

# ELECENG 3CL4 Lab 3 Report

Aaron Pinto  
pintoa9  
L02

Raeed Hassan  
hassam41  
L02

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## Member Contributions

Both group members contributed an even amount to both the exercises and the report. Both members went through the exercises together and contributed to all sections of the report.

## Objective

To design a proportional controller and a proportional controller with velocity feedback for the DC motor servomechanism, and explore trade-offs involved in the selection of the controller parameters and their impact on transient and steady-state responses of the control system.

### 3 Experiment: Qualitative Trade-offs in Rise-time, Steady-State Error, Overshoot, and Settling Time for a Proportional Controller

In order to measure the peak overshoot (with respect to the final value) and steady state error, we measured the delta between the first peak and the steady state value using the peak finder tool for the peak and a cursor for the steady state value. The settling time measurement was performed by moving a cursor to the point at which the last oscillation was ending and the plot showed a straight line after. The time value shown on the cursor table was then taken as the settling time. The rise time was measured using a cursor as the time from 0 to the first instance of when the output reached the steady state value. We tried the "Bilevel Measurements" tool, but we found it to be inaccurate, though it did give us an approximation of where our values should be.

$k_p$	0.5	1	2	3	4	5
peak overshoot (%)	0.7	38.4	54.7	65.7	75.3	82.4
steady-state error (deg)	26.89	8.09	5.10	3.69	2.64	1.93
settling time (sec)	0.336	0.469	0.618	0.771	0.881	1.067
rise time (sec)	0.336	0.125	0.100	0.076	0.064	0.058

Table 1: Measurements for Experiment 1

We measured values for the peak overshoot, steady-state error, settling time, and rise time at  $k_p$  values of 0.5, 1, 2, 3, 4, and 5. The measurements are presented in Table 1. The figures for the step response plots are shown in Appendix A. As we increased the proportional gain, we observed that the peak overshoot percentage increased, the steady state error decreased the settling time increased, and the rise time decreased. This matches our expectations from the theoretical calculations and investigations in the pre-lab and the behaviour that we have observed in previous labs.

## 4 Experiment: Proportional Controller Design

To determine the values for  $k_p$  that would meet the design specifications (produce underdamped with maximum overshoot of 50%, 55%, 60%, and 65%), we used the expression from the lab document to estimate the percent overshoot of an underdamped system. The expression was rearranged to solve for  $k_p$  in Equation 1. The calculations to determine the values that would meet the specifications were done in MATLAB, with the MATLAB code shown in Listing 1. The values of  $A$  and  $\tau_m$  were the average of their determined values from time-domain and frequency-domain analysis in lab 2.

$$\begin{aligned}
 P.O. &= 100 \exp\left(-\frac{\pi}{\sqrt{4k_p A \tau_m - 1}}\right) \\
 \ln\left(\frac{P.O.}{100}\right) &= -\frac{\pi}{\sqrt{4k_p A \tau_m - 1}} \\
 \sqrt{4k_p A \tau_m - 1} &= \frac{-\pi}{\ln\left(\frac{P.O.}{100}\right)} \\
 4k_p A \tau_m - 1 &= \left(\frac{-\pi}{\ln\left(\frac{P.O.}{100}\right)}\right)^2 \\
 4k_p A \tau_m &= \left(\frac{-\pi}{\ln\left(\frac{P.O.}{100}\right)}\right)^2 + 1 \\
 k_p &= \left(\left(\frac{-\pi}{\ln\left(\frac{P.O.}{100}\right)}\right)^2 + 1\right) / 4A\tau_m
 \end{aligned} \tag{1}$$

Listing 1: Calculating  $k_p$  to meet specifications

```

1 %% Experiment 2
2 tau_m = (0.133 + 0.155)/2; % average of lab 2 determined values
3 A = (25.877 + 30.303)/2; % average of lab 2 determined values
4
5 po = [50 55 60 65]; % percent overshoot specifications
6 kp = ((-pi./log(po./100)).^2 + 1) ./ (4 * A * tau_m)

```

The procedure for measuring the peak overshoot, steady-state error and settling time was identical to the procedure followed in the previous experiment. The peak overshoot and settling time were measured with no step disturbance ( $\tau_d = 0$ ), while the steady-state error was measured with a step disturbance ( $\tau_d = 0.1745$ ). The measurements are presented in Table 2. The figures for the step response plots are shown in Appendix B.

