
Hard Disk Design

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Task 1

The differential equation of input voltage and head position is given, so it is pretty easy to get the open loop transfer function by taking the lapalce transform of both side and can easily get

$$\frac{Y(s)}{U(s)} = \frac{1}{Js^2 + bs}$$

Task 2

open loop transfer function is given by multiplying both G1 and G2

$$G1(s)G2(s) = \frac{Km}{(Ls + R) * (Js^2 + bs)} = \frac{Km}{LJs^3 + Lbs^2 + RJs^2 + Rbs}$$

```
s = tf('s');
J = 1;
b = 20;
R = 1;
L = 0.001;
Km = 5;
G1 = Km/(L*s+R)
G2 = 1/(J*s^2+b*s)
openTF = G1*G2
t=[0:0.005:0.5];
y = step(openTF,t);
plot(t,y);
```

G1 =

$$\frac{5}{0.001 s + 1}$$

Continuous-time transfer function.

$G2 =$

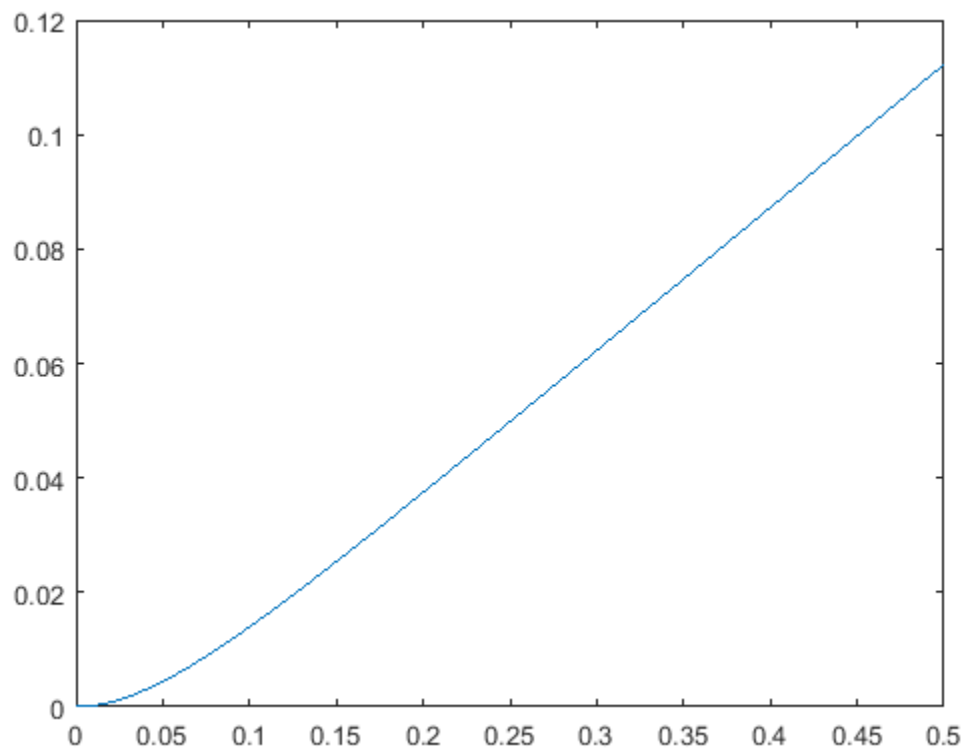
$$\frac{1}{s^2 + 20 s}$$

Continuous-time transfer function.

$openTF =$

$$\frac{5}{0.001 s^3 + 1.02 s^2 + 20 s}$$

Continuous-time transfer function.



You can see that if a constant voltage is applied, then the read head will moves in a constant speed. And at the begining when the voltage is applied, there is a curve, which indicates that the read head is accelerating under applied voltage.

Task 3a

The proportional compensator is applied, so that the open loop transfer function is given by

$$K a * G1(s) * G2(s)$$

and closed loop transfer function is given by

$$\frac{K a * G1(s) * G2(s)}{1 + K a * G1(s) * G2(s)}$$

after plug in $G1(s)G2(s)$ from previous computation, we have

$$\frac{K a * K m}{L J s^3 + (L b + R J) s^2 + R b s + K a K m}$$

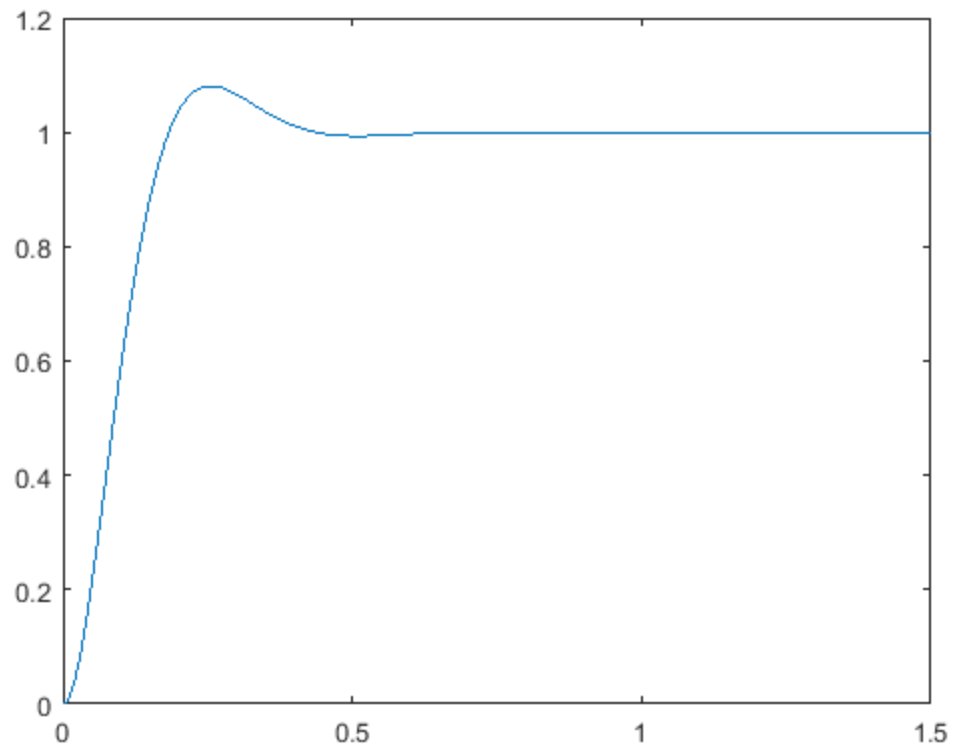
Try plugging in $K a = 50$, we can get the following plot

```
Ka = 50;
t=[0:0.005:1.5];
ProportionalTF =(Ka*G1*G2)/(1+Ka*G1*G2)
y = step(ProportionalTF, t);
plot(t,y);
```

