EI5503 CONTROL SYSTEM ANALYSIS AND DESIGN

ASSIGNMENT REPORT ON

MODELLING OF CONICAL TANKUSING MATLAB - SIMULINK

Submitted by

Gayathri R 2019505012

Rakhul Kumar B 2019505033

V – SEMESTER B.E (E&I)

DEPARTMENT OF INSTRUMENTATION ENGINEERING

MADRAS INSTITUTE OF TECHNOLOGY CAMPUS

ANNA UNIVERSITY,

CHROMEPET, CHENNAI – 600044.

AIM

To derive the transfer function and state space model of a conical process tank analytically and verify the same using simulation.

ABSTRACT

The control of liquid level is mandatory in process industries. But the control of nonlinear process is complex. Many process industries use conical tanks because of its nonlinear shape which contributes better drainage for solid mixtures, slurries and viscous liquids. For example, a level well above the surface can upset the process reaction balances and damage equipment, but a level below the required setpoint can also cause serious problems.

So, level control of conical tank presents a challenging task due to its non- linearity and constantly changing cross-section. The main objective is to implement the suitable controller design for conical tank system to maintain the desired level.

SYSTEM DESCRIPTION

The conical tank level process is a highly nonlinear process because of its varying cross section from bottom to top. The experimental setup is shown in Fig. 1. The parameters that vary with respect to the process variable are considered. At a fixed outlet flow rate the system is controlled and maintained at the desired level. The tank level process to be simulated is single input single output (SISO) tank system. The desired level **h** is maintained by manipulating the inlet flow rate $\mathbf{F_{in}}$ to the system. Here **h** is the controlled variable and $\mathbf{F_{in}}$ is the manipulated variable.

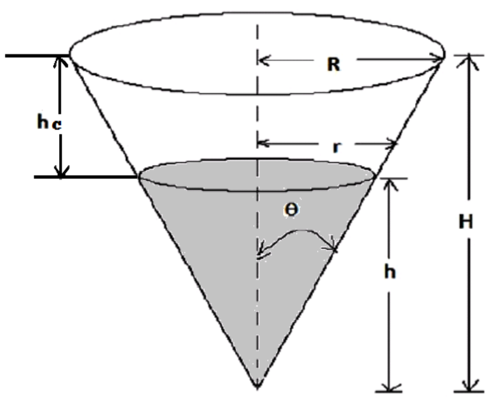

Fig. 1

Table 1.Operating Parameters

Sl. No	Parameter	Description	Value
1	R	Total radius of the cone	19.25cm
2	H	Height of the tank	73cm
3	Fin	Maximum inflow rate of the tank	400 LPH
4	β	Value co-efficient	55cm ^{2}/s

Table. 1

DERIVATION

$$\frac{dh}{dt} = \frac{Fin - K\sqrt{h}}{\pi(\frac{R}{H})^2 h^2}$$

$$\alpha = \frac{1}{\pi(\frac{R}{H}^2)h^2} \quad \cancel{\beta = \alpha K v}$$

$$\frac{dh}{dt} = \alpha h^{-2} Fin - \beta h^{\frac{-3}{2}} \qquad \text{(Equation 1)}$$

$$\frac{dh_s}{dt} = \alpha F_{in.s} h_s^{-2} - \beta h_s^{\frac{-3}{2}} \qquad \text{(Equation 2)}$$

$$\alpha F_{in.s} = \beta\, h_s^{1/2} \qquad \text{(Equation 3)}$$

$$y = h - h_s \qquad \text{(Equation 4)}$$

$$Let\ F_{in}\ be\ Q$$

$$u = F_{in} - F_{in.s}$$

Equation 1 – Equation 2

$$\frac{d}{dt}(h - h_s) = [\alpha F_{in} h^{-2} - \alpha F_{in.s} h_s^{-2}] - \beta h^{\frac{-3}{2}} + \beta h_s^{\frac{-3}{2}}$$

$$\frac{dy}{dt} = [\alpha Q h^{-2} - \beta h_s^{\frac{1}{2}} . h_s^{-2} - \beta h^{\frac{-3}{2}} + \beta h_s^{\frac{-3}{2}}]$$