Moving from our first value of  $k_p$  to our second, we observed some unusual behaviour where the steady state error increased and the settling time decreased, which is the opposite of what we expected to happen. We re-ran the test multiple times and still achieved the same results every time. This behaviour can be seen in the figures for  $k_p = 1.3314$  (Figure 7)

$k_p$	1.3314	1.7685	2.3395	3.3489
theoretical peak overshoot (%)	50	55	60	65
peak overshoot (%)	41.0	50.4	59.8	69.9
theoretical steady-state error (deg)	7.51	5.65	4.17	2.99
steady-state error (deg)	6.68	7.03	3.34	2.11
settling time (sec)	0.53	0.51	0.58	0.70

Table 2: Measurements for Experiment 2

and  $k_p = 1.7685$  (Figure 8). Apart from this irregular result at a  $k_p$  of 1.7685, the rest of the results followed the expected trend of peak overshoot increasing, steady state error decreasing and settling time increasing, as we increased our  $k_p$ .

We also observed that the theoretical values for the peak overshoot and the steady-state error were closer to the measured results for higher values of  $k_p$  (and higher theoretical peak overshoot). We believe that the effects of the non-linearities in the system are more prevalent at lower values of  $k_p$ , which could cause these discrepancies to appear. The expressions used to derive the appropriate value of  $k_p$  to meet the design requirements were also estimations for a moderately underdamped closed loop system. It is likely that the estimations are more accurate for the higher values of overshoot that we had.

## 6 Joint Design of Proportional Controller and Velocity Feedback

There are two design requirements to consider. We know that the magnitude of the steady-state error can be given by the expression  $|e_{ss}| = \frac{\tau_d}{k_p}$ . If the steady-state error at  $k_p = 1$  is 10 degrees, to reduce the steady-state by a factor of 5 (to 2 degrees), we need to increase  $k_p$  by a factor of 5. Therefore the design requirement for the magnitude of the steady-state error can be met by any  $k_p > 5$ . We can also determine the  $\zeta$  value of the system for the target percent overshoot of 10%, which is done in Equation 2

$$\zeta = -\frac{\ln\left(\frac{P.O.}{100}\right)}{\sqrt{\pi^2 + \ln^2\left(\frac{P.O.}{100}\right)}} \quad (2)$$

We can rearrange the expression relating  $\zeta$ ,  $k_p$ , and  $k_v$  to solve for  $k_v$ , and determine the minimum value of  $k_v$  to meet the percent overshoot requirement. This is done in Equation 3

$$\begin{aligned} \zeta &= \frac{1 + k_v A}{2\sqrt{k_p A \tau_m}} \\ k_v &= \frac{2\zeta\sqrt{k_p A \tau_m} - 1}{A} \end{aligned} \quad (3)$$

The MATLAB code to determine the minimum values of  $k_v$  for various acceptable  $k_p$  is shown in Listing 2.

Listing 2: Calculating  $k_v$  to meet specifications

```

8 %% Experiment 3
9 po = 10;
10 zeta = -log(po/100)/sqrt(pi^2 + log(po/100)^2);
11 kp = [5 6 7];
12 kv = (zeta*2*sqrt(kp*A*tau_m)-1)/A

```

The procedure for measuring the peak overshoot and steady-state error was identical to the procedure followed in the first experiment. The peak overshoot and steady-state time were measured with a step disturbance ( $\tau_d = 0.1745$ ). The measurements are presented in Table 3. The figures for the step response plots are shown in Appendix C

$k_p$	5	6	7
$k_v$	0.1537	0.1718	0.1884
peak overshoot (%)	11.70	11.33	8.25
steady-state error (deg)	2.11	1.76	1.41

Table 3: Measurements for Experiment 3

The results are close to what is expected, with values of peak overshoot and steady-state error near or within the design requirements. We can also observe a similar pattern to what has occurred in the previous experiments, where the expected peak overshoot and steady-state error are within the design requirements (expected from our design) for larger values of  $k_p$ , but slightly outside our expectations for lower values of  $k_p$ .