ProportionalTF =

$$\frac{0.25 \, s^3 + 255 \, s^2 + 5000 \, s}{1e-06 \, s^6 + 0.00204 \, s^5 + 1.08 \, s^4 + 41.05 \, s^3 + 655 \, s^2 + 5000 \, s}$$

Continuous-time transfer function.



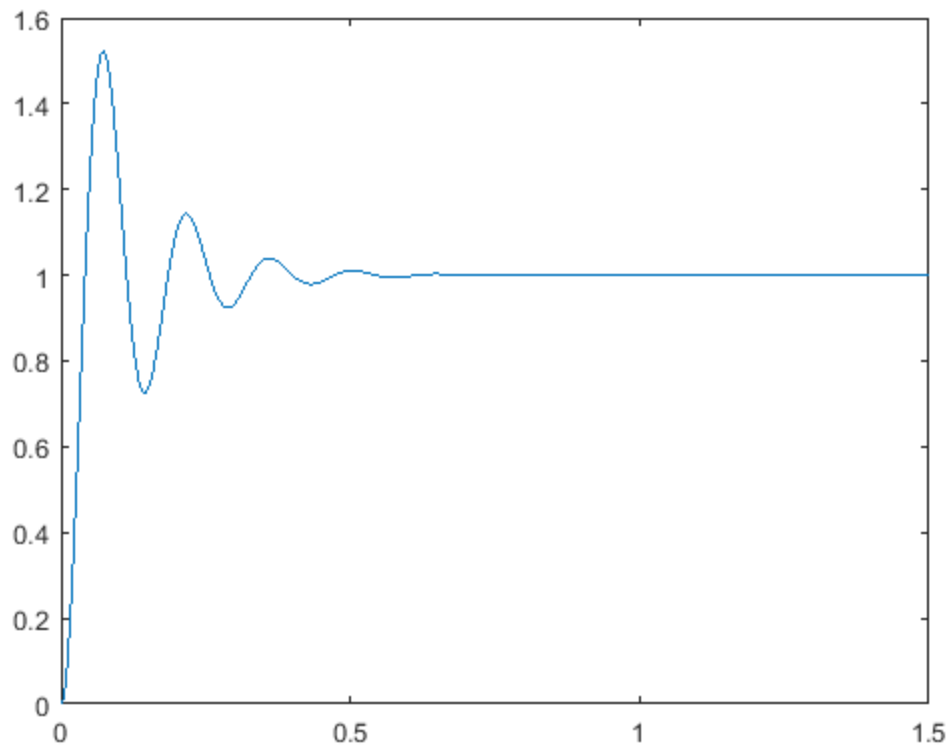
Then applied step when $K_a = 400$

```
Ka = 400;
ProportionalTF = (Ka*openTF)/(1+Ka*openTF)
y = step(ProportionalTF, t);
plot(t,y);
```

ProportionalTF =

$$\frac{2 s^3 + 2040 s^2 + 40000 s}{1e-06 s^6 + 0.00204 s^5 + 1.08 s^4 + 42.8 s^3 + 2440 s^2 + 40000 s}$$

Continuous-time transfer function.



Clearly you can see that the $K_a=50$ has less over shoot than $K_a=400$ does. This is because for $K_a=400$, the feedback amplification is too big and make system too sensitive.

Task 3b

So when disturbance is Introduced to the system, the disturbance input flows into system between $G1$ and $G2$. So that we can derive the transfer function for disturbance:

$$Tw = \frac{G2(s)}{1 + Ka * G1(s) * G2(s)}$$

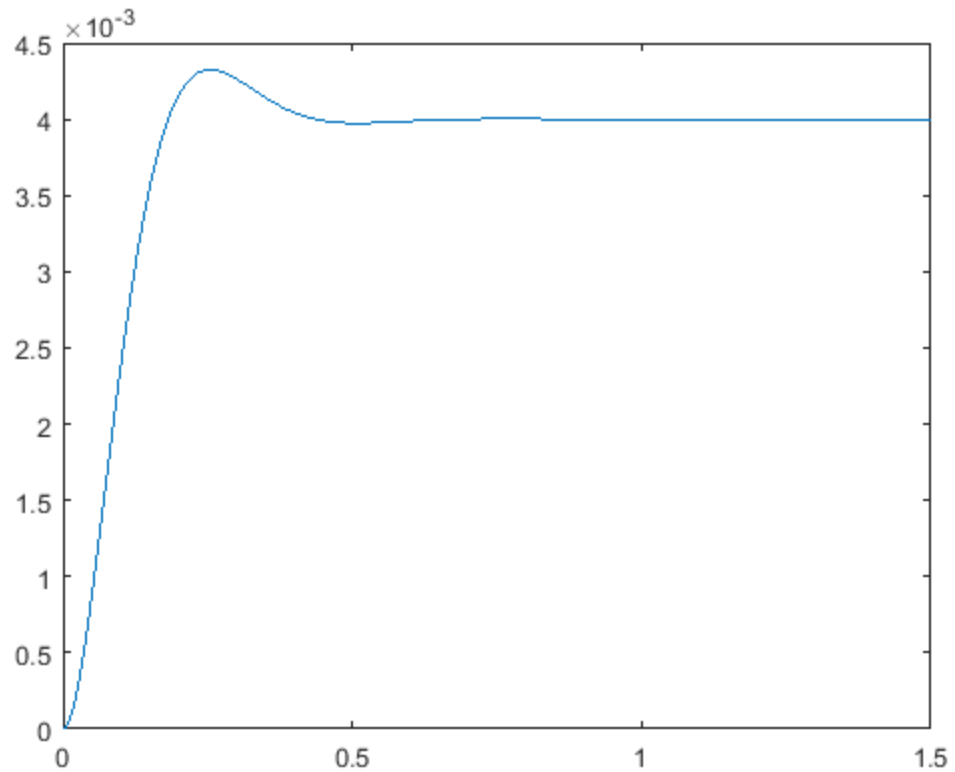
First plot the response of disturbance in case of $Ka = 50$

```
Ka = 50;
Tw = G2/(1+Ka*G1*G2)
y = step(Tw, t);
plot(t,y);
```

