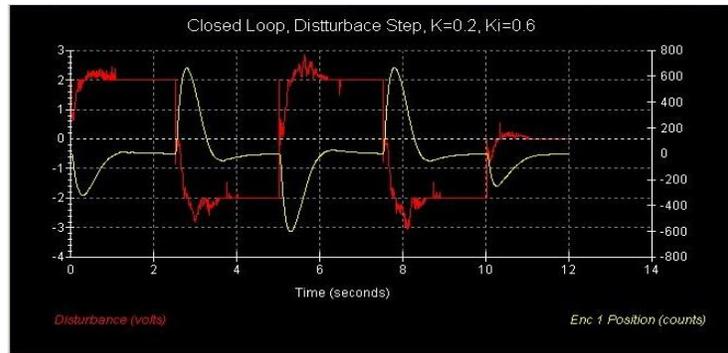
5.5 DISTURBANCE ATTENUATION

The effectiveness of PI control in eliminating the steady state error caused by a disturbance input will be demonstrated. Please note that the settings given are only typical since gain and inertia and friction vary from unit to unit.

- 1) Set up a PID control scheme with Continuous Time type, with $K_p = 0.2$ and $K_i = K_d = 0$ and with viscous friction introduced through the disturbance motor and set at 4 Volt-sec/radian.
- 2) From the ‘Command’ menu, select an input STEP trajectory with a magnitude of zero counts and 6000ms dwell, number of Repetitions 1. This configures the system to acquire data over a period of 12 seconds.
- 3) From the ‘Command’ menu again, select a disturbance step trajectory of 2 Volts magnitude, 2500ms dwell, and number of Repetitions 2. From Set Up Plot, select Encoder 1 Position for the Right axis and Disturbance Effort for the Left axis, after making sure that the latter has been added under Data Acquisition. Then RUN the system, after making sure that both “Include Viscous friction” and “Include Disturbance” boxes are checked. A plot similar to the one shown below should result.

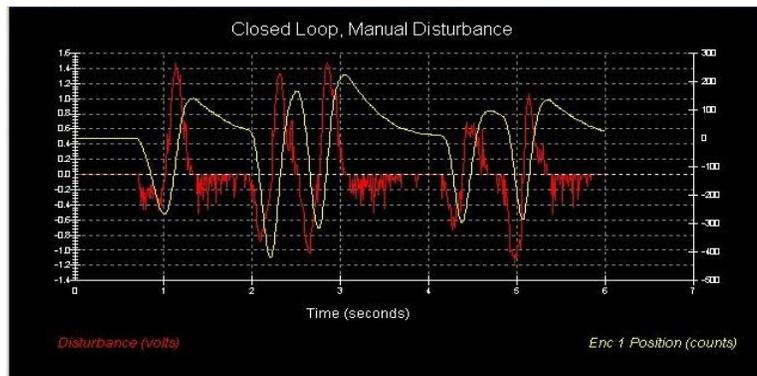


- 4) Now, re-enter “Set up algorithm” and set $K_i = 0.6$. Implement the controller and repeat Step 3 above with the integral action included. The resulting plot will be similar to the one shown below. It is seen that the integral action attempts to ‘force’ the error to zero.



The error-reducing force can also be felt by hand: Re-enter the Command menu and set the disturbance to zero. Then implement the system and click on ‘RUN’. With the thumb and forefinger of the left hand, gently attempt to disturb the load disk by a small angle, say $\pm 10^\circ$ to 15° . The integral action resisting the displacement can be felt on your hand.

Since data has been uploaded by the attempted disturbance, the data-acquisition sequence will proceed and the disturbance that you manually introduced, as well as the resulting corrective action can be displayed. Note that if a larger disturbance is given, the system will overload and open the feedback loop. A typical plot of the action following two ‘hand-induced’ disturbances is shown below.



- 5) Repeat Step 4 above with lower and higher values of K_i and describe your observations. Use the results from Step 5 above to evaluate the maximum value of K_i that can be used with the given settings.

RESULTS

- 1) Obtain the equivalent OLTF $G_{ufs}(s) = T(s) / [1-T(s)]$ and sketch the root locus diagram for the system. Attempt a correlation with the location of the closed-loop poles.
- 2) Comment on any problems or differences encountered in this correlation.
- 3) [Optional] Use Simulink to simulate the system response in PID-CONTROL of 5.4 PID Control.

=====

6 EXPT #4: TRANSIENT AND FREQUENCY RESPONSE

6.1 OBJECTIVE

- To study the transient response of open-loop and closed-loop system.
- To study the frequency response of a first order system (magnitude and phase) and determine the cut-off frequency(ω_c).
- To determine the frequency response (magnitude and phase) of a second order closed-loop system.

6.2 INTRODUCTION

6.2.1 SYSTEM TRANSIENT RESPONSE

The typical unit step response of a second order system shown in Figure 6-1 is used to define various performance criteria such as the 10% to 90% Rise time (T_r), the Peak time (T_p), the percent overshoot (PO), the 2% Settling time (T_s), and the Damped Natural Frequency ($\omega_d = \omega_n \sqrt{1 - \zeta^2}$).

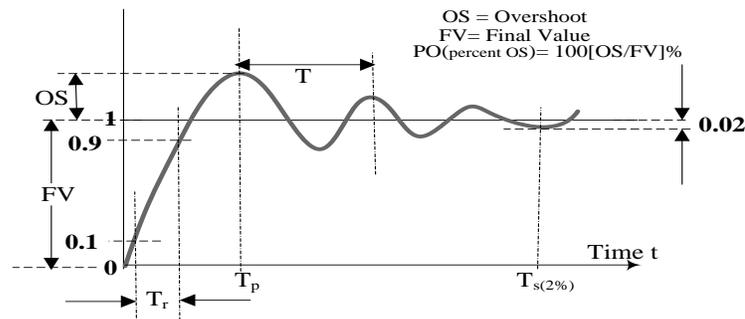


Figure 6.1: Typical unit response of a system

Definition of these parameters allows performance comparisons between different system designs to be made with the objective of selecting a system with the desired performance specifications. The terms OS, T_p , etc. are sometimes loosely applied to a similar response which is not strictly a classical second-order response.

The system parameters damping ratio (ζ) and undamped natural frequency (ω_n) are related to some of the observed parameters shown in the figure above. Some relations are given below:

$$\text{Percent Overshoot (PO)} = 100 \exp\left(\frac{-\pi\zeta}{\sqrt{1-\zeta^2}}\right) \% \quad (6.1)$$

The relation between PO and ζ is shown in Figure 6.2.