## A Experiment 1 Figures

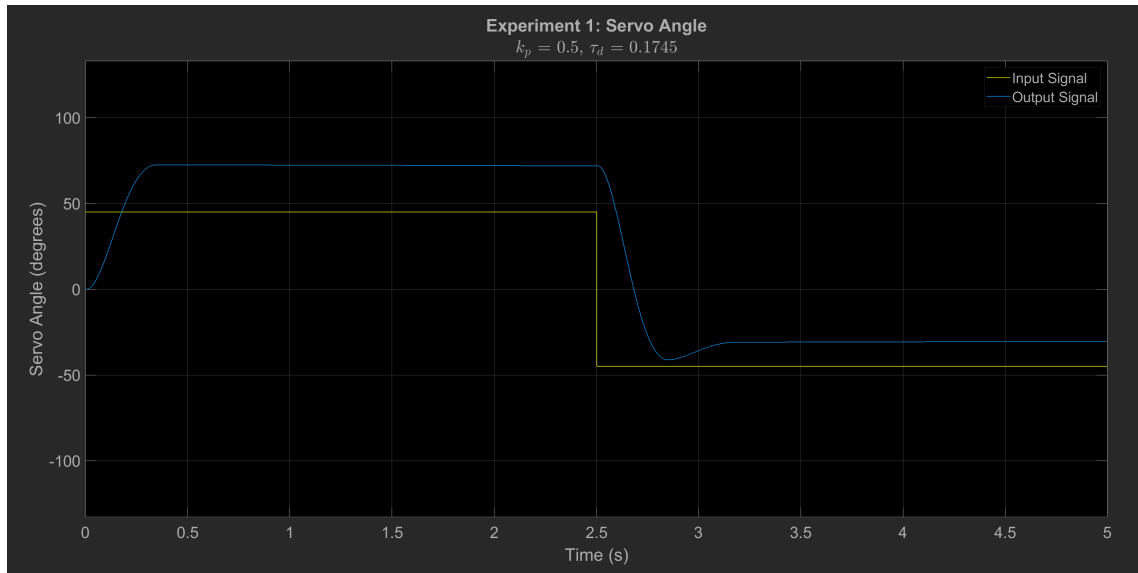


Figure 1: Experiment 1:  $k_p = 0.5$

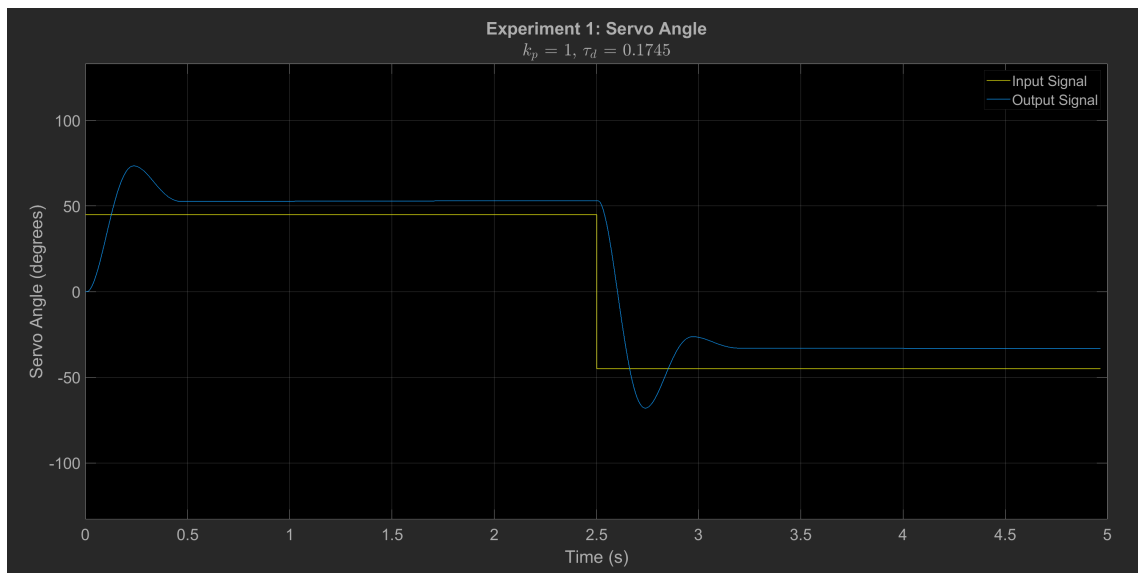


Figure 2: Experiment 1:  $k_p = 1$