$$\frac{dy}{dt} = \alpha Q h^{-2} - \beta h^{-3/2} \qquad \text{(Equation 5)}$$

$$Let\ Q h^{-2} = f(h, Q)$$

$$By\ Taylor\ Series\ Expansion,\ to\ linearize\ [Qh^{-2}]\ and\ [h^{-3/2}]$$

$$f(h, Q) = f(h_s, Q_s) + \frac{\partial}{\partial h} f(h - h_s) + \frac{\partial}{\partial Q} f(Q - Q_s) + Higher\ Order$$

$$Qh^{-2} = Q_s h_s^{-2} - 2Q_s h_s^{-3}(h - h_s) \; + h_s^{-2}(Q - Q_s)$$ (Equation 6)

$$h^{-3/2} => f(h) = f(h_s) + \frac{f^{'}(h)(h - h_s)}{1!} + Higher\ Order\ Terms$$

$$h^{-3/2} = h_s^{-3/2} - \frac{3}{2} hs^{-5/2}(h - h_s)$$ (Equation 7)

Substitute Equation 6 and Equation 7 in Equation 5; From Equation 4

$$\frac{dy}{dt} = [\alpha Q_s h_s^{-2} - 2\alpha Q_s h_s^{-3}(y) + \alpha h_s^{-2}(u)] - \beta[h_s^{-3/2} - \frac{3}{2} h_s^{-5/2} y]$$

$$\frac{dy}{dt} = -2\alpha Q_s h_s^{-3} y + \alpha h_s^{-2} u + [\frac{3}{2}\beta h_s^{-5/2} y]$$

$$\frac{dy}{dt} = -2\beta h_s^{-5/2} y + \frac{3}{2}\beta h_s^{-5/2} y + \alpha h_s^{-2} u$$

$$\tfrac{dy}{dt} = \beta h_s^{-5/2} y(\tfrac{3}{2} - 2) + \alpha h_s^{-2} u$$

$$\frac{dy}{dt} = \frac{-1}{2}\beta h_s^{-5/2} y + \alpha h_s^{-2} u$$

$$\frac{2}{\beta}\, h_s^{5/2}(\frac{dy}{dt}) + y = \frac{2\alpha}{\beta}\, h_s^{1/2}\, u$$

$$Y(s)\; [\frac{2}{\beta}\, h_s^{5/2}\; s + 1] = U(s)\; [\frac{2\alpha}{\beta}\, h_s^{1/2}\;]$$

$$Transfer\ Function => \frac{Y(s)}{U(s)} = \frac{\frac{2\alpha}{\beta}\, h_s^{1/2}}{(\frac{2}{\beta}\, h_s^{5/2})\, s + 1}$$ (Equation 8)

$$Time\ Constant = \tau = \frac{2}{\beta}\, h_s^{5/2}$$

$$Steady\ State\ Gain = K = \frac{2}{K_v} h_s^{1/2}$$

From **Table 1**,

$$F_{in} = 400\,lph = \frac{1000}{9}\,cm^3/s \qquad K_v = 55\ cm^2\ s^{-1}$$

$$H = 73\,cm\ \ and\ \ R = 19.25\,cm \qquad \alpha = \frac{1}{\pi(\frac{R}{H})^2} = 4.57756 \qquad \beta = \alpha K_v = 251.7658$$

$$@\ Steady\ State\ (h - > h_s)$$

$$\frac{dh}{dt} = 0\ \ => \frac{F_{in} - K_v\sqrt{h_s}}{\pi(\frac{R}{H})^2 h_s^2} = 0$$

Hence, $F_{in} = K_v\sqrt{h_s}$

$$(1000/9 * 55)^2 = h_s$$

$$h_s = 4.0812\,cm$$

Substitute the steady state parameters in the transfer function,

$$TF = \frac{(\frac{2}{K_v})h_s^{1/2}}{[(\frac{2}{\beta})h_s^{5/2}]\ (s+1)}$$

$$=> \frac{0.07346}{0.26730s + 1}$$

$$TF = \frac{0.2748}{s + 3.741}$$

Thus the $TF = \frac{0.2748}{s+3.741}$ is obtained by analytical method.

MATLAB SIMULATION

The differential equation is simulated in MATLAB (Simulink), with $\mathbf{F_{in}}$ = 400 lph (111.111 cm^3/s) applied as a step input, the steady state value of **h ($\mathbf{h_s}$)** is obtained as 4.081 cm.