$Tw =$

$$\frac{0.001 s^3 + 1.02 s^2 + 20 s}{0.001 s^5 + 1.04 s^4 + 40.4 s^3 + 650 s^2 + 5000 s}$$

Continuous-time transfer function.



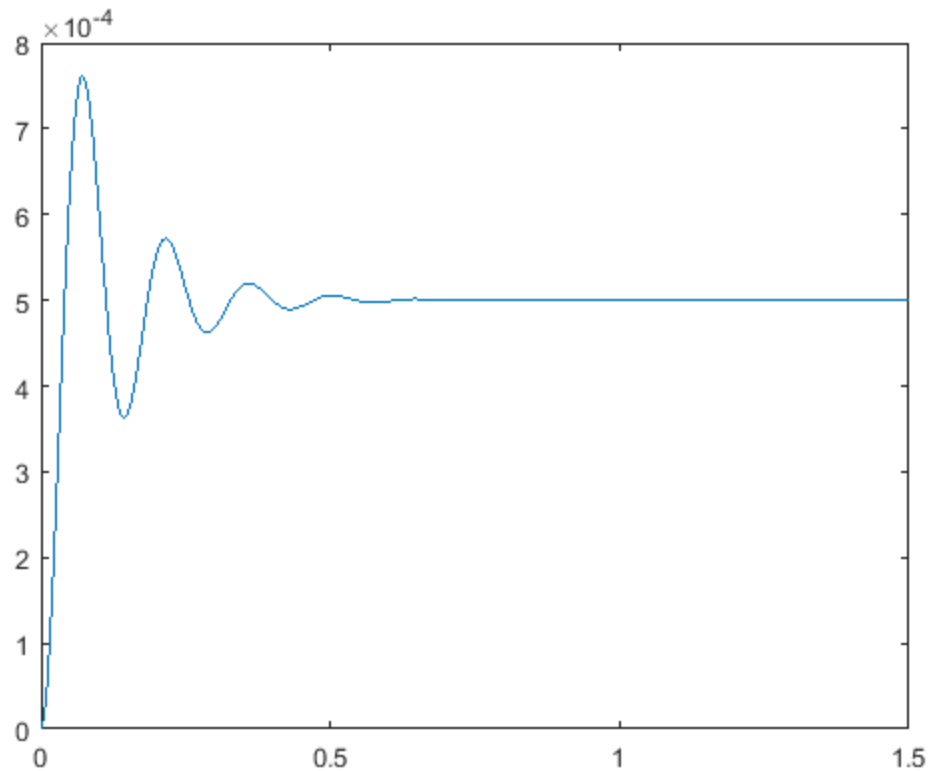
Then plot the response of disturbance in case of $K_a = 400$

```
Ka = 400;
Tw = G2/(1+Ka*G1*G2)
y = step(Tw, t);
plot(t,y);
```

$T_w =$

$$\frac{0.001 s^3 + 1.02 s^2 + 20 s}{0.001 s^5 + 1.04 s^4 + 40.4 s^3 + 2400 s^2 + 40000 s}$$

Continuous-time transfer function.



Task 3C

We can plot overshoot percentage and settling time as a function of K_a , and analyze the optimal K_a for the system