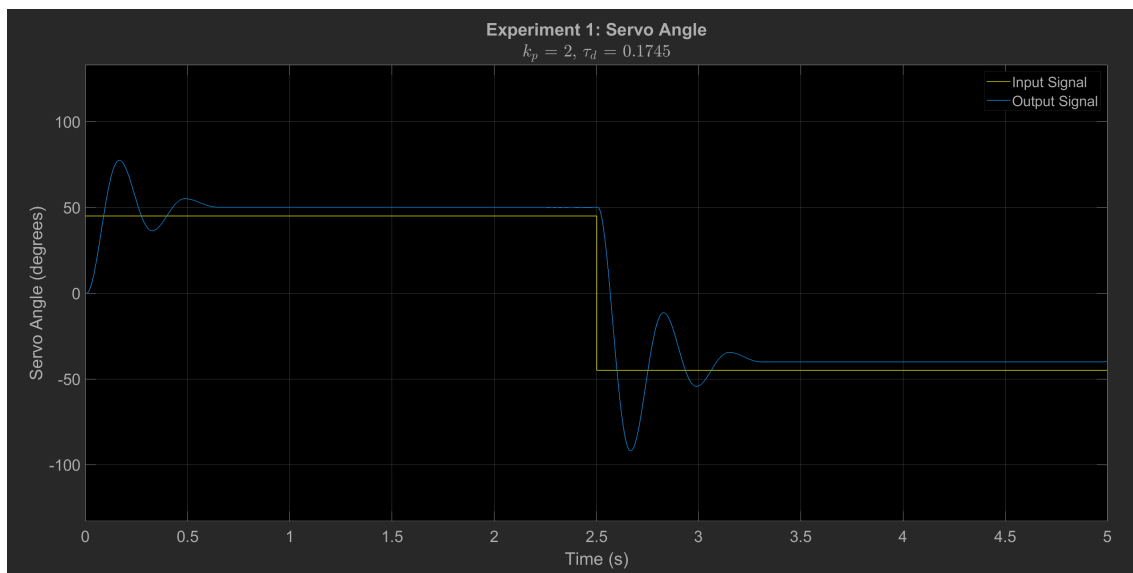


Figure 3: Experiment 1:  $k_p = 2$

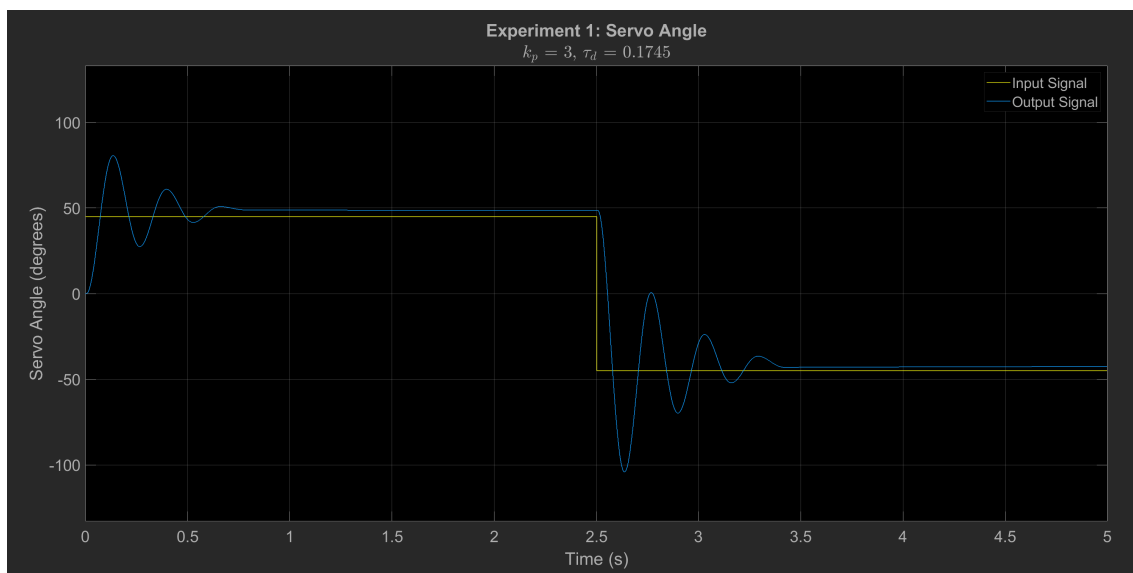


Figure 4: Experiment 1:  $k_p = 3$