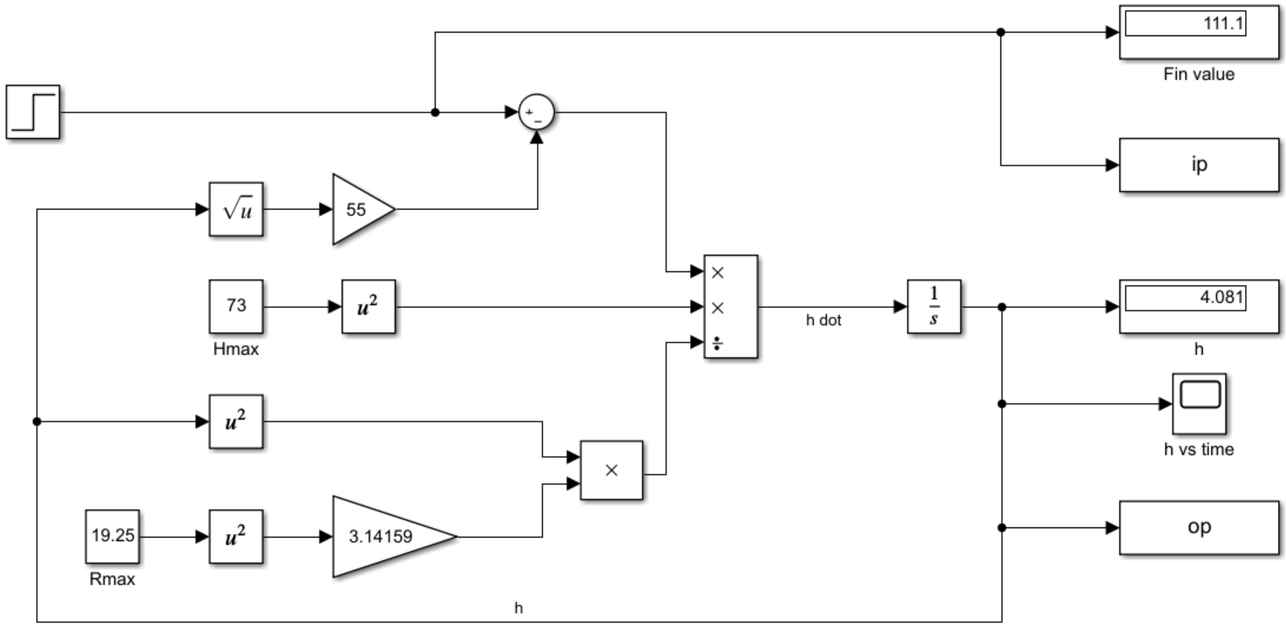

Fig. 2

GRAPH

Simulated height response

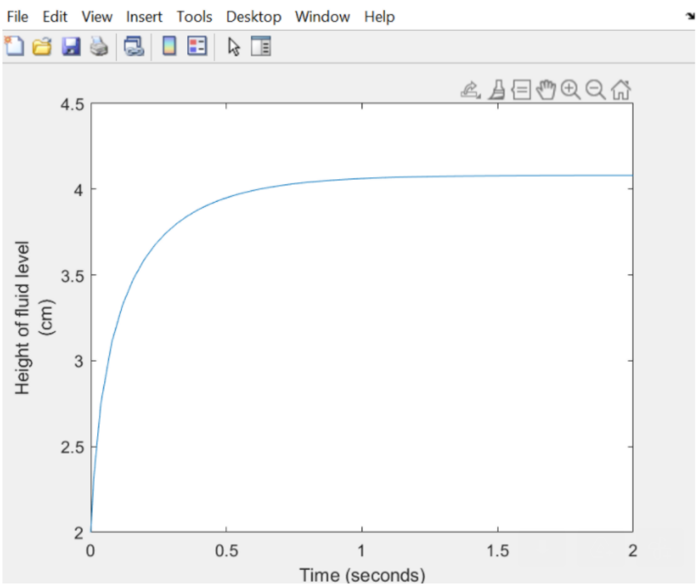

Fig. 3

The transfer function of the system is obtained by using “linmod” command,

>> [numerator, denominator] = linmod (‘file name’, output, input)

