University of Bristol

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Sensors, Signals and Control

Part 1: Identification of Transfer Functions

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1 Introduction and Open Loop Discussion

This report compares the experimental and theoretical transfer functions of 3 degree of freedom Quanser-Control rig. Control design is important to understand the behaviour of a dynamic system, and then improve the performance. Sensors and actuators are used in the Quanser to measure and vary performance characteristics of the Quanser. In this case, an elevation change was introduced to the Quanser in order to observe an oscillating damped behaviour. Measuring this response a theoretical transfer function was then estimated.

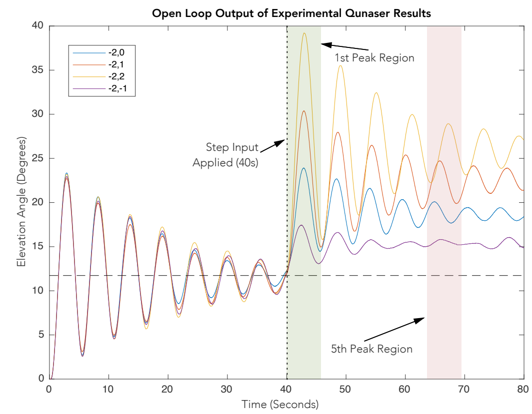


Figure 1: Graph Showing the Open Loop Nature of the Experimental Quanser Response

An Open-Loop system is a where behavioural characteristics can be controlled manually. These changes are not feedback into the system, therefore the output has no effect on the input of the system [1] meaning self-correction is not possible. In the case of the Quanser-Control Rig, elevation angle was independent of the output and manually controlled, whereas pitch and travel data was manually feedback to the system. Figure 2 shows the open loop behaviour of the elevation axis, as the elevation angle was varied between 10 and 40 degrees.

2 Method and Results

2.1 Finding Experimentation Results from Quansers

1. Replace the elevator input with a step block, using the parameters: Start Time: 40s, Start Value: -2, End Value: -1 to 2. This was used to automate the step input at a specific time for each elevator input test. A step input time of 40s was chosen to allow the initial response to settle to an acceptable level (see Figure 2).
2. Use range of elevator input values, varying from an initial value of -2 to 2 in steps of 1. Repeat each test case, saving workspace variables.
3. Check data for anomalies, Averaged repeats for valid results across the different step inputs.

2.2 Analyse Transfer Function

1. Isolate elevation values for corresponding inputs from 40s to 80s; this captures this captures the response after step input.
2. In order to estimate a transfer function - the following parameters were calculated: Natural frequency, Undamped natural frequency and damping ratio, refer to Table **??**.

Table 1: Table Showing Key Parameter Calculations [2],[3]

1-DOF Parameters	Definition	Units	Identification Strategy
Λ_i	Logarithmic Decrement	-	$\Lambda_i = \frac{1}{N}\ln(\frac{y_i}{y_{i+N}})$
ζ_i	Damping Ratio	-	$\zeta_i = \frac{\Lambda_i}{2\pi}$
T_D	Period of damped Oscillation	s	$T_D = \frac{x_{i+N} - x_i}{N}$
ω_D	Damped Natural frequency	$rads^{-1}$	$\omega_D = \frac{2\pi}{T_D}$
ω_0	Undamped Natural Frequency	$rads^{-1}$	$\omega_0 = \frac{\omega_D}{\sqrt{1-\zeta i^2}}$

2.2.1 Second Order

To calculate the Second Order Transfer-Function, a forced response behaviour was noted. Using Table **??** equations [2] [3], in addition to the x and y values taken from the peaks highlighted in figure 2 the logarithmic decrement and the period of damp oscillation was approximated. Using these equations values for the damping ratio ζ and natural frequency ω_n were obtained and substituted into the formal equation shown in equation **??**.

$$\frac{y(s)}{u(s)} = \frac{k \cdot \omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} \tag{1}$$

In order to obtain a single transfer function which represents the system as a whole for varying elevators angle steps, estimated transfer functions were found for each test case. These parameters were then averaged obtaining a single fit transfer function where gain was changed to model different elevator angle step inputs. This captured some of the behaviour of the system as step level varied.

To calculated the a representative gain scaling factor k for each of the step inputs, max elevation for each step input was taken (from the first peak shown in Figure 2). These values were plotted on a graph to find their correlation, shown in figure 3. The gain k value was heuristically adjusting to match the estimated amplitude with the experimental results from -2 to 2, where it was found that $k = 0.26$. This value was used to translate the correlation equation between points into scaling factors.

