

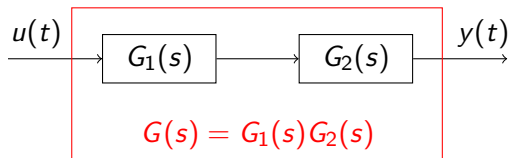
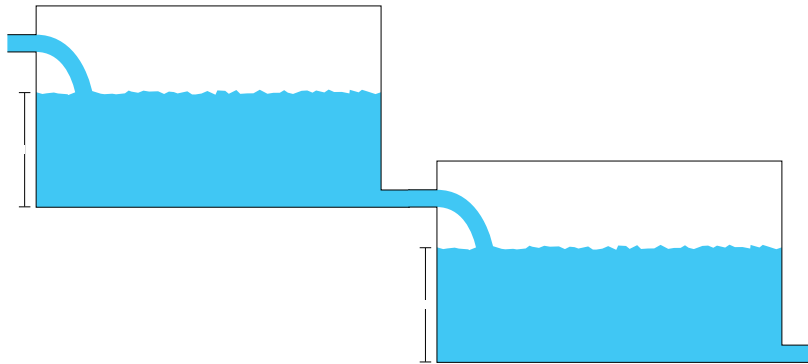
# Process Automation Laboratory - PID control

Kjartan Halvorsen

2020-09-01

# Second-order models

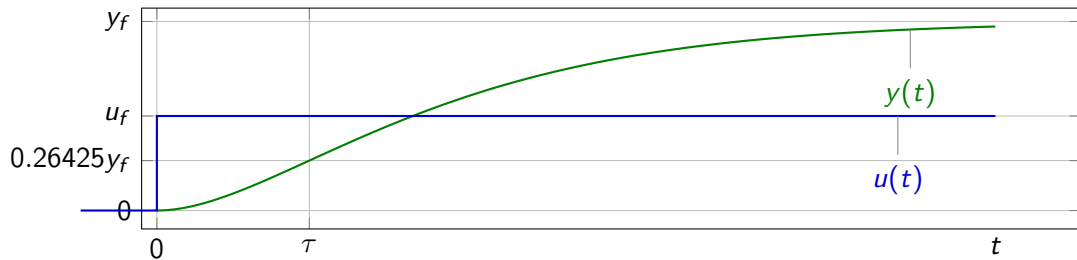
## Two first-order models in series



## Fitting second-order critically-damped model

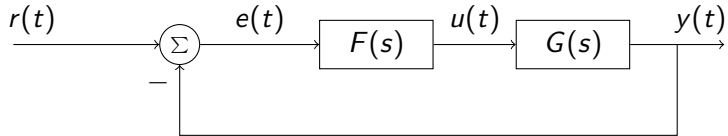
Model with two identical time-constants. Assuming model

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

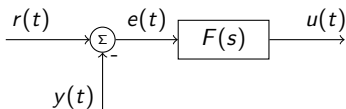


$$y_f = \lim_{t \rightarrow \infty} y(t) = u_f K \quad \Rightarrow \quad K = \frac{y_f}{u_f}.$$

## Feedback control



# The PID controller



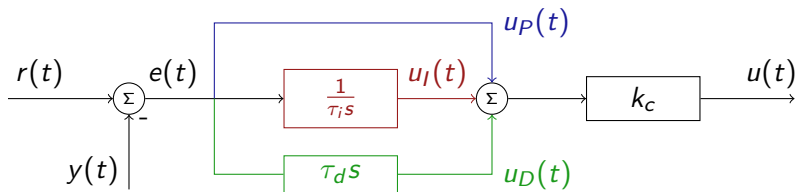
## Parallel form (ISA)

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

## Series form

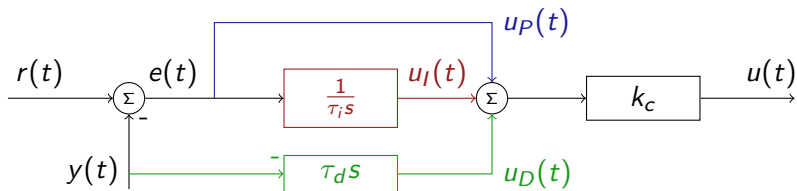
$$F(s) = K_c \left( \frac{\tau_I s + 1}{\tau_I s} \right) (\tau_D s + 1) = \underbrace{\frac{K_c(\tau_I + \tau_D)}{\tau_I}}_{k_c} \left( 1 + \underbrace{\frac{1}{(\tau_I + \tau_D) s}}_{\tau_i} + \underbrace{\frac{\tau_I \tau_D}{\tau_I + \tau_D}}_{\tau_d} s \right)$$