If $[\text{PO}(\%) / 100] = p$, then

$$\zeta = \frac{\sqrt{(\ln p)^2}}{\sqrt{\pi^2 + (\ln p)^2}} = \frac{\sqrt{(\ln p)^2}}{\sqrt{9.87 + (\ln p)^2}} \quad (6.2)$$

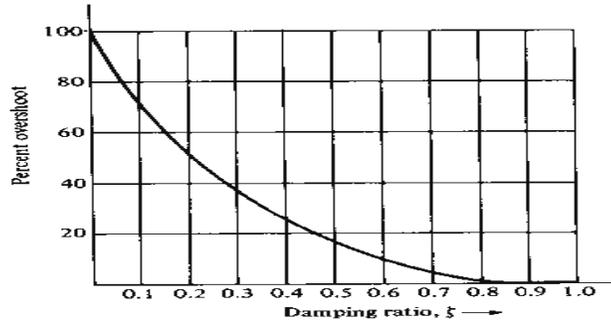


Figure 6.2: The relation between PO and ζ

Equation (6.2) may be used for precise calculation of ζ when the PO is specified.

Also, the peak time and 2% settling time are given by:

$$T_p = \frac{\pi}{\omega_d} \quad \text{and} \quad T_s = \frac{4}{\zeta\omega_n}$$

In this experiment, the effect of changing the proportional gain factor K_p on the step response is observed. The effects of introducing derivative feedback in the forward as well as in the feedback path are then investigated in the second part. The “PI + Velocity FB” configuration in figure 6.3, will be mostly used.

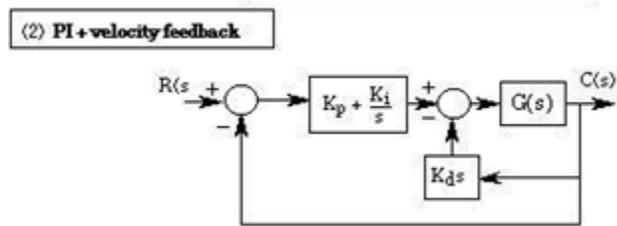


Figure 6.3: System Configuration

If we set $K_i = 0$, the closed-loop transfer function will be a ‘standard’ second order system with no zeros:

$$T(s) = \frac{C(s)}{R(s)} = \frac{\frac{KK_p}{J}}{s^2 + \left(\frac{B + KK_d}{J}\right)s + \frac{KK_p}{J}} = \frac{\omega_n^2}{s^2 + 2\omega_n\zeta s + \omega_n^2}$$

then

$$\omega_n = \sqrt{\frac{KK_p}{J}} \quad \text{and} \quad \zeta = \frac{B + KK_d}{2\sqrt{KK_pJ}} \quad (6.3)$$

It can be seen that increasing k_p will result in an increase in ω_n (indicative of a faster ‘rise time’ and hence improved transient response) and a decrease in ζ (indicative of higher ‘overshoot’). From the CLTF above, it can be seen that the damping term contains k_d , the ‘velocity-feedback’ coefficient. The velocity feedback therefore provides an adjustable (artificial) damping which is added to the natural damping B . In the second part of the experiment, the effect of this artificial damping is verified. Increasing the overall damping by raising the value of k_d can compensate for the increased OS resulting from increasing k_p . The term ‘velocity feedback’ arises from the use of the derivative of the output signal, which is velocity, in a position-control system as a feedback signal.

6.2.2 FREQUENCY RESPONSE

The steady state response of a linear system to sinusoidal input signals of varying frequency is generally known as the “frequency response”. Frequency response is obtained by applying a fixed-amplitude sinusoidal input signal and measuring the resultant changes in amplitude and phase of the output (with respect to the input), as a function of increasing frequency. More precisely, these changes are expressed, in terms of output and input phasor quantities, as the following quantities:

$$\text{Magnitude Ratio } M = \text{Output amplitude} / \text{Input amplitude}$$

and

$$\text{Phase-shift } \phi = \text{Output phase angle} - \text{Input phase angle}$$

Both of which are dependent upon the radian-frequency $\omega=2\pi f$, where f is the frequency in Hz. The most common modes of presentation of frequency-response data are Bode Plots as shown in figure 6-4 and Polar Plots as shown in figure 6-5.

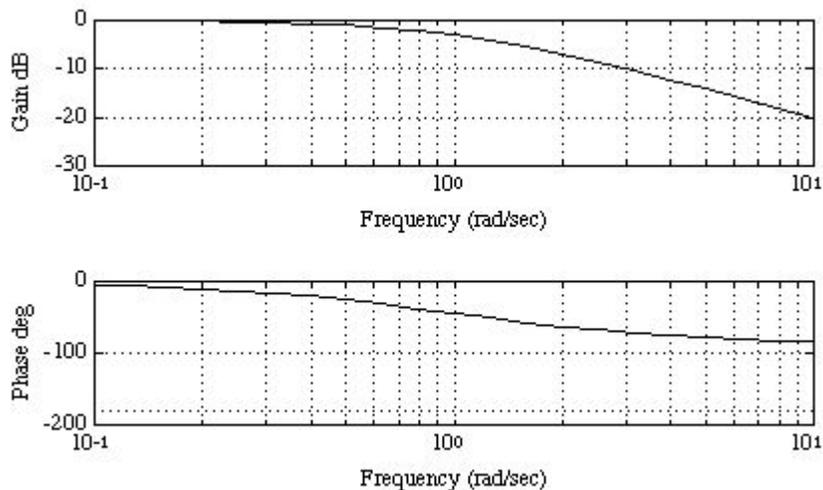


Figure 6.4: Bode Plots

In Bode plots, M (when expressed in decibels, $M \text{ (dB)} = 20 \log M$) and ϕ (expressed in either degrees or radians) are plotted against a logarithmic frequency scale which will allow a *large range* of frequencies to be shown. The Bode and Polar plots of the OLTF are used in system design, whereas the Bode plots of the CLTF are usually provided as a part of the system specifications. (Historically, design of feedback compensators was done using the Bode plots of the OLTF, with the reference quantities of ‘Gain Margin’ and ‘Phase Margin’ which are also indicative of relative system stability. Students should consult the course textbook to understand the meaning of these two terms.)

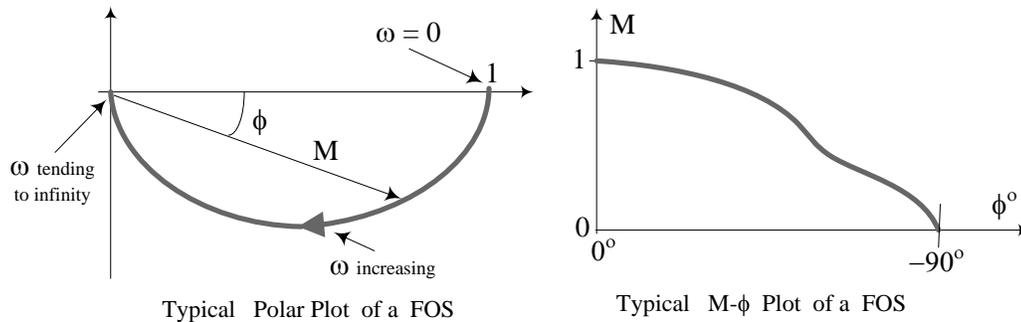


Figure 6.5: Polar Plots

Straight-line segmental approximations of the Bode plots (also called “asymptotic plots” of a transfer function) can be quickly sketched, if the transfer function can be analytically obtained in factored form (See ‘asymptotic plots’ in your course textbook). Conversely, an asymptotic plot can be ‘fitted’ to an experimentally-obtained magnitude plot in order to obtain the transfer-function.