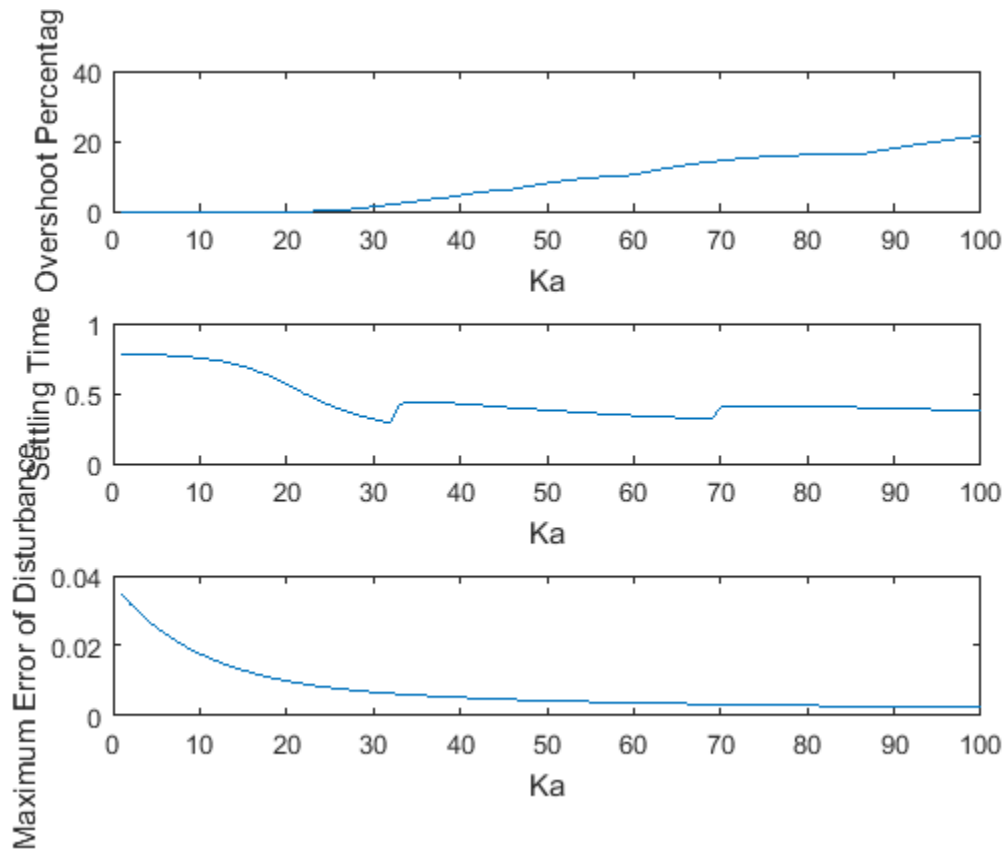
```

overshoot = [];
settlingTime = [];
maxError = [];
n=[1:100];
t=[0:0.05:0.8];
for Ka=n
    ProportionalTF = (Ka*openTF)/(1+Ka*openTF);
    y = step(ProportionalTF, t);
    info = stepinfo(y, t, 'SettlingTimeThreshold', 0.02);
    overshoot = [overshoot, info.Overshoot];
    settlingTime = [settlingTime info.SettlingTime];

    Tw = G2/(1+Ka*G1*G2);
    y = step(Tw, t);
    maxError = [maxError max(y)];
end
subplot(3,1,1);
plot(n,overshoot);xlabel('Ka');ylabel('Overshoot Percentage');
subplot(3,1,2);
plot(n,settlingTime);xlabel('Ka');ylabel('Settling Time');
subplot(3,1,3);

```

```
plot(n,maxError);xlabel('Ka');ylabel('Maximum Error of Disturbance');
```



For overshoot less than 5%, Ka is required to be equal or less than 41, Ka value that satisfy settling time requirement is more than 100 and is not in the graph. For disturbance less than 0.005, Ka is required to be equal or bigger than 41. Clearly, you cannot satisfy three requirements at the same time.

Task 4

The closed loop transfer function in this case would be

$$\frac{KaG1(s)G2(s)}{1 + KaH(s)G1(s)G2(s)}$$

So both Ka and Kh are varying, so we can plot a 3-D graph in which x axis is Ka and Y axis is Kh and Z axis is the property under examination like Settling Time, Overshoot and disturbance. We can find the candidate that satisfies all three constraints by finding the overlap of Ka and Kh values that satisfies three constraints.

```
[KaRange, KhRange] = meshgrid(55:65, 0:0.01:0.1);
overshootMatrix = [];
settlingTimeMatrix = [];
candidatePairs = [];
t=[0:0.05:0.8];
G12= G1*G2;
```



```

for Kh = KhRange(:,1)'
    %overshootArr=[];
    %settlingTimeArr=[];
    for Ka = KaRange(1,:)
        CLTF = (Ka*G12)/(1+Ka*(1+Kh*s)*G12);
        y = step(CLTF, t);
        info = stepinfo(y, t, 'SettlingTimeThreshold', 0.02);
        %overshootArr = [overshootArr, info.Overshoot];
        %settlingTimeArr = [settlingTimeArr, info.SettlingTime];
        Tw = G2/(1+Ka*(1+Kh*s)*G12);
        y = step(Tw,t);
        maxDisturbance = max(y);

        if(info.Overshoot <= 5 & info.SettlingTime <0.25 & y<0.005)
            candidatePairs = [candidatePairs; Ka, Kh];
        end
    end
    %overshootMatrix = [overshootMatrix; overshootArr];
    %settlingTimeMatrix = [settlingTimeMatrix; settlingTimeArr];
end
%mesh(KaRange, KhRange, settlingTimeMatrix);
%mesh(KaRange, KhRange, overshootMatrix);
candidatePairs

```

```

candidatePairs =

```

```

    56.0000    0.0300
    57.0000    0.0300
    58.0000    0.0300
    59.0000    0.0300
    60.0000    0.0300
    61.0000    0.0300
    62.0000    0.0300
    63.0000    0.0300
    64.0000    0.0300
    65.0000    0.0300

```

We can see that there are bunch of valid pair of Ka and Kh that satisfies the design, we can select Ka = 60 and Kh = 0.03 to examine.

```

Ka = 60; Kh = 0.03;
CLTF = (Ka*G12)/(1+Ka*(1+Kh*s)*G12);
y = step(CLTF, t);
figure(6);
plot(t,y);title('System Step Response');
info = stepinfo(y, t, 'SettlingTimeThreshold', 0.02)

```

```

Tw = G2/(1+Ka*(1+Kh*s)*G12);
y = step(Tw,t);
figure(7);
plot(t,y);title('System Step Disturbance Response');

