**Executive Summary**

The purpose of this experiment was to accomplish two tasks; to analyze a Controller under three different modes of operation: Proportional (P), Proportional + Integral (PI), and Proportional + Derivate (PD), and using benchmark parameters of Proportional Control to improve the output of the latter two modes of operation.

The second task involved combining of all three modes of operation to achieve a stable Proportional + Integral + Derivative (PID) Controller, and, using one of three methods of tuning: trial-and-error, Ziegler-Nichols “Ultimate Gain” Method or Ziegler-Nichols “Process Reaction” Method, to improve the closed loop response to find the best parameters to meet given specifications.

Certain specifications were to be obtained from the controllers under different gains. The specifications included Percent Overshoot (PO), Settling Time, Rise Time, and Steady State Error for both step and ramp input. In the first part of the lab, all of the transfer functions of each controllers were tested with different gain values and the PI and PD controllers were tested on different time constants as well. It is observed that the specifications will change from gain to another and from time constant as well as the difference between each controller compared to the benchmarked response. Further details will be supported within the report for clarification purposes.

In the last part of this experiment, the three controllers wee all summed up in a parallel connection to come up with what is called the PID controller. The “Ultimate Gain” Method was chosen for designing/tuning the controller which states manipulating the value of the gain of the P controller and getting the period off the plot and then using the modified equations to obtain both integral and derivative time constants that can be achieved of the PID. For our case, the value of the gain of the P controller was 7.1946 and the chosen value was the benchmarked gain which was 3.05 V/V.

**Part 1: Exploring Control Modes (P, PI and PD)**

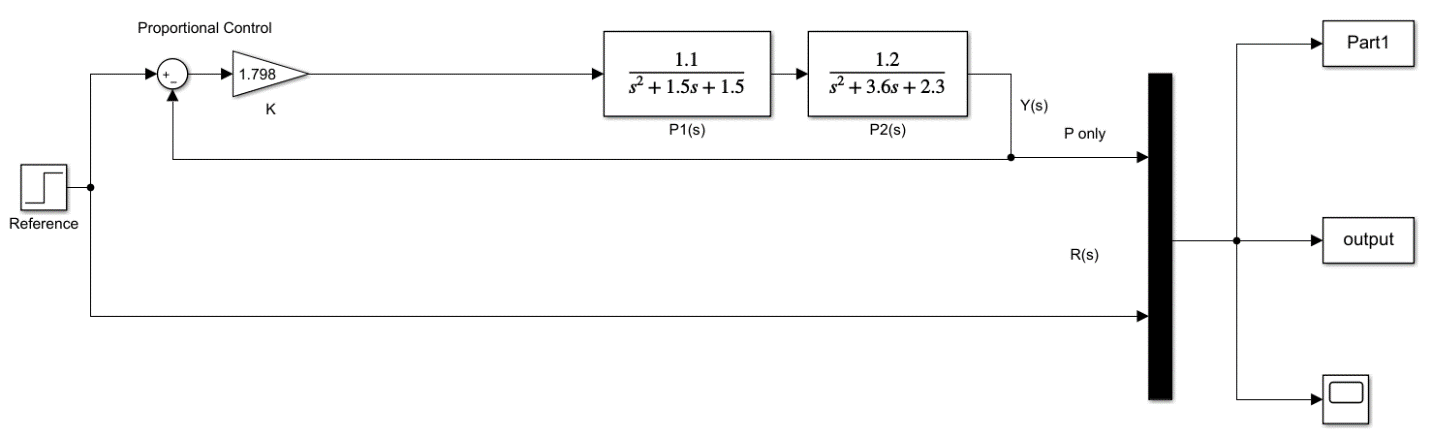
**Proportional (P) Control**

Figure 1: P Controller SIMULINK Diagram

The transfer function used is as follows:

The characteristic equation is:

It was found that the Critical Gain is 7.198.

Different gain values were used, and the results were tabulated in the following table:

Table 1: Steady State Error of P Controller under Different Operational Gain

|  |  |  |
| --- | --- | --- |
| **Proportional Gain Value** “” | **Steady State Output Value** “yss” | **Steady State Error** **Percentage** “ess”(%) |
| 1 | 0.2768 | 73.32 |
| 2 | 0.4335 | 56.65 |
| 3 | 0.5345 | 46.55 |
| 4 | 0.6049 | 39.51 |
| 5 | 0.6568 | 34.32 |
| 6 | 0.6945 | 30.55 |
| 7 | 0.7948 | 20.52 |

The steady state error percentage was calculated using the following equation:

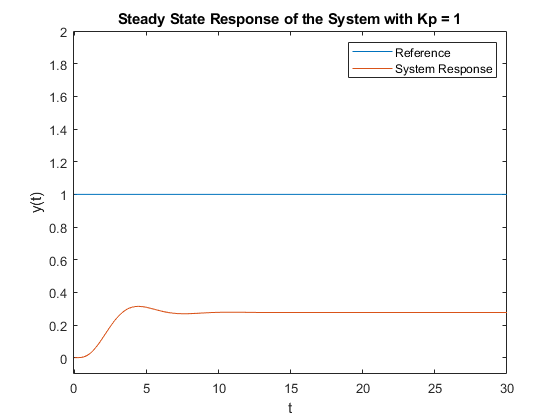
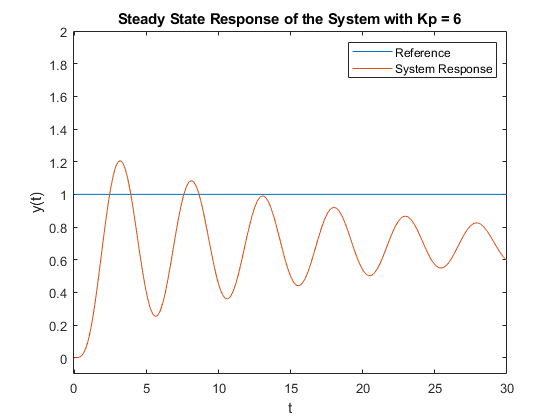
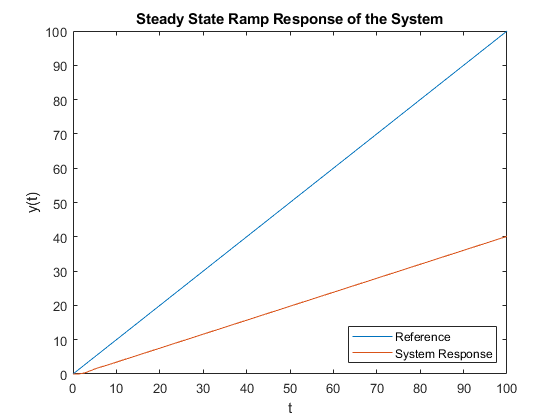
A ramp response was also studied to determine the system steady state response parameters outside of a step response. The results are as follows:

Figure 4: Steady State Response of P Controller with Unit Ramp Reference

Figure 2: Steady State Response of P Controller with Gain = 1

Figure 3: Steady State Response of P Controller with Gain = 6

As seen in the figure above, the ramp response is not an accurate way of determining response parameters as it will have a velocity constant, , of infinity due to the infinitely different slopes between the two signals. This is situation is modeled by the equation:

Furthermore, a unit step response can be used to measure the transient response of the system. These transient response parameters include settling time, percentage overshoot and peak time values. The table below describes the parameters at different values.

Table 2: Transient Parameters of P Controller under Different Operational Gain

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Proportional Gain Value** “” | **Percentage Overshoot** “PO” (%) | **Overshoot Peak Value** “PO” | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| 1 | 13.44 | 0.3140 | 8.3612 | 3.3445 |
| 2 | 27.34 | 0.5520 | 10.70 | 3.01 |
| 3 | 40.29 | 0.7498 | 15.38 | 2.6756 |
| 4 | 51.78 | 0.9181 | 22.40 | 2.3411 |
| 5 | 62.94 | 1.0701 | 34.11 | 2.3411 |
| 6 | 72.37 | 1.1971 | 67.89 | 2.0067 |
| 7 | 67.2623 | 1.3294 | 99.66 | 2.0067 |

To calculate the Percentage Overshoot, the following equation was used:

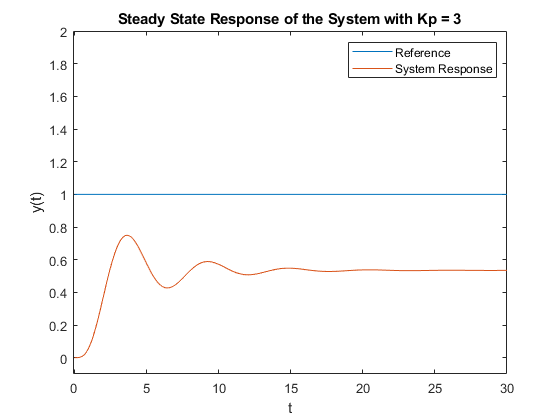
Note that placing reference lines within the MATLAB scope plot and using the cursor function to solve for the time in which the 2% settling occurs was the technique used to determine this settling time. An example plots with proportional gain of 3 can be found below:

Figure 5: Steady State Response of P Controller with Gain = 3

Table 3: Effect on Transient Response of P Controller with Change in Gain

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Proportional Controller Gain** | **ess Step** (%) | **ess Ramp** (%) | **PO** | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| Increase | Decrease | Decrease | Increase | Increase | Decrease |
| Decrease | Increase | Increase | Decrease | Decrease | Increase |

“Benchmarking” the System

The system was “benchmarked” using the “Quarter Decay” response of the Proportional Controller [1]. The Operational Gain to achieve Quarter Decay was done through Trial-And-Error such that:

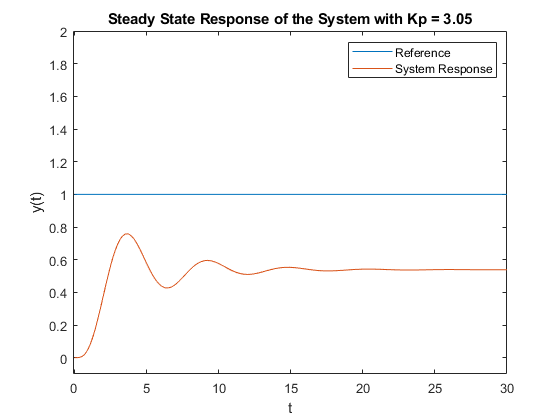


Figure 6: Steady State Response of P Controller when Kp = 3.05

Table 4: Transient Parameters of Benchmarked P Controller

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| **Proportional Gain Value** “” | **Percentage Overshoot** “PO” (%) | **Overshoot Peak Value** “PO” | **Steady State Output Value** “yss” | **Steady State Error** **Percentage** “ess”(%) | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| 3.05 | 40.88 | 0.7587 | 0.5386 | 46.14 | 15.38 | 2.6756 |

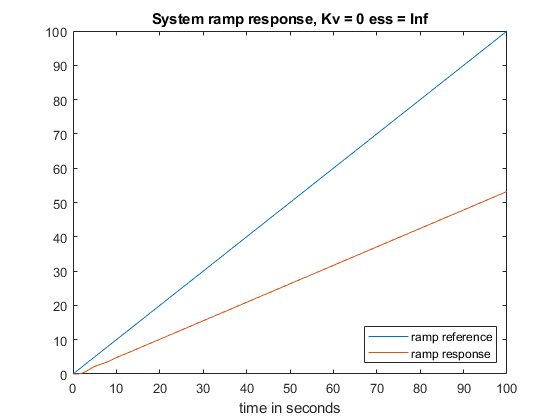


Figure 7: Ramp Response for Benchmark

**Proportional + Integral (PI) Control**

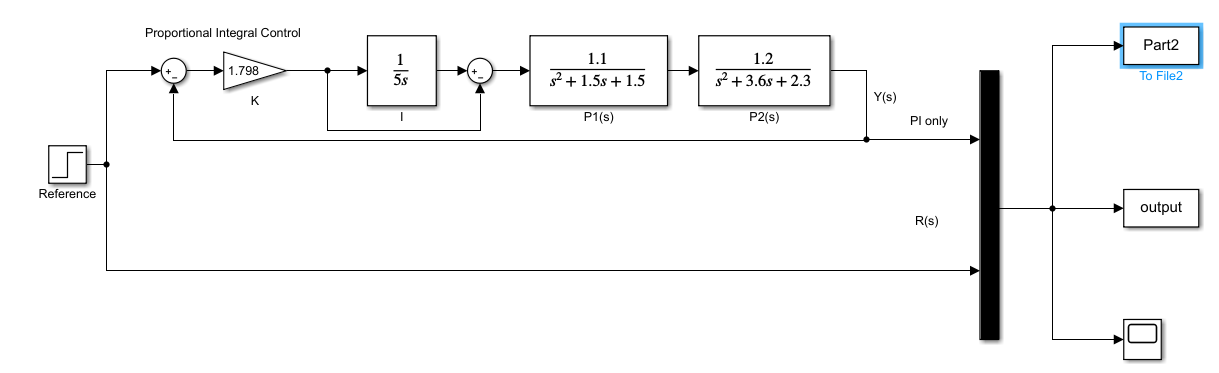


Figure 8: PI Controller SIMULINK Diagram

Proportional + Integral (PI) is used to create a more optimal and accurate system response. The same principles applied to Proportional Control will be applied here again to study the PI response. It is important to note that a value of was used to conduct these studies.