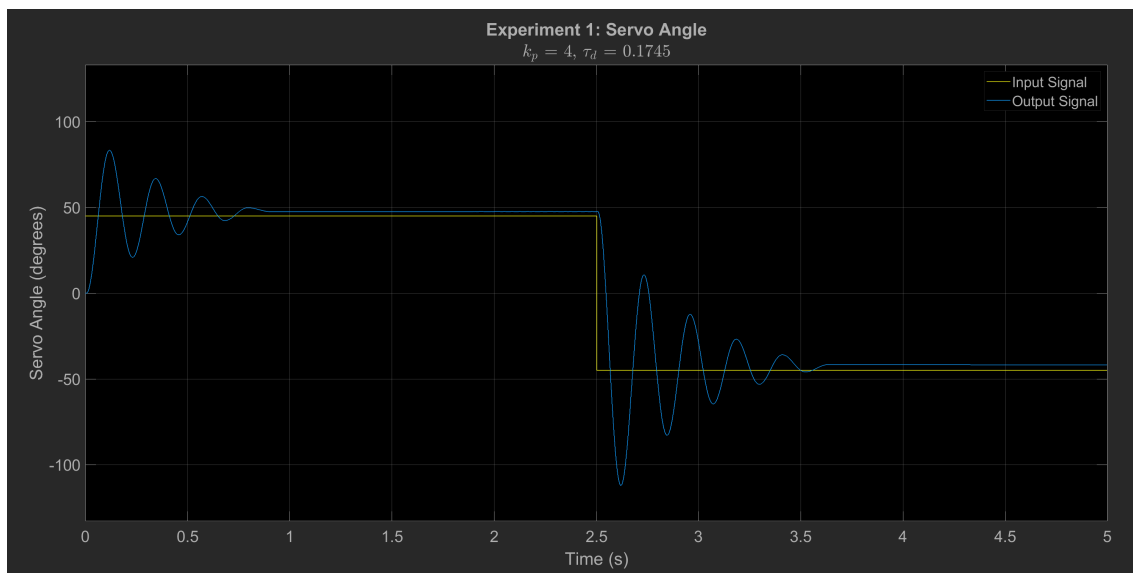


Figure 5: Experiment 1:  $k_p = 4$

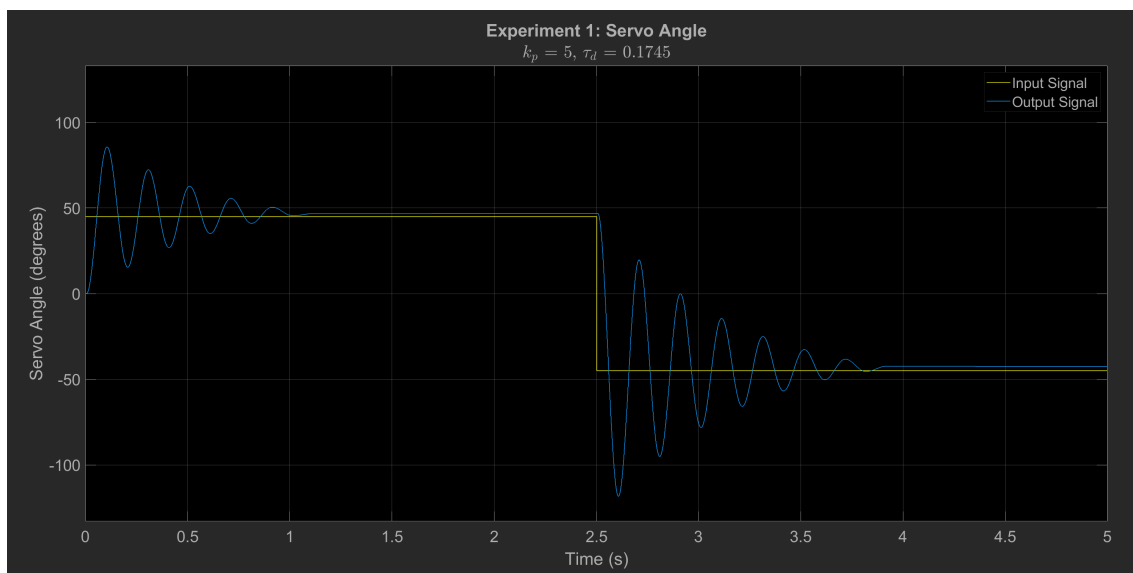


Figure 6: Experiment 1:  $k_p = 5$



## B Experiment 2 Figures