```

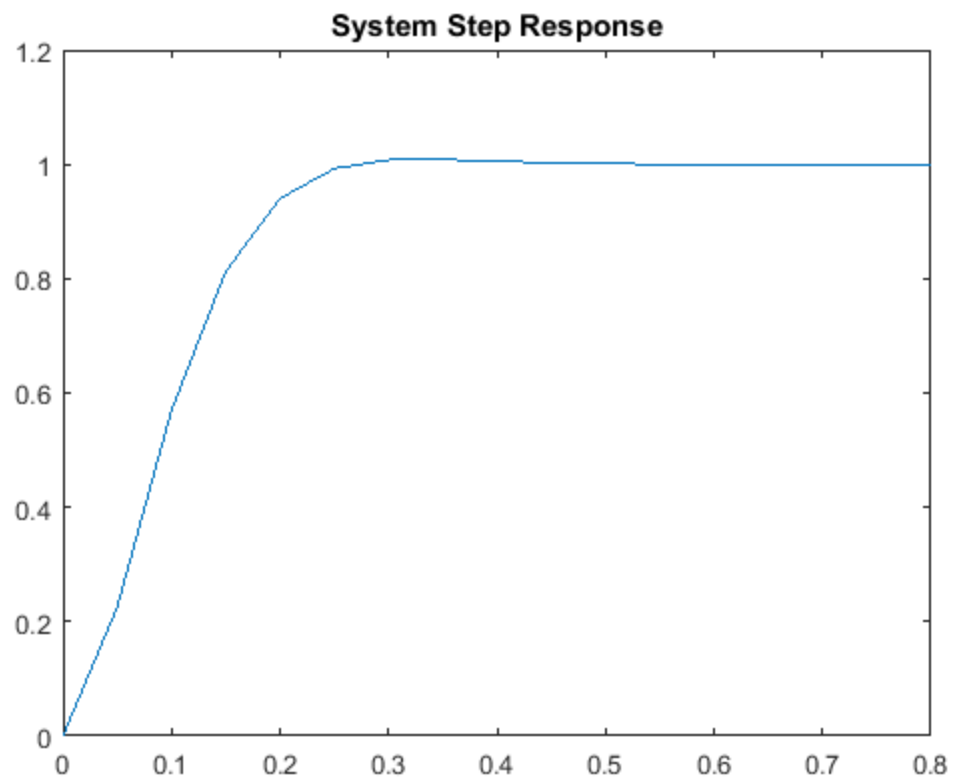
```
maxDisturbance = max(y)
```

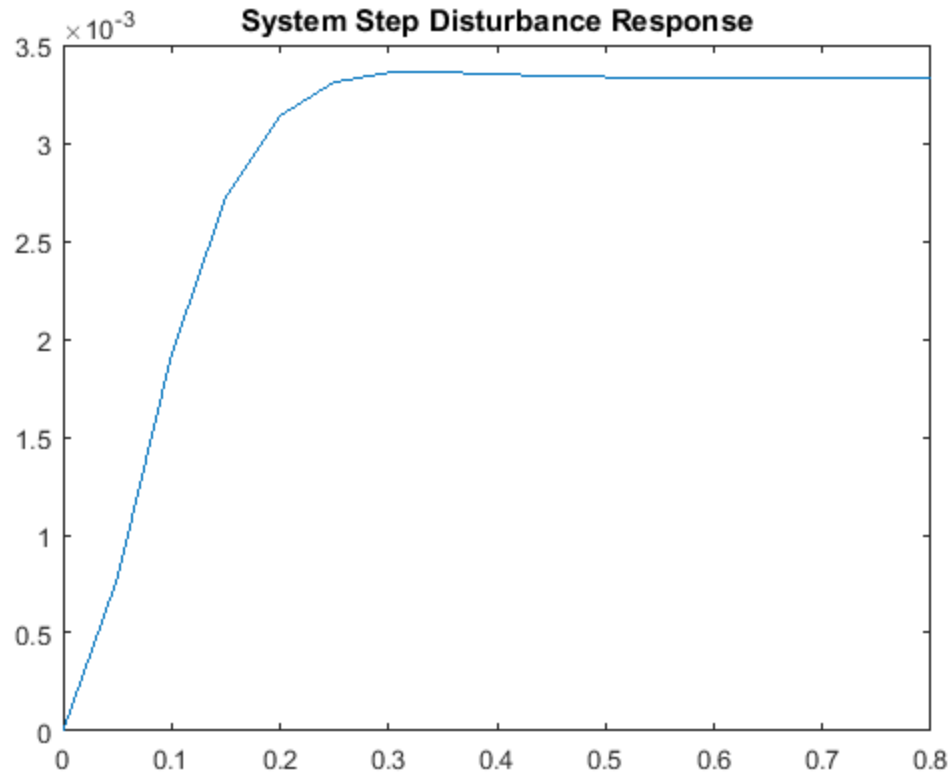
```
info =
```

```
    RiseTime: 0.1621  
    SettlingTime: 0.2380  
    SettlingMin: 0.9401  
    SettlingMax: 1.0084  
    Overshoot: 0.8390  
    Undershoot: 0  
         Peak: 1.0084  
    PeakTime: 0.3500
```

```
maxDisturbance =
```

```
0.0034
```





So all of the constraints are satisfied.

Task 5

So now the closed loop transfer function becomes

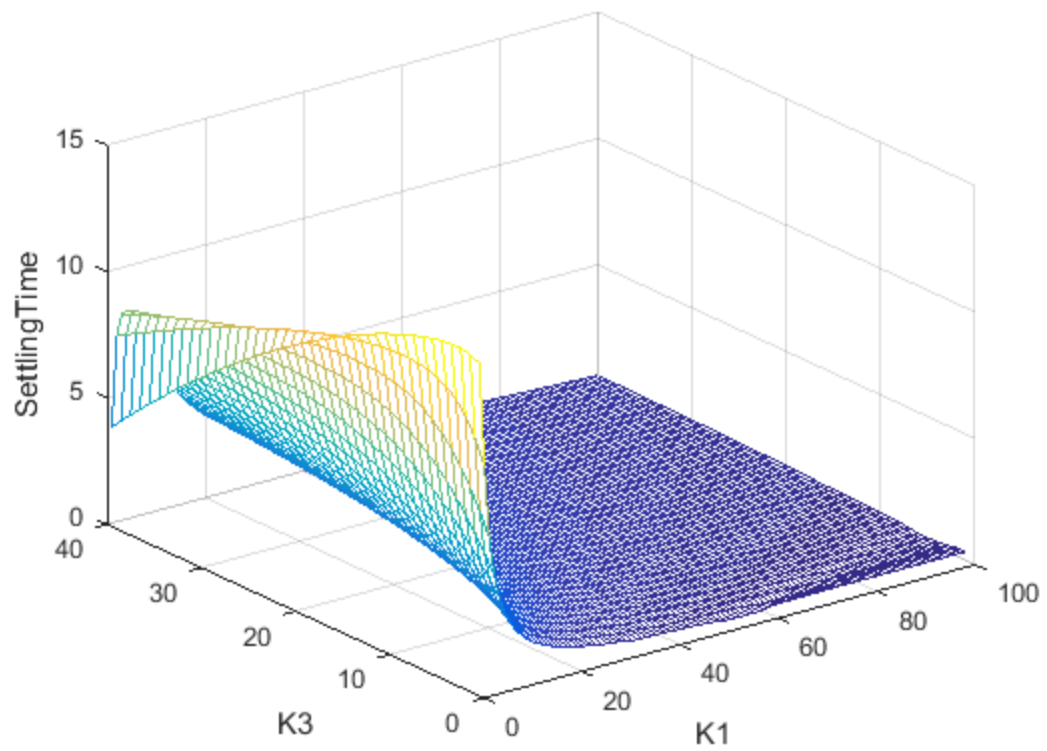
$$CLTF = \frac{F(s)G1(s)G2(s)}{1 + F(s)G1(s)G2(s)}$$

