The Iterative Algorithm of Tuning Controllers to the Model Object with Advance and Inertia Second Order

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***Abstract* — This paper proposes an iterative algorithm of tuning the typical controllers PI, PID to the model objects with advance and inertia (second order). The proposed algorithm is using the maximal stability degree method for tuning controllers. As the result of this study the algorithm of tuning controllers and the procedure of determining the system's performance in dependence of maximal stability value is proposed.**

***Index Terms* — the iterative algorithm, the maximal stability degree method, tuning of controllers**

I. INTRODUCTION

During the automation of many slow technological processes the mathematical objects' models of control process are represented as the models with advance and respectively order inertia [1,2,3,4].

The procedure of tuning controllers to the model object with inertia and anticipation becomes difficult [1,2,3,4]. This paper analyses the model object (fixed part) with advance and inertia (second order) with transfer function, which is presented in the follow form

$$H_{PF}(s) = \frac{b_0 s + b_1}{a_0 s^2 + a_1 s + a_2}, \tag{1}$$

where b_0, b_1, a_0, a_1, a_2 are the parameters of object.

It is proposed to tune the standard controllers PI and PID using the maximal stability degree (M.S.D) method [3,5,6] to the model object (1) with known parameters b_0, b, a_0, a_1, a_2 and to analyse the dynamic of control system for the case when it varyies the object's parameters from the nominal values keeping the tuning parameters of controllers PI and PID.

II. THE ITERATIVE ALGORITHM OF TUNING CONTROLLERS

We assume that the control system is formed of an object with transfer function $H_{PF}(s)$, which is presented in relation (1), and transfer function of controller $H_R(s)$ with typical control laws PI, PID, Fig.1.

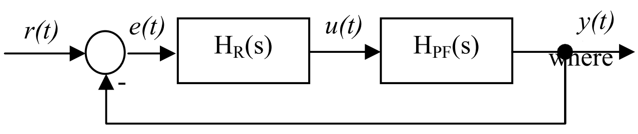

Figure 1. Structure scheme of control system.

It will tune the typical algorithms of tuning PI and PID for the model object with known parameters, using the M.S.D. method.

For the tuning of the PID controller using the M.S.D. method the algebraic expressions [5,6] were applied, which are the analytical expressions

$$k_p = \frac{d_o J^3 - d_1 J^2 + d_2 J - d_3}{\left(b_1 - b_0 J\right)^2}\ , \tag{2}$$

$$k_i = \frac{a_0 J^3 - a_1 J^2 + a_2 J}{-b_0 J + b_1} + k_p J, \tag{3}$$

where
$d_0 = 2a_0 b_0$,
$d_1 = 3a_0 b_1 + a_1 b_0$,
$d_2 = 2a_1 b_1$,
$d_3 = a_2 b_1$.

The optimal values of parameters k_p and k_i of PI controller were determined from expressions (2) and (3).

In the case of tuning parameters of PID controller using the M.S.D. method the algebraic expressions [5,6] were applied, which are the analytical expressions

$$k_p = \frac{d_0 J^3 - d_1 J^2 + d_2 J - d_3}{\left(b_1 - b_0 J\right)^2} + 2k_d J, \tag{4}$$

where
$d_0 = 2a_0 b_0$,
$d_1 = 3a_0 b_1 + a_1 b_0$,
$d_2 = 2a_1 b_1$,
$d_3 = a_2 b_1$,

$$k_i = \frac{a_0 J^3 - a_1 J^2 + a_2 J}{b_1 - b_0 J} - k_d J^2 + k_p J, \tag{5}$$

$$k_d = \frac{-d_0 J^4 + d_1 J^3 - d_2 J^2 + d_3 J - d_4}{2\left(b_1 - b_0 J\right)^4}, \tag{6}$$

where $d_0 = 2a_0 b_0^3$,
$d_1 = 8a_0 b_0^2 b_1$,
$d_2 = 12 a_0 b_0 b_1^2$,

$d_3 = 6a_0b_1^3 + 2a_1b_0b_1^2 - 2a_2b_0^2b_1$.

From expressions (4), (5) and (6) were determined the optimal values of parameters k_p, k_i and k_d of PID controller.

The tuning parameters of PI and PID controller - k_p , k_i and k_d are the function of known parametrs of control object and of the unknown value J stability degree of control system: $k_p=f(J)$, $k_i=f(J)$, $k_d=f(J)$ (see relations (2), (3), (4), (5) and (6)). Based on these relations in the case of known object's parameters and in the case of variation stability degree $J \geq 0$ in the strict limits, the respectivie calculations were made and the dependences $k_p=f(J)$, $k_i=f(J)$, $k_d=f(J)$ for PI and PID controllers were obtained.

A simulation was made to verify the performance of control system. If the performance doesn't satisfy the imposed performance, the iterative process will choose other sets of values of controllers parameters from curves $k_p=f(J)$, $k_i=f(J)$, $k_d=f(J)$, the procedure will repeat until the performance of system will be satisfied.