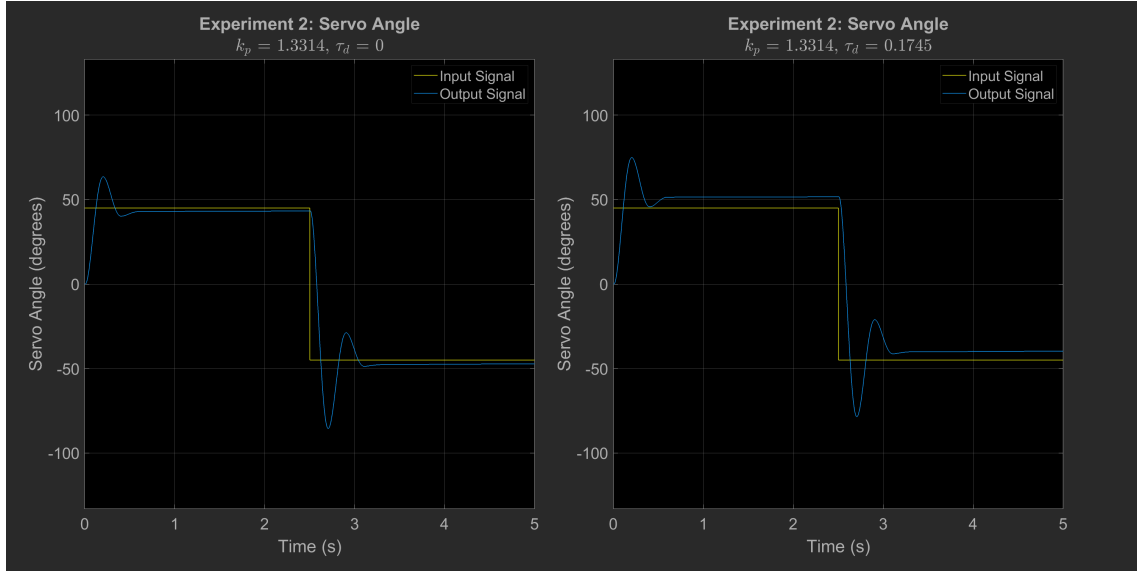


Figure 7: Experiment 2:  $k_p = 1.3314$

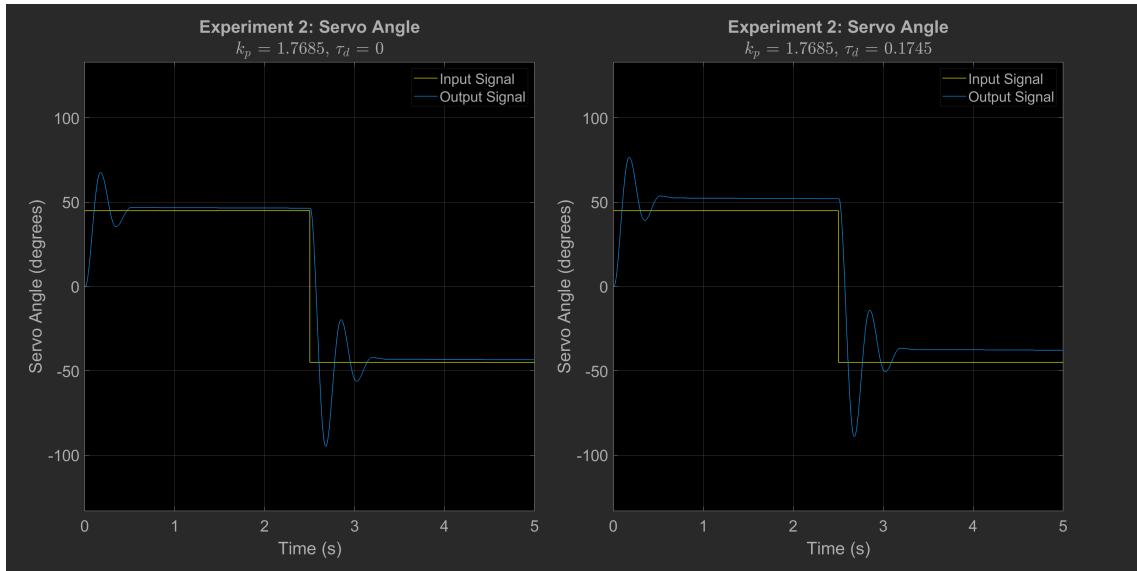


Figure 8: Experiment 2:  $k_p = 1.7685$

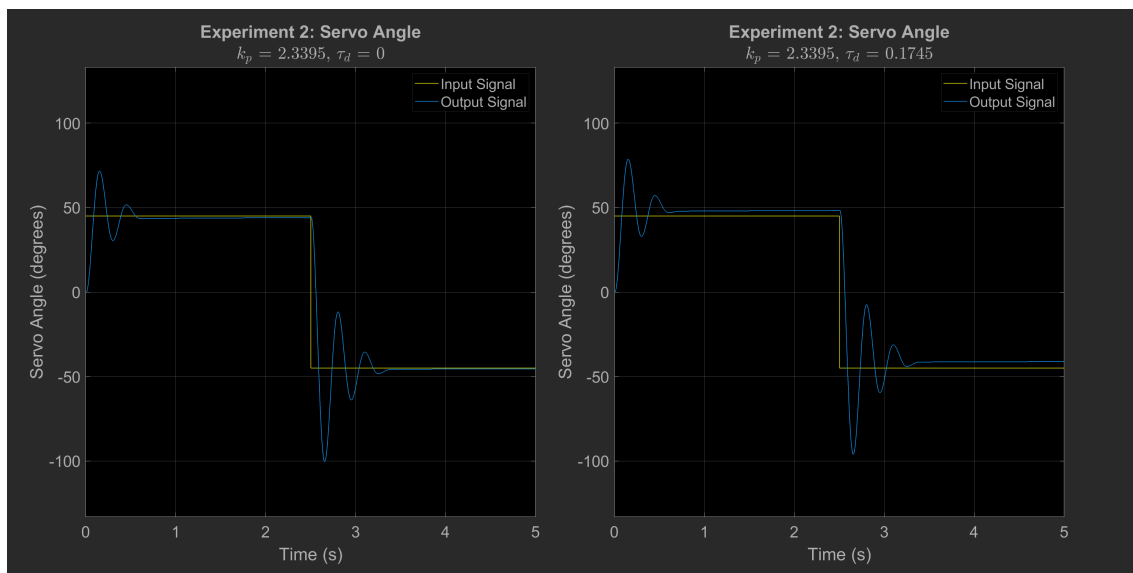