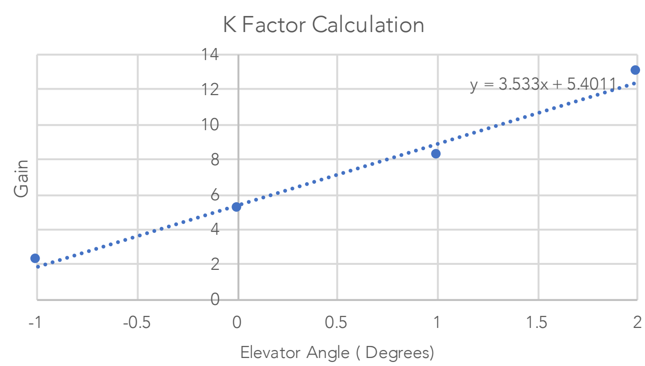


Figure 2: Graph Finding the Gain For Each Step Input

After applying this method, amplitudes for all the steps fitted more closely. Finally damping ratio and undamped natural frequency were tweaked to give the final fit, again by trial and error.

2.2.2 First Order

Standard First Order Response Transfer Function:

$$\frac{y(s)}{u(s)} = \frac{k}{\tau s + 1} \tag{2}$$

Due to the Quanser-Control Rig being a Second Order System Equation 2 was not applicable for finding the First Order Transfer Function. Instead this was estimated by considering the Second Order Transfer Function case where: $\zeta = 1$ and $s^2 = 0$.

$$\frac{k \cdot \omega_n^2}{2\zeta\omega_n s + \omega_n^2} \rightarrow \frac{k \cdot \omega_n^2}{2\omega_n s + \omega_n^2} \tag{3}$$

3 Results

$$\text{2nd Order Transfer Function :} \qquad k \cdot \frac{1.109}{s^2 + 0.1313s + 1.109} \tag{4}$$

Where: $\zeta = 0.0623$ $\omega_n = 1.0532$

$$\text{1st Order Transfer Function :} \qquad k \cdot \frac{1.109}{2.106s + 1.109} \tag{5}$$

