Process Automation Laboratory - PID control

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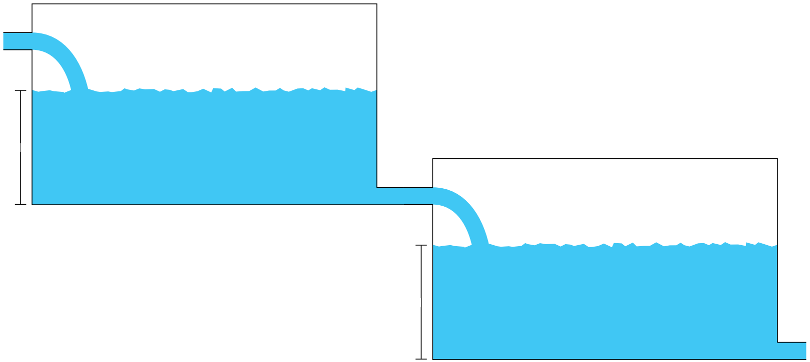
Second-order models

Two first-order models in series



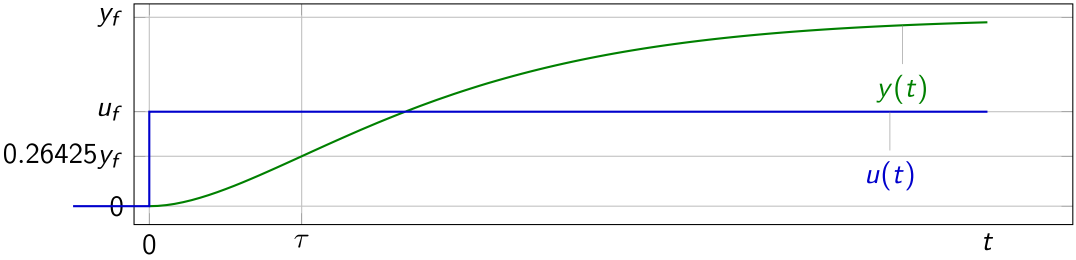
$$u(t) \longrightarrow \boxed{G_1(s)} \longrightarrow \boxed{G_2(s)} \longrightarrow y(t)$$

$$G(s) = G_1(s)G_2(s)$$

Fitting second-order critically-damped model

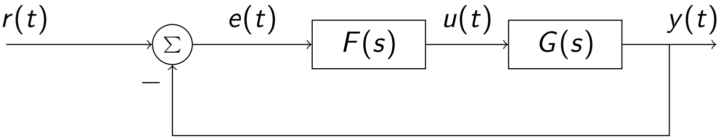
Model with two identical time-constants. Assuming model

$$Y(s) = \frac{K}{(s\tau+1)^2} U(s) \quad \stackrel{U(s)=\frac{u_f}{s}}{\Longrightarrow} \quad y(t) = u_f K \left(1 - (1 + \frac{t}{\tau}) \mathrm{e}^{-\frac{t}{\tau}}\right) u_H(t)$$

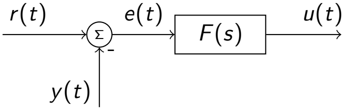


$$y_f = \lim_{t\to\infty} y(t) = u_f K \quad \Rightarrow \quad K = \frac{y_f}{u_f}.$$

Feedback control



The PID controller



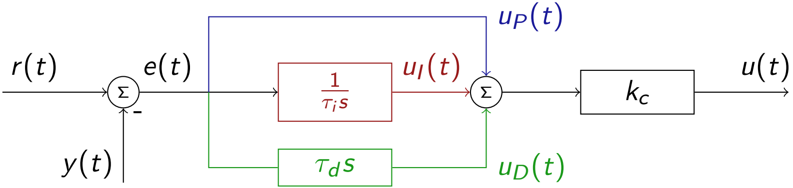
Parallel form (ISA)

$$F(s) = k_c \left(1 + \frac{1}{\tau_i s} + \tau_d s \right)$$

Series form

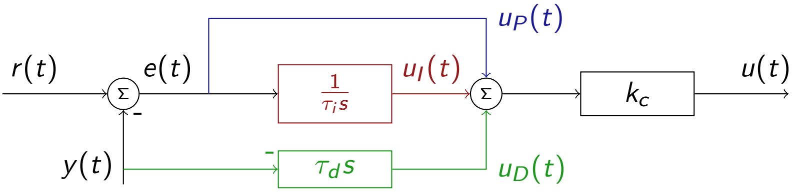
$$F(s) = K_c \left(\frac{\tau_I s + 1}{\tau_I s} \right) (\tau_D s + 1) = \underbrace{\frac{K_c(\tau_I + \tau_D)}{\tau_I}}_{k_c} \left(1 + \frac{1}{\underbrace{(\tau_I + \tau_D)}_{\tau_i} s} + \underbrace{\frac{\tau_I \tau_D}{\tau_I + \tau_D}}_{\tau_d} s \right)$$

The PID - Parallel form



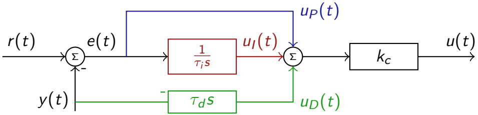
$$u(t) = k_c\left(e(t) + \frac{1}{\tau_i}\int_0^t e(\xi)d\xi + \tau_d \frac{d}{dt}e(t)\right)$$