6.2.3 Results

Write the results of transient response and frequency response in separate papers, which will be signed by your lab instructor at the end of the lab.

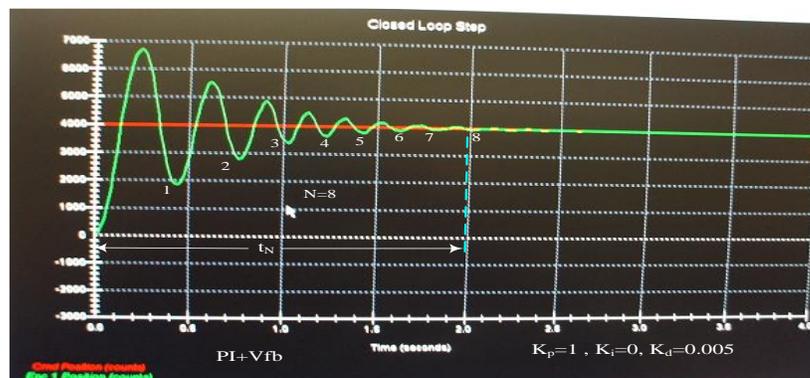
6.3 CLOSED-LOOP TRANSIENT RESPONSE

PROCEDURE

- 1) Reset the controller from the Utility menu. From the Control Algorithm menu, implement the configuration “PI + velocity feedback”, the type of Continuous time with the following settings:

$$T_s = 0.00442 \text{ sec}, \quad K_p = 1 \quad K_i = 0 \quad \text{and} \quad K_d = 0.005$$

- 2) Obtain the closed-loop step response using a Step Size of 4000 Counts, Dwell Time of 4000 ms, and number of Repetitions 1. RUN the step test and display the plot. Use axis-scaling to display only the section of the response within the dwell period of 4 seconds to make the display appear as a ‘step response’ as shown below for an instance.

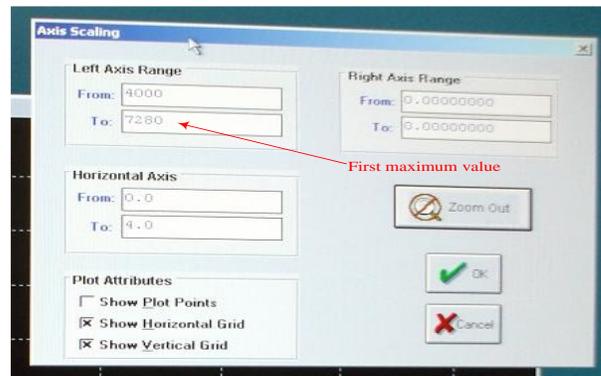


Obtain* values for: the damped natural frequency ω_d and the overshoot (OS) and using a suitable axis scaling of the plot.

Finding ω_d : The frequency ω_d can be found by finding the peak time t_p . Then, the corresponding radian frequency is given by $\omega_d = \frac{\pi}{T_p}$.

Finding OS: The OS can be found by re-scaling the left axis to display values from 4000 Counts. The magnitude difference between the first positive peak¹ X_1 and 4000 is the OS. The percent overshoot (PO) is then given by

$$PO = 100 \left[\frac{X_1 - 4000}{4000} \right] \% \quad (6.4)$$



3) Export raw data into a data file for further MATLAB analysis.

4) Repeat Steps 1 and 2 for K_p values of 0.7, 0.4, 0.1 and obtain the corresponding values of ω_d and the OS. Note that in each case the controller may be reset from the 'Set Algorithm' menu by clicking on 'Implement' after each change in the K_p value is made.

RESULTS

- 1) Tabulate ω_d and OS values for the above cases.
- 2) Write a brief summary about the difference between open-loop and closed-loop system?
- 3) From the OS values, use Equation (6.2) to calculate and tabulate the values of ζ , corresponding to the four K_p values used. Obtain a plot showing the effect of increasing K_p on the damping ratio ζ and comment on the result.
- 4) From the tabulated values of ζ and ω_d , determine the corresponding ω_n values. Obtain a plot showing the effect of increasing K_p on the natural frequency ω_n and comment on the result.

ANALYSIS in MATLAB*

- 1) Use the following settings: $T_s = 0.00442$ sec, $K_p = 0.1$, $K_i = 0$ and $K_d = 0.005$ and the obtained model in Experiment #2, write MATLAB code to calculate CLTF in the configuration of "PI + velocity feedback", see formula 6.3.

¹ After the plot is displayed, selecting 'Axis Scaling' will show the 'left axis' scales as 'From..., To...'. The value indicated in the 'To...' box is an accurate figure for the first maximum value X_1 from which the PO can be readily deduced. This is shown in the next figure.

Sample code is listed below, you may have to change the parameter to yours (obtained in Experiment #2):

```
K=5, B=0.002, J=0.02;
Kp = 0.1, Kd = 0.005;
s = tf('s');
cltf = (K*Kp)/(J*s^2+(B+K*Kd)*s + K*Kp);
```

- 2) Refer to sample code in Experiment #1, using MATLAB LTI Viewer to analysis system step response.
- 3) Compare the result with the exported raw data, for at least one K_p .

6.4 OPEN-LOOP FREQUENCY RESPONSE

The frequency response of the first order system $G(s)=C(s)/R(s)= 1/(1+\tau s)$ can be expressed by the magnitude-ratio and phase shift equations, which are reproduced below:

$$\text{Output/input magnitude ratio: } M(\omega) = C(\omega)/R(\omega) = 1/(1+ \omega^2\tau^2)^{0.5}$$

$$\text{Phase-shift: } \phi(\omega) = -\tan^{-1}(\omega\tau)$$

and are plotted with respect to a logarithmic frequency-axis. In this experiment, the frequency response of the velocity (rather than position) is considered. The transfer function will be of first-order and also the response will be plotted against a linear frequency-axis, to correspond to more basic form of expression.