The transfer function used is as follows:

The characteristic equation is:

It was found that the Critical Gain is 6.247.

Different gain values were used, and the results were tabulated in the following table:

Table 5: Steady State Error of PI Controller under Different Operational Gain

|  |  |  |
| --- | --- | --- |
| **Operational Gain Value** “” | **Steady State Output Value** “yss” | **Steady State Error** **Percentage** “ess”(%) |
| 1 | 1 | 0 |
| 2 | 1 | 0 |
| 3 | 1 | 0 |
| 4 | 1 | 0 |
| 5 | 1 | 0 |
| 6 | 1 | 9.43 |

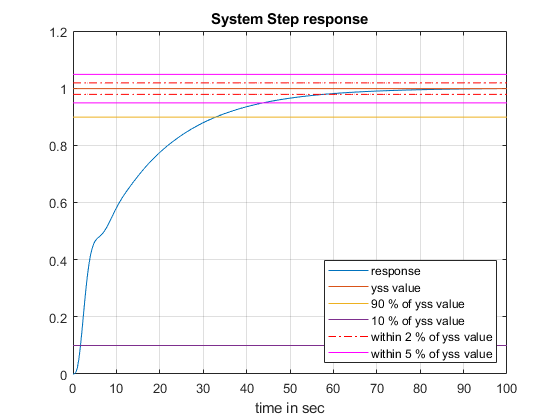
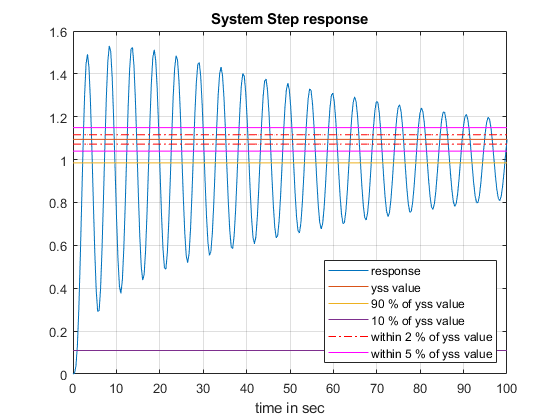
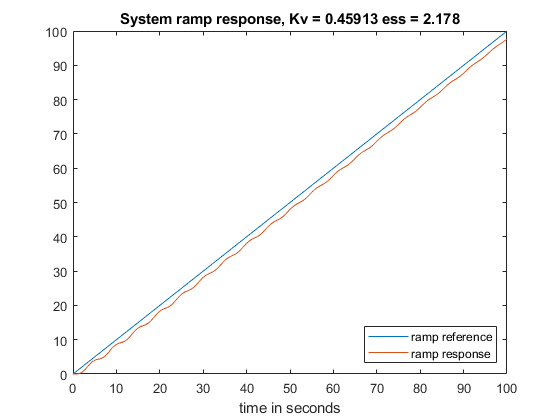
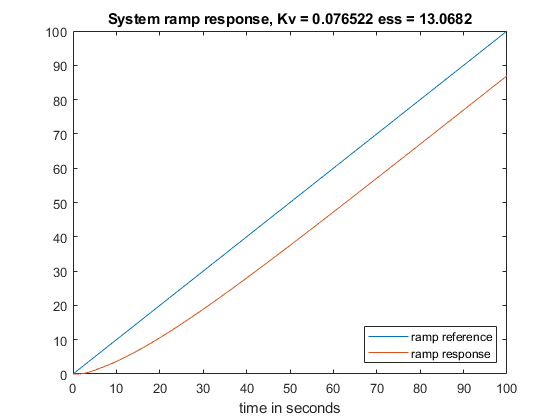


Figure 11: System Ramp Response of PI Controller with Operational Gain = 1

Figure 12: System Ramp Response of PI Controller with Operational Gain = 6

Figure 10: Steady State Response of PI Controller with Gain = 6

Figure 9: Steady State Response of PI Controller with Gain = 1

It is observed from Figure 11 and 12 that the PI Controller Ramp Response continues at a constant slope value similar to the Unit Ramp reference. This situation can be modeled by the equation:

Different responses of has been recorded in the table below:

Table 6: System Ramp Response at Different Operational Gain

|  |  |  |
| --- | --- | --- |
| **Operational Gain Value** “” |  | **System Ramp Error** **Percentage** “ess Ramp”(%) |
| 1 | 0.0765 | 13.0682 |
| 2 | 0.1530 | 6.5341 |
| 3 | 0.2296 | 4.3561 |
| 4 | 0.3061 | 3.2670 |
| 5 | 0.3826 | 2.6136 |
| 6 | 0.4591 | 2.1780 |