III. APPLICATION AND COMPUTER SIMULATION

To show the efficiency of the proposed algorithm for tuning the typical controllers PI, PID to the model of object (1), which has the following parameters

b_0=0,874, b_1=0,236, a_0=1, a_1=1,248, a_2=0,274

the procedure described above for tuning typical controllers will be used.

For the relations $k_p=f(J)$, $k_i=f(J)$ of PI controller (see relations (2), (3)) with the known parameters values of object and at the variation of stability degree J in the respectively limits the iterative calculations were made and the obtained results are presented in the Fig. 2.

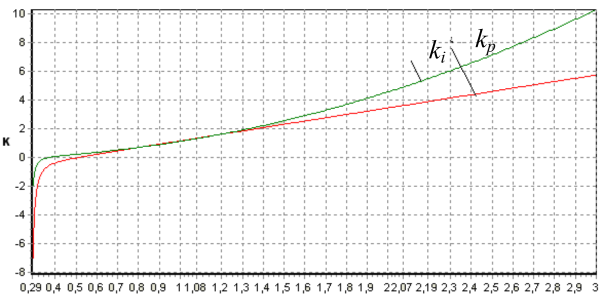

Figure 2. The dependence of *PI* controller parameters of the stability degree value.

The iterative calculations were made for the relations $k_p=f(J)$, $k_i=f(J)$, $k_d=f(J)$ of PID controllers (see relations (4), (5) and (6)) with the known parameters values of object and at the variation of stability degree J in the respectively limits and the obtained results are presented in the Fig. 3.

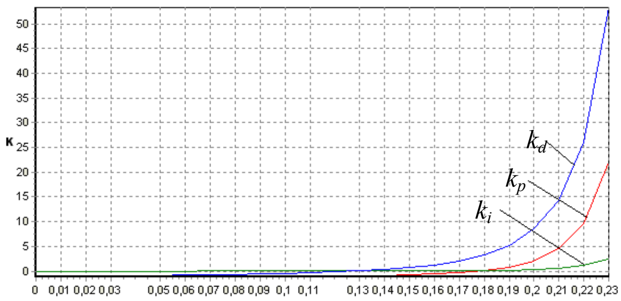

Figure 3. The dependence of PID controller parameters of the stability degree value.

The sets of values J - k_p, k_i for the PI controller (Table I) and J - k_p , k_i, k_d for the PID controller (in Table II) were chosen to analyse the set of performance of control system with PI and PID controllers from Fig. 2 and 3.

To verify the obtained results in case of tuning controllers PI, PID to the model object (1) using the M.S.D. a computer simulation of the control system in MATLAB was made.

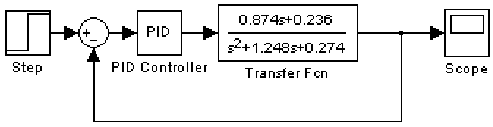

Figure 4. Simulation diagrams of the control system.

The obtained results of the tuning of PI controller, using M.S.D. are presented in the figure 5, where curve *1* – was obtained for the values presented in the Table I, row 1; curve *2* – was obtained for the values presented in the Table I, row *2*; curve *3* – was obtained for the values presented in Table I, row 3.

TABLE I. THE VALUES OF THE PI CONTROLLER'S PARAMETERS

Item	J	k_p	k_i
1	1	1.164	1.123
2	2	3.127	4.22
3	3	5.723	10.215

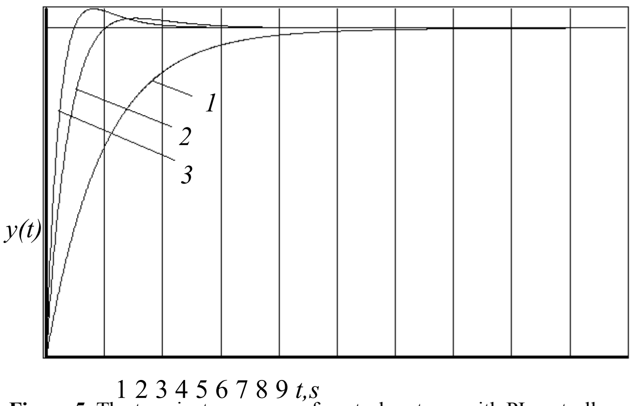

Figure 5. The transient processes of control systems with PI controller.

Analysing the performance of the control system from Fig. 5 it was observed that the optimal performances were obtained for curves with $J_{opt}=3$, $\varepsilon = \pm 5$ % and t_r=2 s, but for the other transitional processes the tuning times are: for curve *1* – 2.5 s, curve *2* – 5.4 s.

The obtained results of the tuning PID controller, using M.S.D. are presented in the figure 6, where curve *1* – was obtained for the values presented in the Table II, row 1; curve *2* – was obtained for the values presented in the Table II, row 2; curve *3* – was obtained for the values presented in the Table II, row 3; curve *4* – was obtained for the values presented in the Table II, row 4.