When applied to the first-order plant of the laboratory system (with $\tau =J/B$), for the velocity will be given by

$$\Omega(\omega) / V_i(\omega) = K_o / (1+ j\omega\tau)$$

Where $K_o = K_e K_a K_t / B$. In the above equation, the symbol Ω has been used here to denote the angular velocity variable in order to avoid confusion with the sinusoidal radian frequency ω . This corresponds to a magnitude of

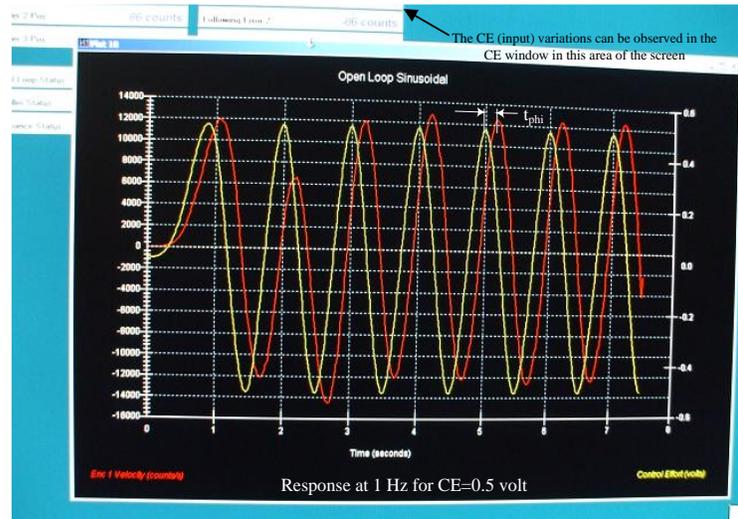
$$M(\omega) = |\Omega(\omega) / V_i(\omega)| = (K_e K_a K_t / B) / (1+ \omega^2\tau^2)^{0.5} \quad (6.5)$$

and a phase shift given by:

$$\phi(\omega) = -\tan^{-1}(\omega\tau) \quad (6.6)$$

For a given open-loop sinusoid input voltage V_i (i.e. Control Effort, CE), the experimental variation of $\Omega(\omega)$ and $\phi(\omega)$ with frequency may be obtained. At any given frequency, the amplitude of the angular velocity Ω (in counts) can be obtained from the displayed value of the Encoder #1 Velocity.

Test frequency range: For the laboratory system, the upper frequency region where ϕ approaches a 90° value is found to be around 1Hz. For example the Encoder #1 velocity output at 1Hz for a 0.5 volt CE is shown below.



Ignoring the initial (transient) part of the display, the phase shift ϕ is found from the time difference t_{ϕ} between two adjacent peaks:

$$\phi = -360 f t_{\phi} \quad (\text{degrees})$$

where f is the frequency in Hz and the negative sign is included to indicate that the output lags the input. In the above figure, for example, $t_{\phi} \approx 0.25$ sec yield to $\phi \approx -90^\circ$ which is the high-frequency limit for the first-order transfer function under consideration.

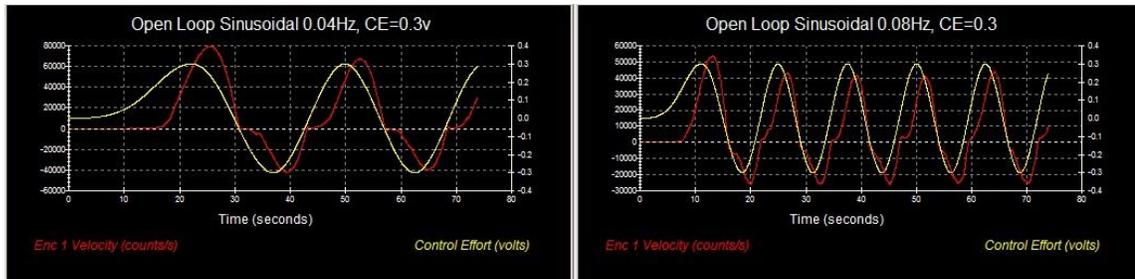
Another point regarding the test that must be mentioned is the initial (or transient) part. The system shows a certain delay before turntable action is observed, and this delay is greater for lower values of the test frequency. However, system activity is indicated by the changing numbers in the 'Control Effort' window at the top left of the screen, which shows the sinusoidal variation of V_i .

PROCEDURE:

- 1) Under 'Data Acquisition' menu, make sure that Control Effort (CE) has been added to the list. Reset the controller from the UTILITY menu. Set up the 'plot' to display the Encoder #1 Velocity on the left axis and the CE on the right axis.
- 2) From the COMMAND menu, select 'Trajectory' and choose Sinusoidal and then click on 'Set Up'. Then select OPEN LOOP, Amplitude **0.4** volts, Frequency **0.06** Hz, and number of Repetitions **8**. Next, go to 'Execute' and RUN the test. (Remember the point mentioned above about a delay in action.) After the data has been acquired, plot the output. (The trace will be similar to the one shown earlier for 1 Hz.)
- 3) Ignoring the initial transient part*, measure the constant peak-to-peak angular velocity output magnitude Ω_{pp} in counts/sec. Also measure the time difference t_{ϕ} between two adjacent peaks in order to estimate the phase shift.
Use the right end of the display. Axis Scaling may be used to examine a section of the steady state display.

- 4) Using Steps 2-3 above as a guide, obtain values for Ω_{pp} (in counts/sec.) and ϕ (in degrees) for frequencies of 0.04, 0.08, 0.1 and 0.2 Hz.

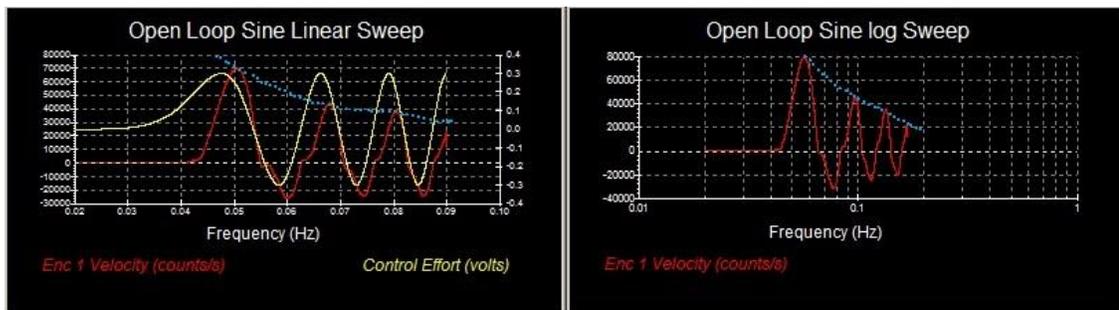
Two typical displays are shown below.



Obtain records for each of the above mentioned frequencies, and 'full screen' displays and obtain the required data as accurately as possible by visual observation.

Tabulate the values of radian frequency ω (radians/sec), Ω_{pp} (counts/sec.) and ϕ° .

- 5) Sweep frequency display: From the COMMAND menu, select 'Trajectory', Sine Sweep. Then click on 'Set Up'. Then select OPEN LOOP, Amplitude 0.5 volts (Amplitude 0.5 volts is fine for some systems; however, if there is a problem showing the plots, you can use Amplitude 0.4 volts or smaller), Frequency range from 0.02 Hz to 0.09 Hz, Sweep Time (Linear Sweep) 50 sec. Under 'Set Up Plot' select 'linear frequency' sweep. Go to 'Execute' and RUN the test. After the data has been acquired, plot the output and minimize the plot. Then re-plot the data using 'logarithmic frequency' sweep. Typical linear and log frequency plots are shown in the screen photograph below.