As seen from both the graph and the calculations, the error continues to infinity at a constant value. This value depends on the two variables, and . With this information at hand, the steady state transient response parameters can be evaluated as they were for the P Controller. The following table describes these findings:

Table 7: Transient Parameters of P Controller under Different Operational Gain

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Operational Gain Value** “” | **Percentage Overshoot** “PO” (%) | **Overshoot Peak Value** “PO” | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| 1 | 0 | 0 | 57.52 | 92.3077 |
| 2 | 0 | 0 | 33.44 | 63.5452 |
| 3 | 0 | 0 | 25.41 | 49.8328 |
| 4 | 17.49 | 1.1749 | 24.08 | 3.0100 |
| 5 | 33.59 | 1.3359 | 49.16 | 2.6756 |
| 6 | 39.82 | 1.3982 | 99.66 | 2.6756 |

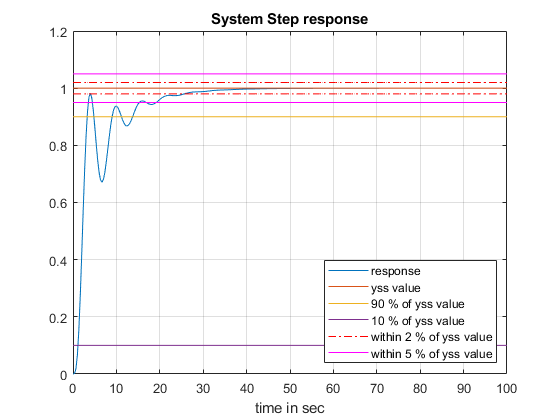


Figure 13: Steady State Response of PI Controller with Gain = 3

Table 8: Transient Response with Varying Time Constant Values

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| **Operational Gain Value** “” | **Integral Time Constant** | **Steady State Output Value** “yss” | **Steady State Error** **Percentage** “ess”(%) | **Overshoot Peak Value** “PO” | **Percentage Overshoot** “PO” (%) | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| 3.05 | 10 | 1 | 0 | 1.3598 | 35.98 | 99.33 | 2.34 |
| 3.05 | 3 | 1 | 0 | 0 | 0 | 19.06 | 36.45 |
| 3.05 | 1 | 1 | 0 | 0 | 0 | 10.03 | 15.38 |

Using the benchmarked Operational Gain value, the different time constants are used to test transient parameters. The benefit of the PI System can be observed as there is no Steady State Error, ensuring the system will always be at the reference point. It can be observed that as the Integral Time Constant increases, the parameters get worse. It is also worth noting that the PI Controller presents worse transient parameters in comparison to the P Controller, with the TSettle 2% and TRise 0-100%being considerably worse.

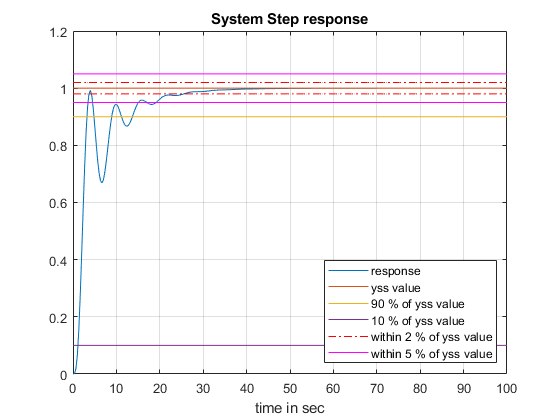


Figure 14: Steady State Response of PI Controller with Time Constant = 3

Table 9: Effect on Transient Response of PI Controller with Change in Gain and

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Operational Controller Gain** | **ess Step** (%) | **ess Ramp** (%) | **PO** | **TSettle 2%** (s) | **TRise 0-100%** (s) |
| Gain increase | No change | Decrease | Increase | Increase | Decrease |
| Gain decrease | No change | Increase | Decrease | Decrease | Increase |
| increase | No change | No change | Increase | Increase | Decrease |
| decrease | No change | No change | Decrease | Decrease | Increase |

**Proportional + Derivative (PD) Control**

**Part 2: PID Control**

**Discussion**

**References**

[1]"PID Controller Tuning Techniques | ECE Tutorials", *Ecetutorials.com*. [Online]. Available: http://ecetutorials.com/process-control/pid-controller-tuning-techniques/.