where $F(s) = K1 + K3s$

we can applied the same precedence as previous task and get the 3-D graph of constraints we are evaluating.

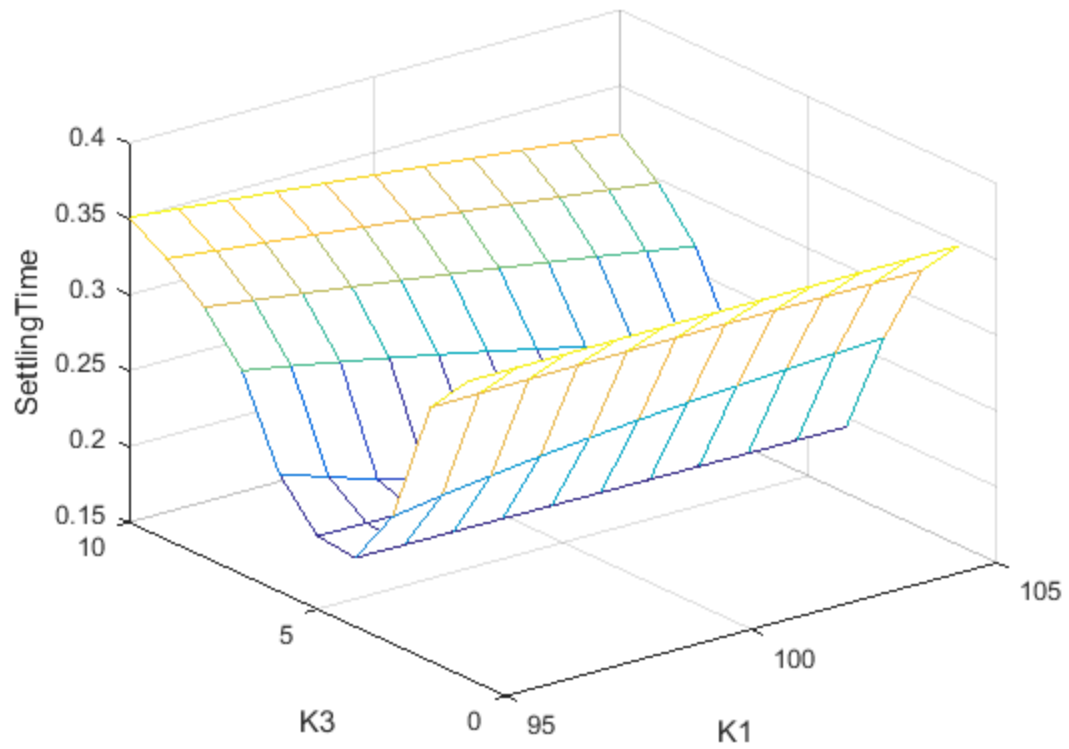
we look at settling time first.

```
openfig('K1-K3 settling time 100x40.fig');
```



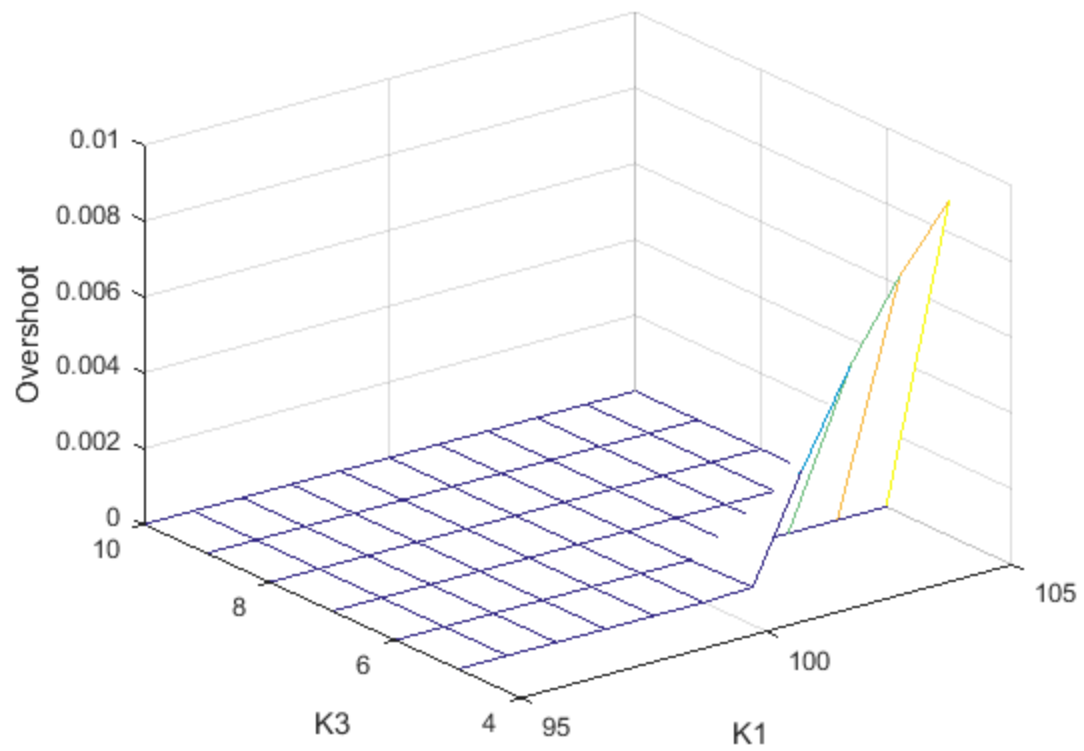
You can see that when K1 is around 100 and K2 is around 5 to 10, settling time is satisfied, then we may take a closer look.

```
openfig('K1-K3 settling time [95,105]x[1,10].fig');
```



