

Control Systems

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CONTENTS

1	Frequency Response Analysis	1
1.1	Polar Plot	1

Abstract—The objective of this manual is to introduce control system design at an elementary level.

Download python codes using

svn co <https://github.com/gadepall/school/trunk/control/ketan/codes>

1 FREQUENCY RESPONSE ANALYSIS

1.1 Polar Plot

1.1.1. A position control system is to be designed such that maximum peak overshoot is less than 25 %. Further, appropriate error constant should be 50. For the motor to be used, load and torque speed curve is shown below, where, $J_1 = 2 \text{ kg-m}^2$, $J_2 = 18 \text{ kg-m}^2$, $f_1 = 2 \text{ N-m/s/rad}$, $f_2 = 36 \text{ N-ms/rad}$. (Although obvious, consider position as the controlled variable and armature voltage as the manipulated variable.).

- Design a lead compensator for the system.
- Design a lag compensator for the system.

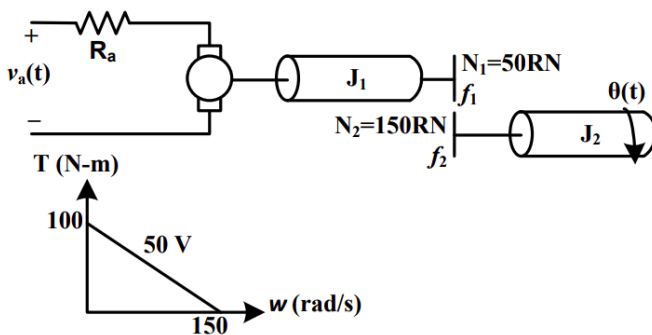


Fig. 1.1.1

Solution: Solving the system shown in 1.1.1,

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From load-torque curve of DC Motor

$$T_m = 2V_a - \frac{2}{3}\omega_1 \quad (1.1.1)$$

Let T_1 , ω_1, θ_1 be the Torque, Angular velocity, Angular displacement on J_1

$$T_m = T_1 + J_1\ddot{\theta}_1 + f_1\dot{\theta}_1 \quad (1.1.2)$$

Similarly for J_2

$$T_1 = J_2\ddot{\theta}_2 + f_2\dot{\theta}_2 \quad (1.1.3)$$

$$T_2 = \frac{N_2}{N_1}T_1 \quad (1.1.4)$$

$$\theta_2 = \frac{N_1}{N_2}\theta_1 \quad (1.1.5)$$

On solving the equations (1.1.1), (1.1.2), (1.1.3), (1.1.4) & (1.1.5)

$$V_a = 6\ddot{\theta}_2 + 10\dot{\theta}_2 \quad (1.1.6)$$

Taking Laplace transform

$$G(s) = K \frac{\theta(s)}{V_a(s)} = \frac{1}{2s(3s+5)} \quad (1.1.7)$$

From Error Constant $K = 500$

$$G(s) = \frac{\theta(s)}{V_a(s)} = 250 \frac{1}{s(3s+5)} \quad (1.1.8)$$

$$\zeta = 0.0695 \quad (1.1.9)$$

$$M_p = e^{\frac{-\zeta\pi}{\sqrt{1-\zeta^2}}} = 81.6\% \quad (1.1.10)$$

$$\phi_M = \tan^{-1}\left(\frac{2\zeta}{\sqrt{-2\zeta^2 + \sqrt{4\zeta^4 + 1}}}\right) \quad (1.1.11)$$

Specifications	Actual	Expected
OS%	81.6%	25%
ζ	0.0695	0.403
ϕ_m	7.35°	39.5°

TABLE 1.1.1: Table of Specifications

$$\phi_{max} = 39.5^\circ - 7.35^\circ + \text{correction factor}$$

$$\phi_{max} = 57^\circ$$

Designing a lead compensator Let

$$G_c(s) = \frac{1}{a} \frac{s + \frac{1}{T}}{s + \frac{1}{aT}} \quad (a < 1) \quad (1.1.12)$$

$$\sin \phi_{max} = \frac{a - 1}{a + 1} \quad (1.1.13)$$

$$a = 0.1 \quad (1.1.14)$$

$$|G(j\omega_c)| = \frac{1}{\sqrt{a}} = 10dB \quad (1.1.15)$$

$$\omega_c = 5^\circ \text{ (Refer figure 1.1.3)} \quad (1.1.16)$$

$$T = \frac{1}{\omega_c \sqrt{a}} \quad (1.1.17)$$

$$T = 0.632 \quad (1.1.18)$$

$$G_c(s) = 10 \frac{s + 1.6}{s + 16} \quad (1.1.19)$$

$$G(s)G_c(s) = 2500 \frac{s + 1.6}{s(3s + 5)(s + 16)} \quad (1.1.20)$$

Designing a lag compensator

$$G_c(s) = \frac{1}{b} \frac{s + \frac{1}{T}}{s + \frac{1}{bT}} \quad (b > 1) \quad (1.1.21)$$

$$\phi_{max} = 39.5^\circ - 7.35^\circ + \text{correction factor} \quad (1.1.22)$$

$$\phi_{max} = 45^\circ \quad (1.1.23)$$

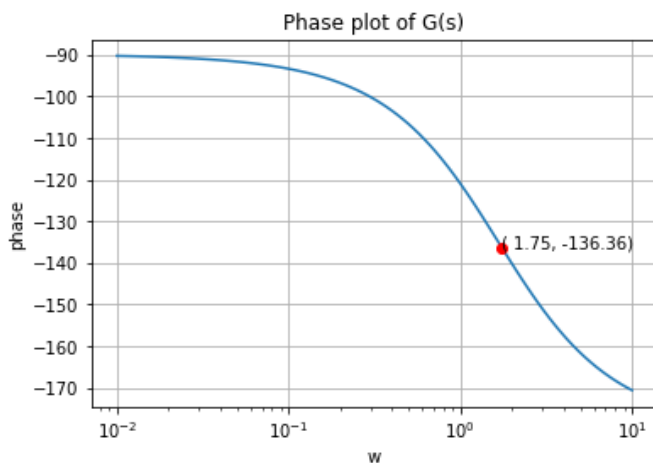


Fig. 1.1.2: Phase plot of G(s)