In these plots, the upper envelope of the plot (as shown by the dotted lines) gives the approximate 'shape' of the magnitude frequency response as explained in Expt#1.

RESULTS:

- Using the data tabulated in Step 4 above, use the conversion factor K_e to convert the values of Ω_{pp} (counts/sec.) to Ω_{pp} (radians/sec.). Plot Ω_{pp} (radians/sec.) against the radian frequency ω using a linear scale.
- Assuming that the input remained constant, the output magnitude should also be a constant (say, Y) at low frequencies approaching 0 Hz. Using the magnitude equation it can be shown that the

output magnitude will drop to $(1/\sqrt{2})Y$ or $0.707Y$ when $\omega_c = 1/\tau$, where ω_c is called the 'cut-off frequency' or 'break frequency'. Assuming Y is the magnitude corresponding to the frequency of 0.04 Hz, determine ω_c and hence find τ .

How does this value compare with the value found in EXPR#2(Sect4.3.2)? Comment on any difference observed.

(The value of $\tau = 1/\omega_c$ can also be estimated by finding $f_c = 1/2\pi\omega_c$ where the phase shift is -45° .)

6.5 CLOSED-LOOP FREQUENCY RESPONSE

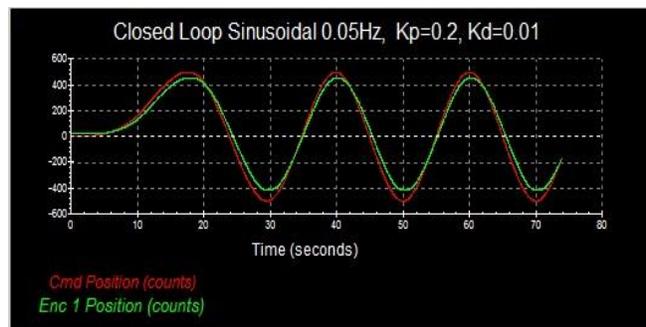
In this experiment, frequency-response measurements are made on the 'optimum' closed-loop control system that was set up at the end of the experiment 5.3.2. The magnitude response is also obtained by a 'swept-frequency' measurement procedure (available in the ECP Model 220 equipment) in which the frequency is increased either logarithmically or linearly over a given range while automatically acquiring and plotting output magnitude data.

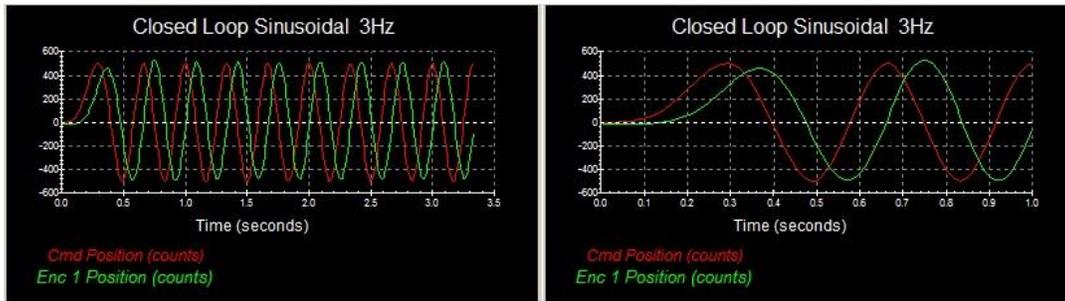
6.5.1 SPOT-FREQUENCY MEASUREMENT

- 1) From the Utility menu, reset the controller. Implement the PID configuration of #1, with the controller values that you selected for 'best performance' from last experiment 5.3.2, PID-Control. Using a step size of 4000 Counts, dwell time of 4000ms, number of repetitions 1. Verify that the 'desirable' response that you had selected is obtained.
- 2) Next, from the 'Command' > 'Trajectory' > 'Sinusoidal' menu, set up a sinewave input of 500 Counts amplitude, Frequency **0.5** Hz, number of repetitions 10. From 'setup plot' choose both 'commanded position' and 'Encoder #1 Position' on the Left axis. Then, RUN the test. The very slow sinusoidal motion of the mechanism will be observed. A typical display is shown below.

Repeat the test at another five well-spaced 'spot' frequencies in the range of 1 to 8 Hz. In each case, use 'Axis Scaling' to 'expand' and display the region beyond the initial (transient) part where the input shows a constant value of ± 500 Counts (1000 Cts, peak-to-peak). Use the scaled display to determine the magnitude ratio M and the phase shift ϕ : M is found by calculating the ratio between output and input peak-to-peak amplitudes. Phase shift ϕ is found by finding the time-difference t_{ϕ} between adjacent peaks of the output and input waveforms and then using the equation

$\phi = -360 f t_{\phi}$ (degrees), (Note: Since the output lags inputs, a negative sign is added) where f is the frequency in Hz. Typical plots at 3 Hz, for both original and axis-scaled versions are shown below.





- 3) Make a three-column table of values of frequency f (Hz), Peak-Peak Output (Counts) and t_{phi} (sec) and enter the six sets of data in the table.

RESULTS:

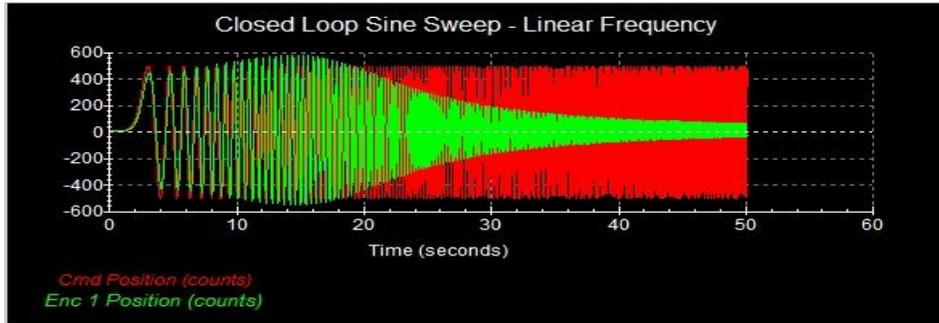
- 1) Use the data table obtained in Step 3 to calculate and tabulate $M(\text{dB})$ and $\phi(\text{degrees})$ against $\omega=2\pi f$ (radians/sec). Obtain Bode magnitude and phase plots for the frequency range 0.05 to 8 Hz (~ 0.3 to 50.3 radians/sec). Use 3-cycle semi-logarithmic graph paper. Also draw the corresponding polar plot for your data range.
- 2) Attempt to fit the Bode magnitude data to an asymptotic plot and hence obtain an approximate transfer function.