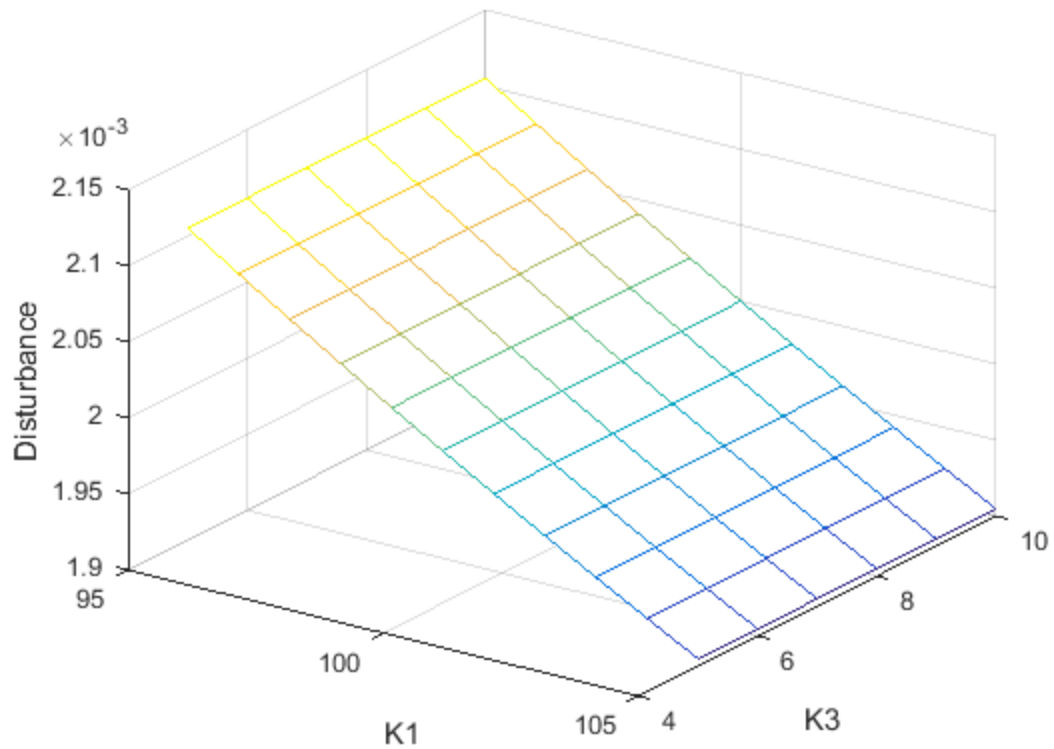
So there are couples of K1 K3 pair meet the settling time requirement, take K1=100 and K3=5 for example, it is under 250ms. We can also evaluate overshoot around this area.

```
openfig('K1-K3 overshoot [95,105]x[5,10].fig');
```



Observe that $K1, K3 = [100 \ 5]$ has no apparent overshoot. Then we examine the disturbance of this area.

```
openfig('K1-K3 disturbance [95,105]x[5,10].fig');
```



You can see that disturbance of $K1, K3 = [95, 100]$ meet the requirement.