## The PID - Parallel form



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

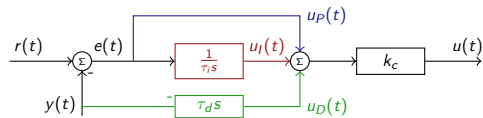
## The PID - Parallel form, modified D-part



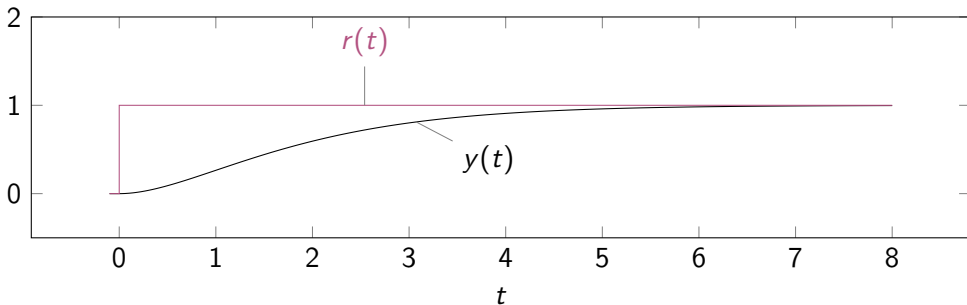
$$u(t) = k_c \left( \underbrace{e(t)}_{u_I(t)} + \frac{1}{\tau_i} \int_0^t e(\xi) d\xi + \underbrace{\tau_d \frac{d}{dt}(-y(t))}_{u_D(t)} \right)$$



## The PID - Parallel form



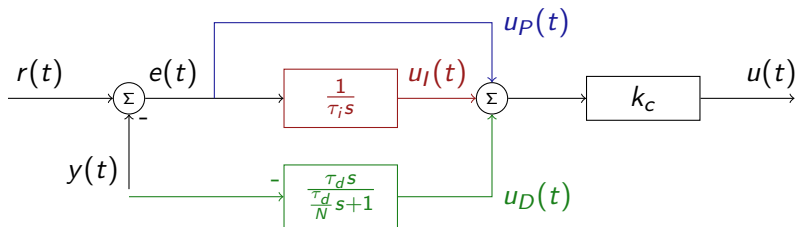
$$u(t) = k_c \left( e(t) + \overbrace{\frac{1}{\tau_i} \int_0^t e(\xi) d\xi}^{u_I(t)} + \underbrace{\tau_d \frac{d}{dt}(-y(t))}_{u_D(t)} \right)$$



**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

## 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)

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

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)

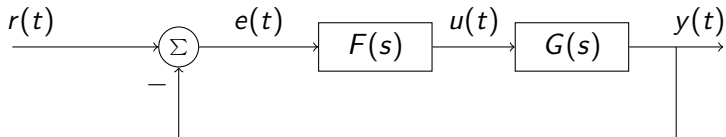
Controller	$k_c$	$\tau_i$	$\tau_d$
P	$\frac{\tau}{\theta K}$		
PI	$\frac{0.9\tau}{\theta K}$	$\frac{\theta}{0.3}$	
PID	$\frac{1.2\tau}{\theta K}$	$2\theta$	$\frac{\theta}{2}$

Gives good control for

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

# Analytical PID tuning

## Analytical PID tuning



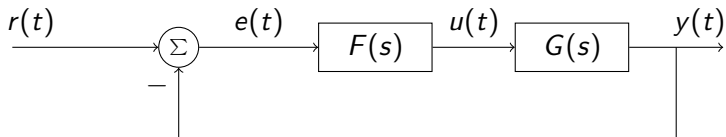
**Activity** Solve for  $F(s)$  in the closed-loop transfer function

$$G_c(s) = \frac{G(s)F(s)}{1 + G(s)F(s)}$$

# Analytical PID tuning - Solution



## Analytic PID tuning - first-order with delay



Given model  $G(s) = K \frac{e^{-s\theta}}{\tau s + 1}$  of the process and desired closed-loop transfer function  $G_c(s) = \frac{e^{-s\theta}}{\tau_c s + 1}$

**Activity** Show that the controller becomes

$$F(s) = \frac{1}{K} \left( \frac{\tau s + 1}{\tau_c s + 1 - e^{-s\theta}} \right) \approx \frac{1}{K} \left( \frac{\tau s + 1}{(\tau_c + \theta)s} \right) = \underbrace{\frac{\tau}{K(\tau_c + \theta)}}_{k_c} \left( 1 + \underbrace{\frac{1}{\tau}}_{\tau_i} s \right).$$

Which is a PI-controller with  $k_c = \frac{\tau}{K(\tau_c + \theta)}$  and  $\tau_i = \tau$ .

## SIMC-PID tuning rule

[ SIMC stands for *SIM*ple Control or *Skogestad Internal Model Control* ]



Given model of the process and desired closed-loop system

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

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

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