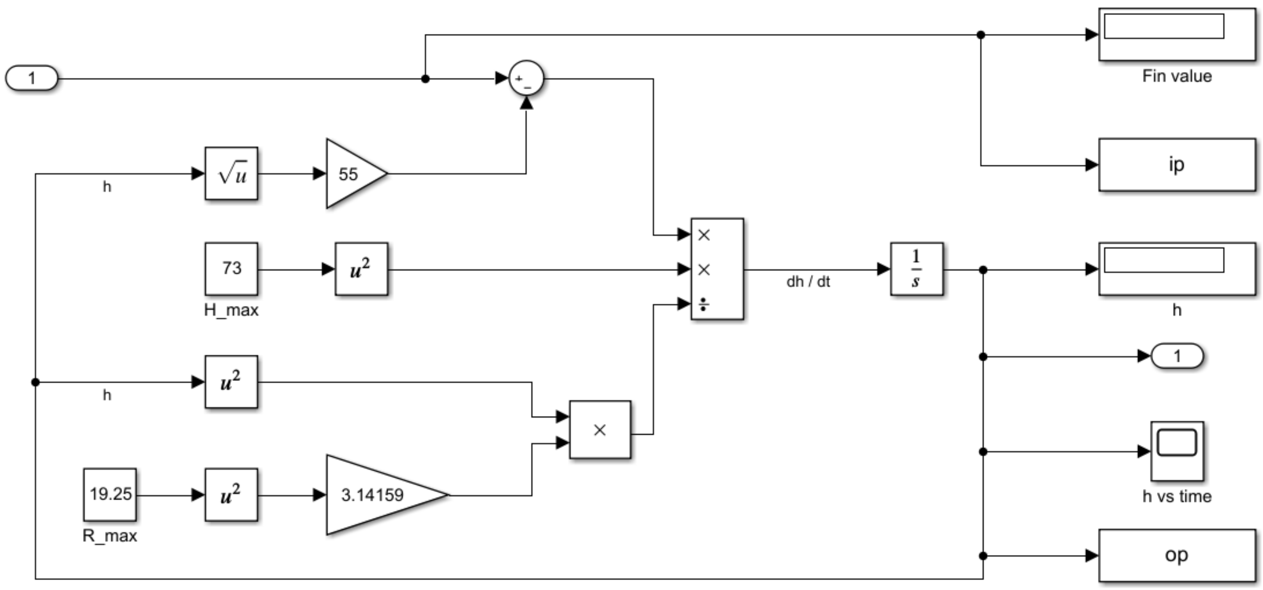

Fig. 4

<u>TRANSFER FUNCTION BY SIMULATION</u>

Command Window

```
>> [n, d] = linmod('conicaltank', 4.0812, 111.111)
n =

         0    0.2748


d =

    1.0000    3.7411

>> sys = tf(n,d)

sys =

   0.2748
  ---------
  s + 3.741

Continuous-time transfer function.
```

STATE SPACE MODEL

Mathematical model of any physical system is given by,

$$\dot{x} = Ax + Bu$$
$$y = Cx + Du$$

where,

A = system matrix
B = input matrix
C = output matrix
D = transition matrix
x = state vector
u = input vector
y = output vector

In the conical tank system, the state space model is represented as,

$$\dot{x} = A\,x + B\,\boldsymbol{F_{in}}$$
$$\boldsymbol{h} = C\,x + D\,\boldsymbol{F_{in}}$$

which can be obtained from the transfer function, $Transfer\ Function => \frac{Y(s)}{U(s)} = \frac{\frac{2\alpha}{\beta}\,h_s^{1/2}}{(\frac{2}{\beta}\,h_s^{5/2})\,s+1}$

$$\frac{h}{Fin} = \frac{0.2748}{s+3.741}$$

Hence, the state space model is,

$$\dot{x} = [-3.741]\,x + [1]\,\boldsymbol{F_{in}}$$
$$\boldsymbol{h} = [0.2748]\,x + [0]\,\boldsymbol{F_{in}}$$

STATE SPACE MODEL BY SIMULATION

Command Window

```
>> [A,B,C,D] = tf2ss(n,d)

A =

   -3.7411


B =

     1


C =

    0.2748


D =

     0
```

RESULT

Thus the transfer function and the state space models are obtained for conical process tank on the given operating point analytically and verified by simulating in MATLAB using Simulink.