Figure 9: Experiment 2:  $k_p = 2.3395$

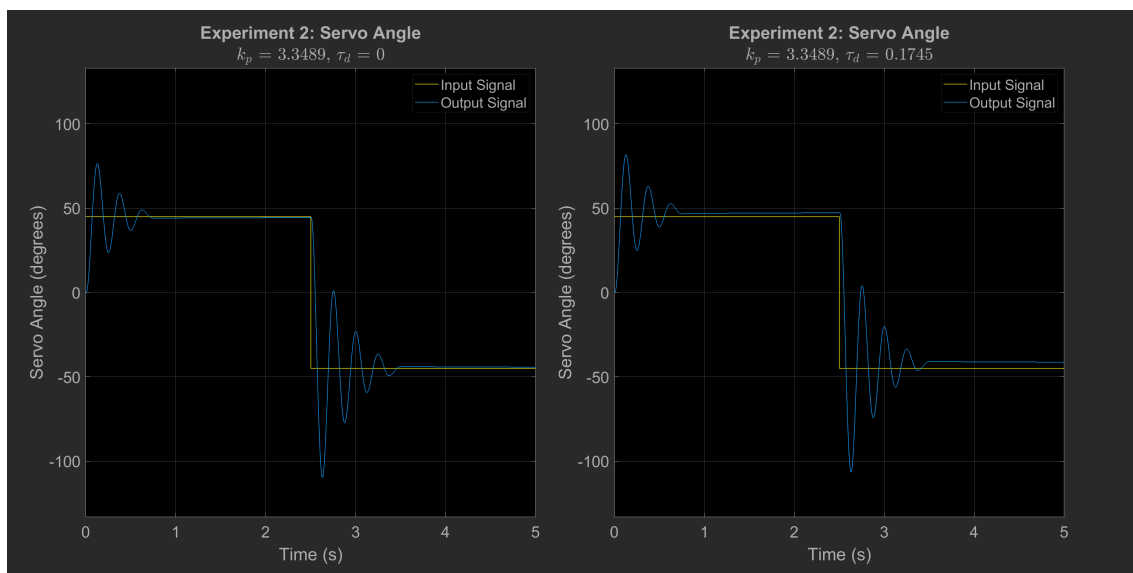


Figure 10: Experiment 2:  $k_p = 3.3489$

## C Experiment 3 Figures