The PID - Parallel form, modified D-part

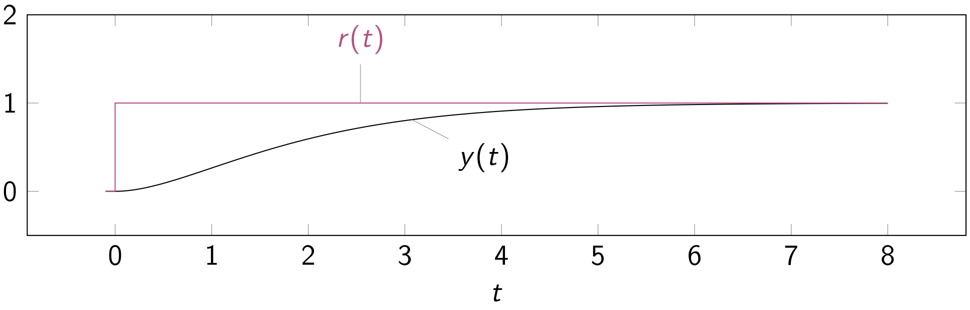


$$u(t) = k_c\left(e(t) + \overbrace{\frac{1}{\tau_i}\int_0^t e(\xi)d\xi}^{u_I(t)} + \underbrace{\tau_d \frac{d}{dt}\big(-y(t)\big)}_{u_D(t)}\right)$$

The PID - Parallel form



$$u(t) = k_c\left(e(t) + \overbrace{\frac{1}{\tau_i}\int_0^t e(\xi)d\xi}^{u_I(t)} + \underbrace{\tau_d\frac{d}{dt}\big(-y(t)\big)}_{u_D(t)}\right)$$



Activity Sketch the error signal $e(t)$, the derivative signal $u_D(t)$ and the integral signal $u_I(t)$ (use $\tau_i = \tau_d = 1$)

The PID - Parallel form, solution

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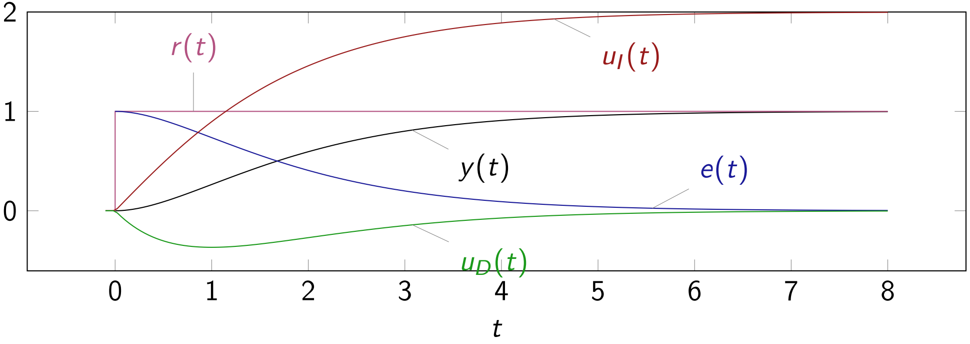
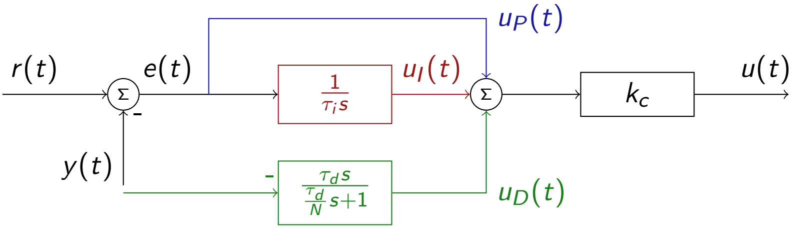
$$u(t) = k_c\left(e(t) + \overbrace{\frac{1}{\tau_i}\int_0^t e(\xi)d\xi}^{u_I(t)} + \underbrace{\tau_d\frac{d}{dt}\left(-y(t)\right)}_{u_D(t)}\right)$$



The PID - practical form



The parameter N is chosen to limit the influence of noisy measurements. Typically,

$$3 < N < 10$$

PID tuning

Method by Smith & Corripio using table by Ziegler-Nichols

Given process model (fitted to response of the system)

$$G(s) = K \frac{\mathrm{e}^{-s\theta}}{\tau s + 1}$$

and PID controller

$$F(s) = k_c \left(1 + \frac{1}{\tau_i s} + \tau_d s\right)$$

Choose the PID parameters according to the following table (Ziegler-Nichols, 1943)

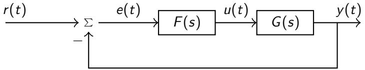
Controller	k_c	τ_i	τ_d
P	$\frac{\tau}{\theta K}$		
PI	$\frac{0.9\tau}{\theta K}$	$\frac{\theta}{0.3}$	
PID	$\frac{1.2\tau}{\theta K}$	2θ	$\frac{\theta}{2}$

Gives good control for

$$0.1 < \frac{\theta}{\tau} < 0.6.$$

SIMC-PID tuning rule

[SIMC stands for *SIMple Control* or *Skogestad Internal Model Control*]



Given model of the process and desired closed-loop system

$$G(s) = K\frac{\mathrm{e}^{-s\theta}}{(\tau_1 s+1)(\tau_2 s+1)}, \quad \tau_1 \geq \tau_2; \qquad G_c(s) = \frac{\mathrm{e}^{-s\theta}}{\tau_c s+1}$$

Good robustness is obtained with PID controller

$$F(s) = K_c\left(\frac{\tau_I s+1}{\tau_I s}\right)(\tau_d s+1) = \frac{K_c(\tau_I+\tau_d)}{\tau_I}\left(1+\frac{1}{(\tau_I+\tau_D)s}+\frac{\tau_I\tau_D}{\tau_I+\tau_D}s\right)$$

with

$$K_c = \frac{\tau_1}{K(\tau_c+\theta)}, \qquad \tau_I = \min\{\tau_1, 4(\tau_c+\theta)\}, \qquad \tau_d = \tau_2$$