TABLE II. THE VALUES OF THE PID CONTROLLER'S PARAMETERS

Item	J	k_p	k_i	k_d
1	0,19	0,101	0.098	3.29
2	0.2	0.822	0.166	5.221
3	0.21	2.095	0.291	8.451
4	0.23	22	2.5	54

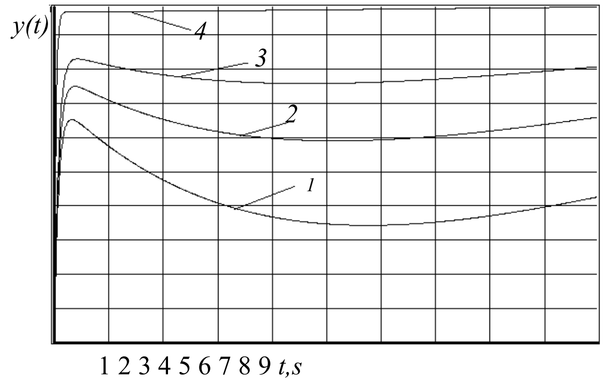

Figure 6. The transient processes of control systems with *PID* controller.

Analysing the performance of the control system from Fig. 6 it was observed that the optimal performances were obtained for curves with $J_{opt}=0.23$, $\varepsilon = \pm 5$ % and $t_r=0.2$ s.

In the Fig. 7 an overlapping of the processes is presented for the following cases: curve *1* - transient processes in the case of the tuning PI controller for the optimal values, curve *2* - transient processes in the case of the tuning PID controller for the optimal values.

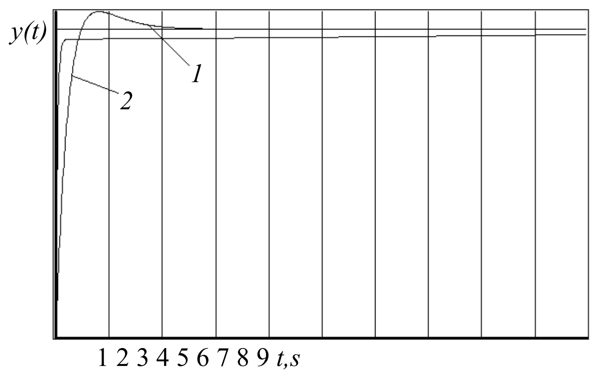

Figure 7. The transient processes of control systems with PI, PID controller.

Fig. 8 presents the domination poles: *1* – for the control system with PI controller tuning by M.S.D. method, the minimal pole has the value - 0,27; *2* - for the control system with PID controller tuning by M.S.D. method, the minimal pole has the value - 0,108.

Analyzing the distribution of poles of characteristic equations of control system with PI, PID controllers tuning by M.S.D., it can be observed that the relative stability of the control system with PI controllers tuning by M.S.D. method has the reserve of stability much higher (≥ 2.5 times) than the reserve of stability of the control system with PID controller tuning by M.S.D. method.

It follows that the robustness of control system with PI controller tuning by M.S.D. method in the case of the variation of parameters of the control object (1) is higher than the robustness of control system with *PID* controller tuning by M.S.D. method.

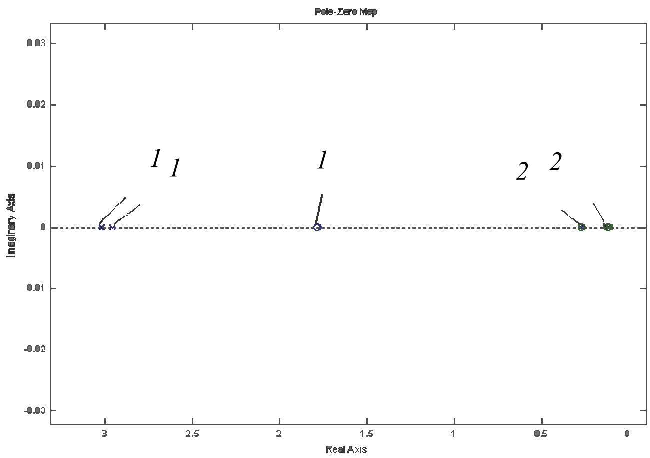

Figure 8. The distribution of the characteristic equation's poles.

IV. CONCLUSION

As a result of the study, the following conclusion can be made:

- The grafo-analitical method of tuning PI, PID controllers to the model objects with inertia second order and anticipation, which permitted to obtain the settled performance, is proposed.
- For the control system with PI controller tuning by M.S.D. method, the transition process of system is aperiodic and optimal for the given values of object (see the curve 1, fig. 7). The robustness of control system with PI controller tuning by M.S.D. method in the case of the variation of parameters of the control object (1) is higher than the robustness of control system with PID controller tuning by M.S.D. method.
- For the control system with PID controller tuning by M.S.D. method the transition process of system is also aperiodic for the given values of the object (view the curve 2 fig. 7), but with lesser relative stability than control system with PI controller.

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