6.5.2 SWEEP FREQUENCY MEASUREMENT

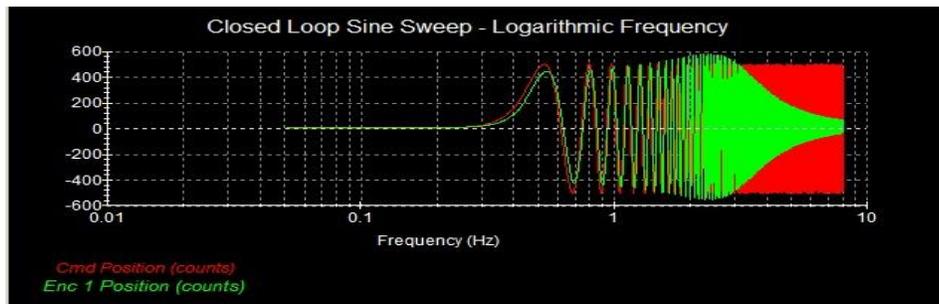
The Command/trajectory menu also offers the facility of displaying the nature of the magnitude-frequency response curve, by choosing the “sine sweep” trajectory. The input signal amplitude, the frequency sweep range, the sweep-time as well as the frequency-sweep mode (either linear or logarithmic) can be specified under Set Up. The vertical axis may be selected to show either linear or dB values. The positive side of the output envelope in the display will indicate the shape of the magnitude-frequency response and the frequency at which a peak occurs can be identified. It must be noted, however, that the displayed shape is only an approximation (especially dependent on the sweep-time) since the excitation time at each frequency may not be sufficient for the system to have reached steady state conditions.

PROCEDURE:

- 1) From the Utility menu, reset the controller. Implement the PID configuration of #1, with the controller values that you selected for ‘best performance’ from last experiment 5.3.2, PID-Control. Using a step size of 4000 Counts, dwell time of 4000ms, number of repetitions 1.
- 2) Use Set Up Trajectory and choose “Sinusoidal sweep”. Setup an input of 500 Counts amplitude, Start frequency 0.05 Hz, End frequency 8Hz, linear sweep and a sweep time of 50 sec. From ‘setup plot’ choose both ‘commanded position’ and ‘Encoder #1 Position’ on the Left axis. Then RUN the test. After a short delay, the sinusoidal motion of the rotary mechanism starting at the low frequency and increasing will be observed. Allow sufficient time for data acquisition to be completed and then display the plot. Typical sweep linear-frequency and log-frequency displays are shown below:

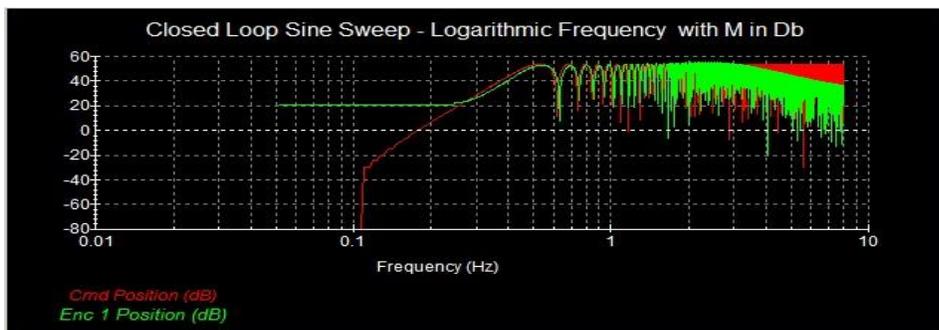


Linear frequency sweep



Logarithmic frequency sweep

- 3) Export raw data into a data file for further MATLAB analysis.
- 4) Try setting other display options for the horizontal and vertical axes. For example, a logarithmic plot with M in dB is shown below (for this part it is enough to change the logarithmic frequency to dB in the plot data setting).



Logarithmic frequency sweep with M (dB) values (upper envelope value only)

RESULT

- 1) Evaluate the amplitude and frequency and at a few points on the curve and compare the results with the spot-frequency data obtained earlier. Comment on the results.
- 2) *Use MATLAB LTI viewer to do system frequency-domain analysis. Refer to the code in the section 6.3 CLOSED-LOOP TRANSIENT RESPONSE .
- 3) Summarize the roles of engineering tool MATLAB/Simulink when you design a control system.

=====

7 EXPT #5: CONTROLLER DESIGN

7.1 OBJECTIVE

This lab will set several tasks to design different controllers for ECP 220 by using Control System Designer (*Sisotool*). The student will verify the design on the model ECP220 as well..

7.2 INTRODUCTION

The performance of the system can therefore be modified to conform to certain given specifications by changing the OLTF. This experiment will design a PID controller and lead compensator to meet the different design requirements.

7.2.1 PID Controller

The proportional, integral, and derivative control can be expressed mathematically as follows

$$u(t) = k_p e(t) + k_i \int_0^t e(\tau) d\tau + k_d (de(t))/dt. \quad (1)$$

The corresponding block diagram is given in the following Figure. The control action is a sum of three terms referred to as proportional (P), integral (I) and derivative (D) control gain. The controller Equation (4.3) can also be described by the transfer function

$$PID(s) = k_p + k_i/s + k_d s. \quad (2)$$

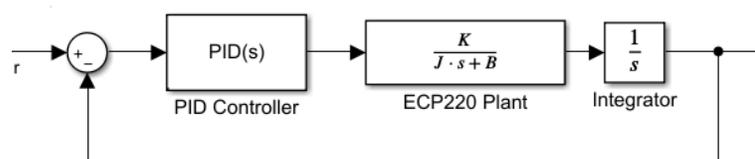


Figure 1 : Block diagram of PID control.

The functionality of the PID controller can be summarized as follows. The proportional term is based on the present error, the integral term depends on past errors, and the derivative term is a prediction of future errors.

The PID controller described by Equation (1) or Equation (2) is an ideal PID controller. However, attempts to implement such a controller may not lead to a good system response for real-world systems. The main reason for this is that measured signals always include measurement noise. Therefore, differentiating a measured (noisy) signal will result in large fluctuations, thus will result in large fluctuations in the control signal.

7.2.2 Matlab Design Tool

MATLAB provides some tools to help the control system design. *sisotool* opens a SISO Design GUI for interactive compensator design. This GUI allows you to design a single-input/single-output (SISO)

compensator using root locus, Bode diagram, Nichols, and Nyquist techniques. It is also possible to automatically design a compensator using this GUI. In this section, an overview of the steps for tuning compensator parameters is presented. Before beginning, you need:

- A model in the MATLAB workspace representing your plant; check your Experiment #2,
- Design requirements for your system.

7.2.3 Design Flow of a Control System

The typical flow of a control system design is shown in the following diagram:

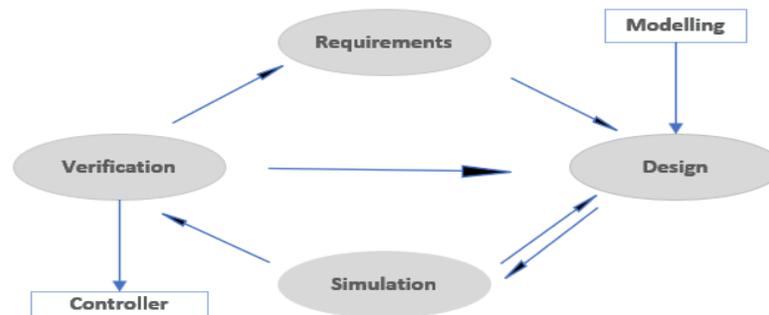


Figure 3 : Control design flow.