The following is the code to generate graph.

```
% [K1Range K3Range] = meshgrid(95:105, 5:10);
% overshootMatrix = [];
% settlingTimeMatrix = [];
% disturbanceMatrix=[];
% candidatePairs = [];
% t=[0:0.2:15];
% G12= G1*G2;
% for K3 = K3Range(:,1)'
%     overshootArr=[];
%     settlingTimeArr=[];
%     disturbanceArr=[];
%     for K1 = K1Range(1,:)
%         CLTF = ((K1+K3*s)*G12)/(1+(K1+K3*s)*G12);
%         y = step(CLTF, t);
%         info = stepinfo(y, t, 'SettlingTimeThreshold', 0.02);
%         overshootArr = [overshootArr, info.Overshoot];
%         settlingTimeArr = [settlingTimeArr, info.SettlingTime];
%     end
%     Tw = G2/(1+(K1+K3*s)*G12);
%     y = step(Tw,t);
%     maxDisturbance = max(y);
%     disturbanceArr = [disturbanceArr, maxDisturbance];
% end
```

```
%         if(info.Overshoot <= 5 & info.SettlingTime <0.25 & y<0.005)
%             candidatePairs = [candidatePairs; Ka, Kh];
%         end
%     end
%     overshootMatrix = [overshootMatrix; overshootArr];
%     settlingTimeMatrix = [settlingTimeMatrix; settlingTimeArr];
%     disturbanceMatrix = [disturbanceMatrix; disturbanceArr];
% end

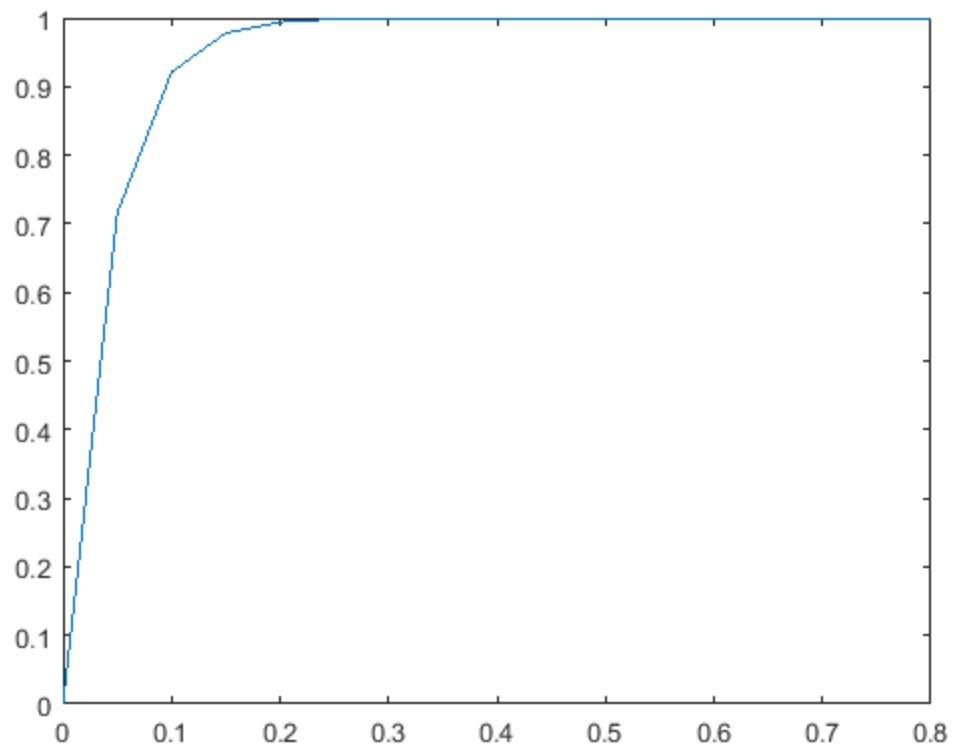
%mesh(K1Range, K3Range,
%     overshootMatrix);xlabel('K1');ylabel('K3');zlabel('Overshoot')
%mesh(K1Range, K3Range,
%     settlingTimeMatrix);xlabel('K1');ylabel('K3');zlabel('SettlingTime')
%mesh(K1Range,
%     K3Range,disturbanceMatrix);xlabel('K1');ylabel('K3');zlabel('Disturbance');view(3)
%candidatePairs
```

We can take $K_1=100$ and $K_3=5$, and evaluate it more quantitatively.

```
K1=100; K3=5;
CLTF = ((K1+K3*s)*G12)/(1+(K1+K3*s)*G12);
y = step(CLTF, t);
info = stepinfo(y, t, 'SettlingTimeThreshold', 0.02)
plot(t,y);
```

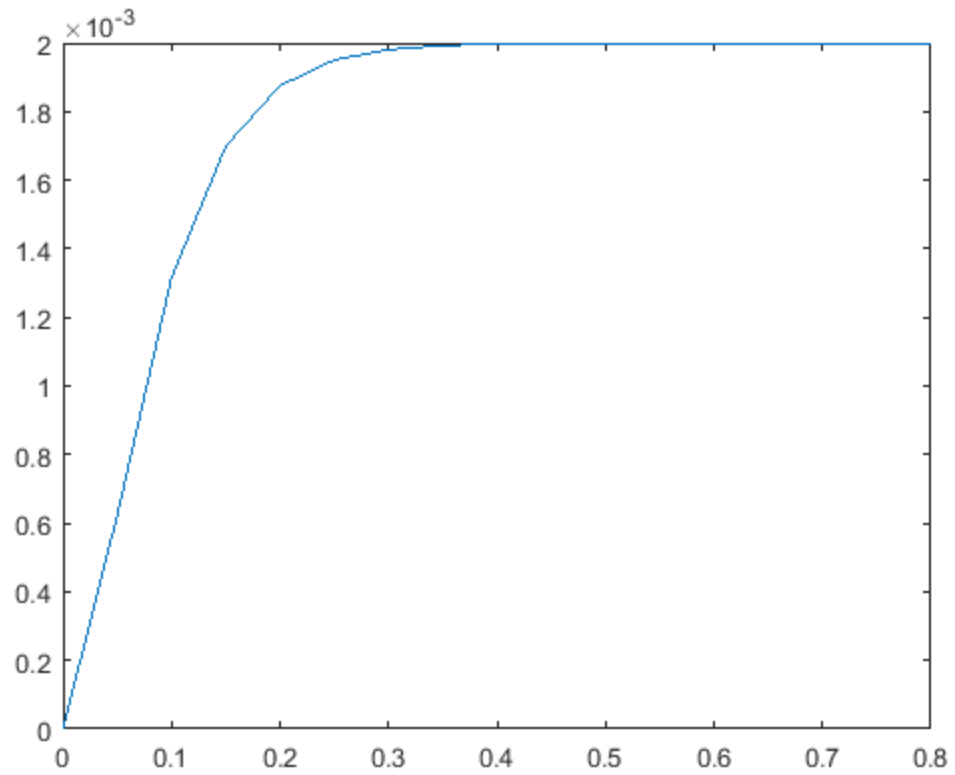
```
info =
```

```
    RiseTime: 0.0879
    SettlingTime: 0.1560
    SettlingMin: 0.9211
    SettlingMax: 1.0000
    Overshoot: 0
    Undershoot: 0
           Peak: 1.0000
    PeakTime: 0.8000
```

We see that there is no overshoot because the K_3 term acts as a damping factor that prevents the response from overshooting.

```
Tw = G2/(1+(K1+K3*s)*G12);  
y = step(Tw,t);  
plot(t,y);
```



The disturbance only reaches $2e-3$.

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