Where: $\zeta = 1$ $\omega_n = 1.0532$

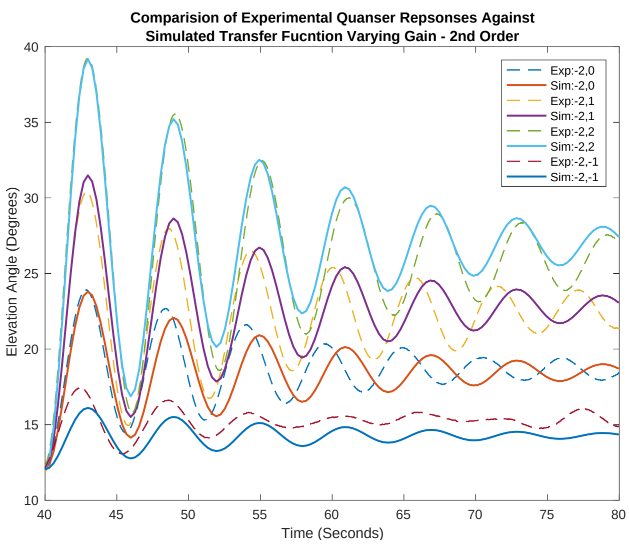


Figure 3: 2nd Order Simualted Transfer Function Comparision

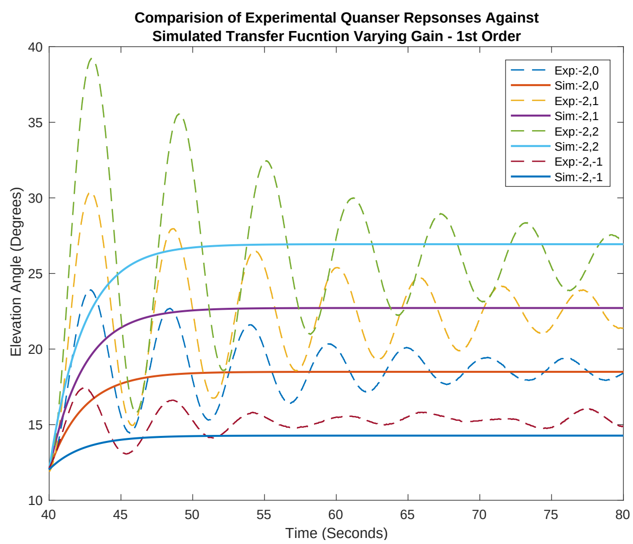


Figure 4: 1st Order Simualted Transfer Function Comparision

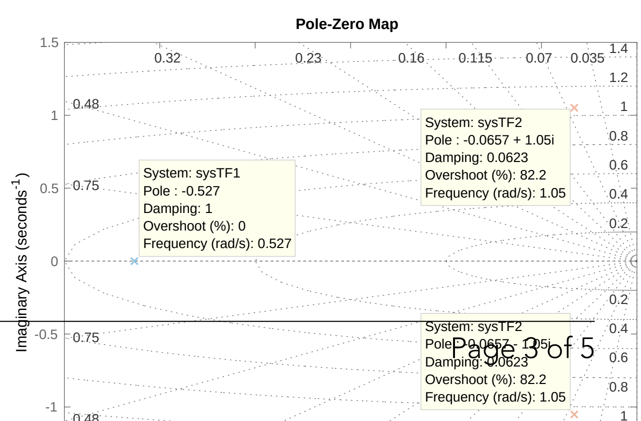
4 Observations and Analysis:

Experimental elevator input

- Step input of 2 was used as the datum which the scaling factors of the other steps was matched against. This results in the 2 step graph being a better fit than the others
- There is an observable phase and amplitude deviation
- Peak amplitude prediction becomes worse for lower amplitude cases
- The upper experimental oscillations were slightly larger than the lower oscillations

Root Locus plot

- The grid lines represent lines of constant damping and lines of natural frequency
- Second order transfer function root locus has a pair of points with an imaginary axis component (complex root) - This shows the underdamped nature of the system as 0<zeta<1
- First order transfer function Root locus point exists purely in the real axis component.



- Increase in gain for the second order shows these roots becoming more positive and negative in the imaginary axis respectively
- Increase in gain for the first order shows the root becoming more negative along the real axis

4.1 Potential Errors

During the quanser operation, a significant observable error was the drift in the quanser-- this was more noticeable when during longer runs. This is potentially due to accumulating error increasing with time duration. Whilst the Quansers have error correcting features -- this is only sensitive to a finite degree so could be considered imperfect. This implies errors may accumulate for a greater run time as the system fails to accurately correct for inconsistencies. Another source of deviation from MATLAB's theoretical transfer function step response - could be the inaccuracy in step input time. Whilst a step block was introduced in the simulink model to automate the `elevator input' at 40 seconds - upon closer observation of the response plots, this was not the case. This was potentially due to accumulated lag in the system and the controller - as a result of computational latency. As a result this likely influenced the initial condition - causing a phase and amplitude shift in experimental results. Another effect of this is; the introduction of error in logarithmic decrement and period of damped frequency calculation as peak points were potentially taken from `error' shifted values. In theory the step input is modelled as an immediate action - whilst experimentally the step response acted over time - this adds to the error shift of the values.

Physically when the Quanser was in operation, there were physical factors to consider when exploring the errors. Friction in the Quanser support hinge potentially resulted in a slightly decreased elevation than desired - this adds to the natural damping response of the system and may explain why the experimental curves in Figure(?) are more compacted time wise than the MATLAB transfer function step plot. However it is useful to note that the MATLAB transfer function was estimated by averaging test cases and hence is derived empirically. The slightly decreased elevation is also compounded by physical wires in the rig which acted as a small `jamming' mechanism to the system.

As with any control system, noise can be introduced by external and internal factors. In the Quanser system - gyro noise and wind resistance were major factors. Sensors in any system measure quantities which need to be controlled - in this case the elevator sensor sampling was stored values at discrete points. Whilst the sampling time was quite small so captured the general nature of the oscillating damped curves - some critical points may have been missed due to this for example at the point of highest amplitude, the inflexion behaviour begins after a region of constant amplitude. Theoretically we see a quicker inflexion transition in this region. see Figure ()?.

Due to the instruction of never taking a step from the `fans off' position (as there are high nonlinear effects during startup) - the initial elevator input was set to -2 (to get the fans running) and then after 40 seconds a elevator step was input into the system. For this reason the step input may have been applied during mid oscillation past the steady state elevation position - this likely either amplified or decreased the actual step input depending on which stage of oscillation the quanser is at.

Above were 1385 words.

References

[1] E. Tutorials. (). Open-loop system and open-loop control systems, [Online]. Available: http://www.electronics-tutorials.ws/systems/open-loop-system.html (visited on 22/02/2017).

[2] D. B. Titurus, ``Vibrations 2 lab notes - tuned vibration absorber'', University of Bristol, Tech. Rep., 2016.

[3] ——, ``Vibrations 2 lecture notes - 2 degree of freedom, tuned vibration absorber'', University of Bristol, Tech. Rep., 2016.