The System Model has been done in previous experiments. This experiment requires the following steps to finish a controller design.

- Requirements
 - Analysis the system model, then
 - Setup overall system performance requirements in time-domain.
- Design
 - Analysis and synthesis-detailed requirement,
 - Identify dynamic characteristics of the acquired model,
 - Tune the system controller.
- Simulation
 - Evaluate the design controller and plant models,
 - Fine-tune the controller without access to hardware to meet overall system performance requirements.
- Verification
 - Test on hardware and verify the design,
 - Update the controller model.

7.3 PID CONTROLLER DESIGN

- Use Control System Designer (*Sisotool*) to design a PID controller in the time domain, tune the controller using the following controller architecture:

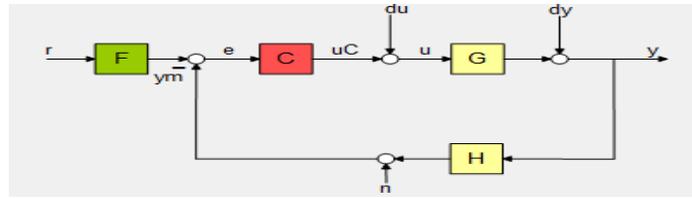


Figure 4 : Architecture of PID control.

7.3.1 Requirement

Based on the model in lab#2, design a PID controller for ECP220 to achieve:

- Rise time (peak time) < 0.1s
- Overshoot < 20%
- Settling time < 0.25s

7.3.2 Procedure

Step 1: Set the initial parameters:

ECP220 transfer function acquired in Lab#2 with parameters K, B and J is

$$G(s) = \frac{K}{s(B+Js)}.$$

Use the following sample code to set all initial values:

```
%Use parameters of K and T, which you got in Lab #2
K = 5.0; J = 0.005; B = 0.002; %Note: use your data instead

Kp=1.0; Ki = 0.0; Kd = 0.01; %PD control, initial values as 1

s = tf('s');
G = K/(s*(J*s+B)); %Motor transfer function
C = Kp + Ki/s+ Kd*s; %PID controller
```

Note:

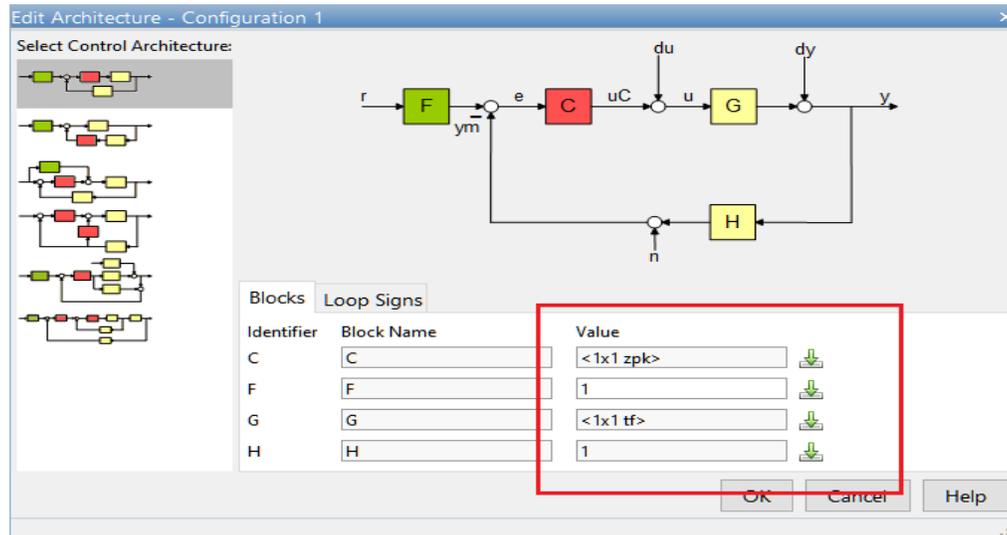
- Replace the value of K, J and B from your previous experiment.
- Set the initial values for the PID controller: Kp, Ki and Kd.
- Save the above code into a m-file named *ecp220_pid.m* and **run it**.

Step 2 : Run Control System Designer (*Sisotool*) by typing the following in the MATLAB Command Window:

```
sisotool
```

Define the control architecture.

- In the *Edit Architecture* tab, click **Edit Architecture**.
- In the Control Architecture dialog box, select the first option for this experiment.

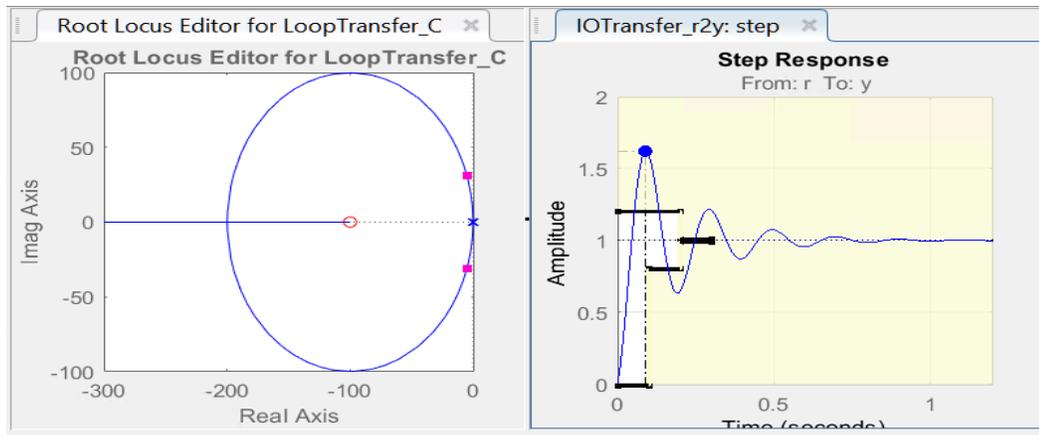


Step 3: Specify the plant model and initial values for the compensator elements in the control architecture.

- click **button** .
- Browse for a model in the MATLAB® workspace. For G and C, select the model G and C in workspace, which is generated from above m-file.
- Set the value of H and F as 1.