ω_c = Frequency at which phase of bode plot of G(s) is $-180 + \phi_{max}$ i.e. -135°

$\omega_c = 1.75 \text{ rad/sec}$ as in Figure 1.1.2

We place the zero at

$$\omega = 0.2\omega_c = 0.35 \text{ rad/sec} \quad (1.1.24)$$

$$\frac{1}{T} = 0.35 \quad (1.1.25)$$

$$T = 2.85 \quad (1.1.26)$$

The following code plots the following bode

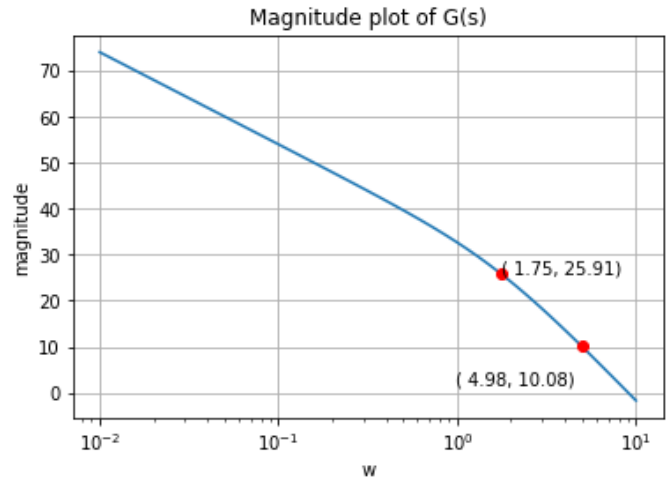


Fig. 1.1.3: Magnitude plot of G(s)

plots

codes/ee18btech11001/ee18btech11001_1.py

The magnitude of $G(j\omega)$ at the new gain crossover frequency $\omega_c = 1.75 \text{ rad/sec}$ is 26 dB as in figure 1.1.3. In order to have ω_c as the new gain crossover frequency, the lag compensator must give an attenuation of -26 dB at ω_c

$$-20 \log b = -26 \text{ dB} \quad (1.1.27)$$

$$b = 19.95 \approx 20 \quad (1.1.28)$$

$$G_c(s) = 0.05 \frac{s + 0.35}{s + 0.0175} \quad (1.1.29)$$

$$G(s)G_c(s) = 12.5 \frac{s + 0.35}{s(3s + 5)(s + 0.0175)} \quad (1.1.30)$$

Performance Evaluation of compensators

The following code plots the performance curves

codes/ee18btech11001/ee18btech11001_2.py

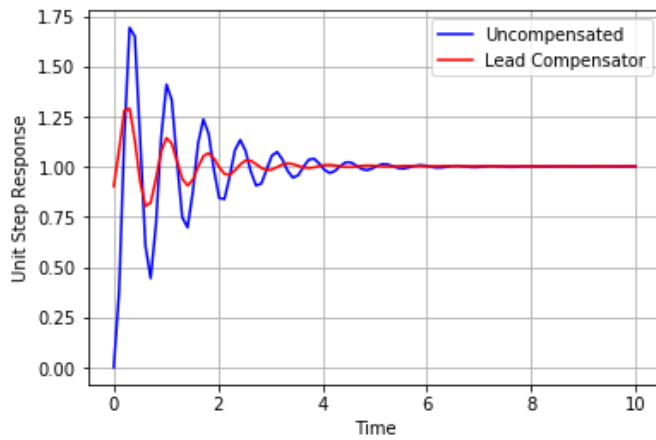


Fig. 1.1.4: Performance of Lead Compensator

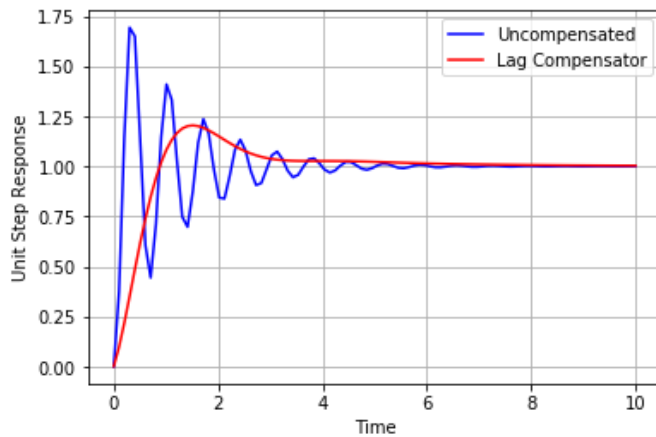


Fig. 1.1.5: Performance of Lag Compensator

Compensator	Actual OS%	Expected OS%
Lead Compensator	26%	25%
Lag Compensator	25%	24%

TABLE 1.1.2: Performance comparison