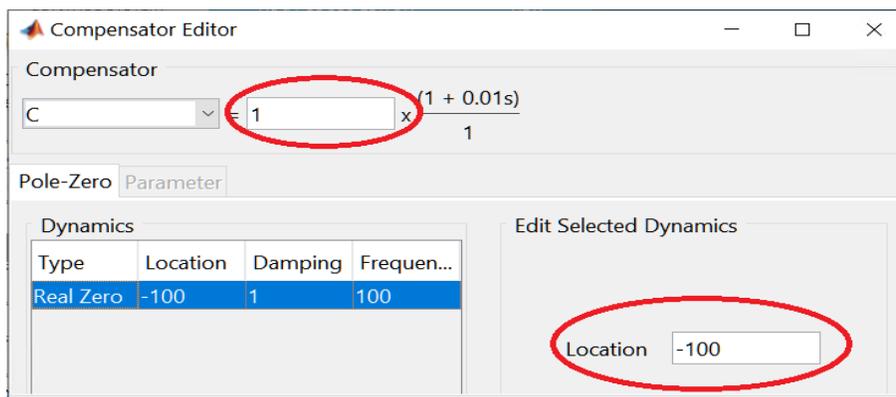
Step 4: Show the following plots:

- From the menu of **Tuning Methods**, choose **Root Locus Editor**.
- From the *New Plot* tab, select a plot type – **Step** to plot the closed-loop Step response ($r2y$).
- Right click the Step Response, choose **Design Requirements/New**, then input the design requirements above.
- Display specific performance characteristics for your system. Right-click to select performance characteristics from characteristic options you can choose peak response, settling time, rise time, and steady state.
- Read these characteristics and fill into attached Table 1.

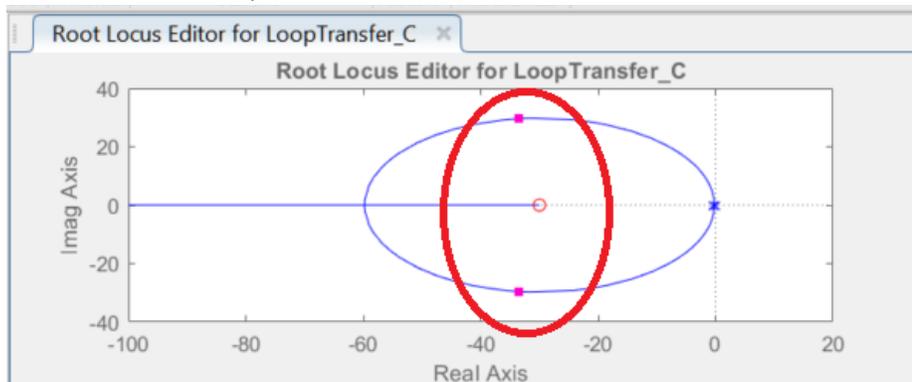


Step 5: Tune PID Controller:

- Right click **Root Locus Editor**, then select **Edit Compensator**, click Real Zero, shown as below:



- Note $C = K_p + K_d \cdot s$, choose K_p of Compensator C from 0.5 to 2.0 and set the location of real zero between -20 to -100, then
- Check of the response **Time** and transient behavior to see if the Step response meets the requirements, OR
- Use Root Locus editor to drag the pole and zero slowly to tune the parameter dynamically.
- Record two sets of K_p and K_d into the table below.



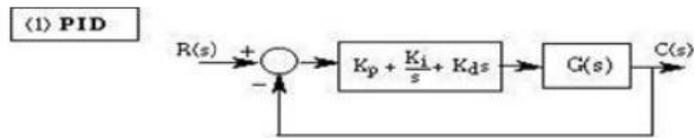
Step 6: Write MATLAB simulation code with tuned values:

- Save *ecp220_pid.m* as *ecp220_pid_tuned.m*,
- Update PID Controller **C** the tuned values of K_p and K_d ,
- Use the function ***feedback(C*G, 1)*** to calculate the closed-loop transfer function,
- Run Linear System Analyser (*ltiview*) to check the system step response.

Attach your code in the lab report.

7.3.3 Verification

Verify the design on ECP220:



- Run ECP Exclusive,
- Reset the controller from the Utility menu. From the Set Up Control Algorithm menu, implement the "PID" with the following settings: $T_s = 0.00442s$, tuned K_p , K_i and K_d with the Continuous Time type,
- Perform a closed-loop step test using a Step Size of 4000 Counts, Dwell Time of 4000 ms and Number of Repetitions 1.

Record the result into the below table and compare it with the simulation, if necessary repeat the above procedure to tune the controller and verify the design again.

LAB REPORT

1. Verification result

Table 1: PID Controller

Parameters	K =		J =		B =	
Characteristics	Rising Time		%Overshoot		Settling Time	
	<i>Matlab</i>	<i>ECP220</i>	<i>Matlab</i>	<i>ECP220</i>	<i>Matlab</i>	<i>ECP220</i>
Kp = 1.0, Kd=0.01						
Kp = Kd=						
Kp = Kd=						

2. Comment on the comparison of Sisotool and ECP220 results.

APPENDIX-A: EXPECTATIONS OF ORIGINALITY

Faculty of Engineering and Computer Science

Expectations of Originality

This form sets out the requirements for originality for work submitted by students in the Faculty of Engineering and Computer Science. Submissions such as assignments, lab reports, project reports, computer programs and take-home exams must conform to the requirements stated on this form and to the Academic Code of Conduct. The course outline may stipulate additional requirements for the course.

1. Your submissions must be your own original work. Group submissions must be the original work of the students in the group.
2. Direct quotations must not exceed 5% of the content of a report, must be enclosed in quotation marks, and must be attributed to the source by a numerical reference citation². Note that engineering reports rarely contain direct quotations.
3. Material paraphrased or taken from a source must be attributed to the source by a numerical reference citation.
4. Text that is inserted from a web site must be enclosed in quotation marks and attributed to the web site by numerical reference citation.
5. Drawings, diagrams, photos, maps or other visual material taken from a source must be attributed to that source by a numerical reference citation.
6. No part of any assignment, lab report or project report submitted for this course can be submitted for any other course.
7. In preparing your submissions, the work of other past or present students cannot be consulted, used, copied, paraphrased or relied upon in any manner whatsoever.
8. Your submissions must consist entirely of your own or your group's ideas, observations, calculations, information and conclusions, except for statements attributed to sources by numerical citation.
9. Your submissions cannot be edited or revised by any other student.
10. For lab reports, the data must be obtained from your own or your lab group's experimental work.
11. For software, the code must be composed by you or by the group submitting the work, except for code that is attributed to its sources by numerical reference.

You must write one of the following statements on each piece of work that you submit:

² Rules for reference citation can be found in "Form and Style" by Patrich MacDonagh and Jack Bordan, fourth edition, May, 2000, available at <http://www.encs.concordia.ca/scs/Forms/Form&Style.pdf>.
Approved by the ENCS Faculty Council February 10, 2012

For individual work: **“I certify that this submission is my original work and meets the Faculty's Expectations of Originality”**, with your signature, I.D. #, and the date.

For group work: **“We certify that this submission is the original work of members of the group and meets the Faculty's Expectations of Originality”**, with the signatures and I.D. #s of all the team members and the date.

A signed copy of this form must be submitted to the instructor at the beginning of the semester in each course.

I certify that I have read the requirements set out on this form, and that I am aware of these requirements. I certify that all the work I will submit for this course will comply with these requirements and with additional requirements stated in the course outline.

Course Number: _____ Instructor: _____

Name: _____ I.D. # _____

Signature: _____ Date: _____