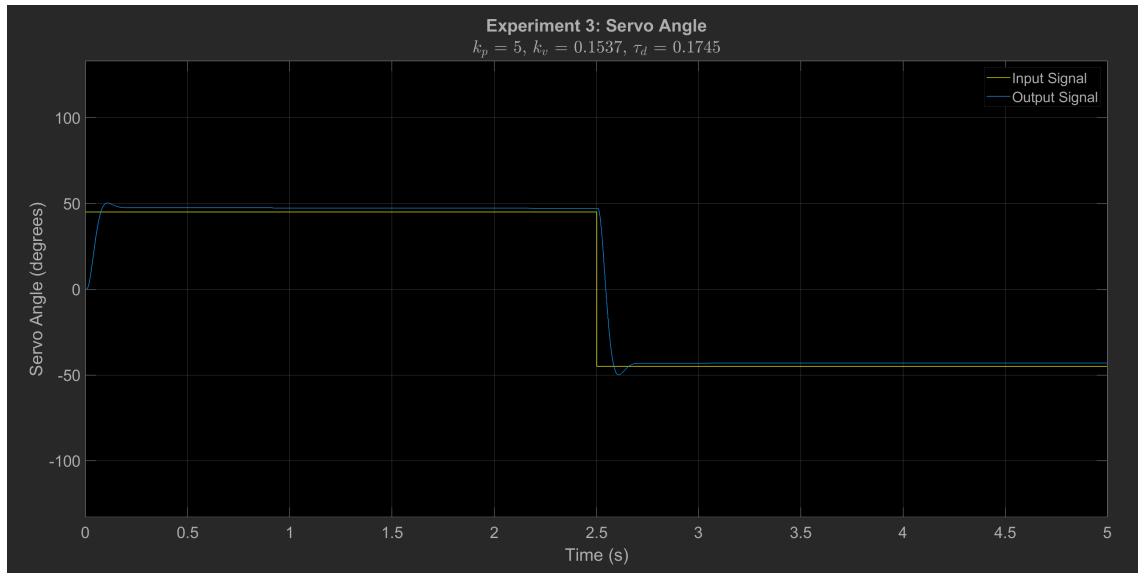


Figure 11: Experiment 3:  $k_p = 5, k_v = 0.1537$

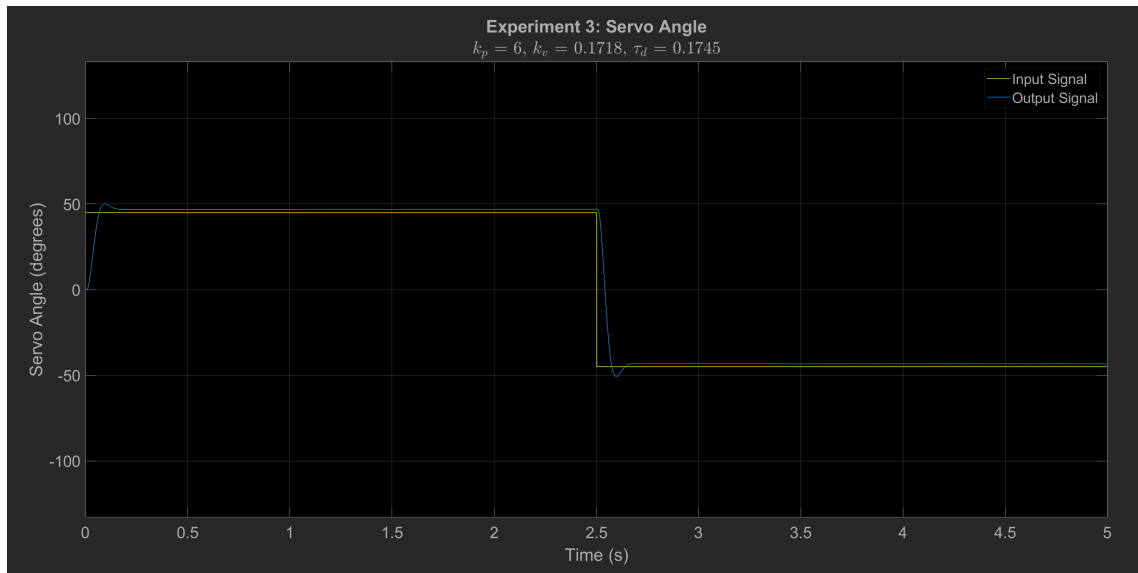


Figure 12: Experiment 3:  $k_p = 6, k_v = 0.1718$

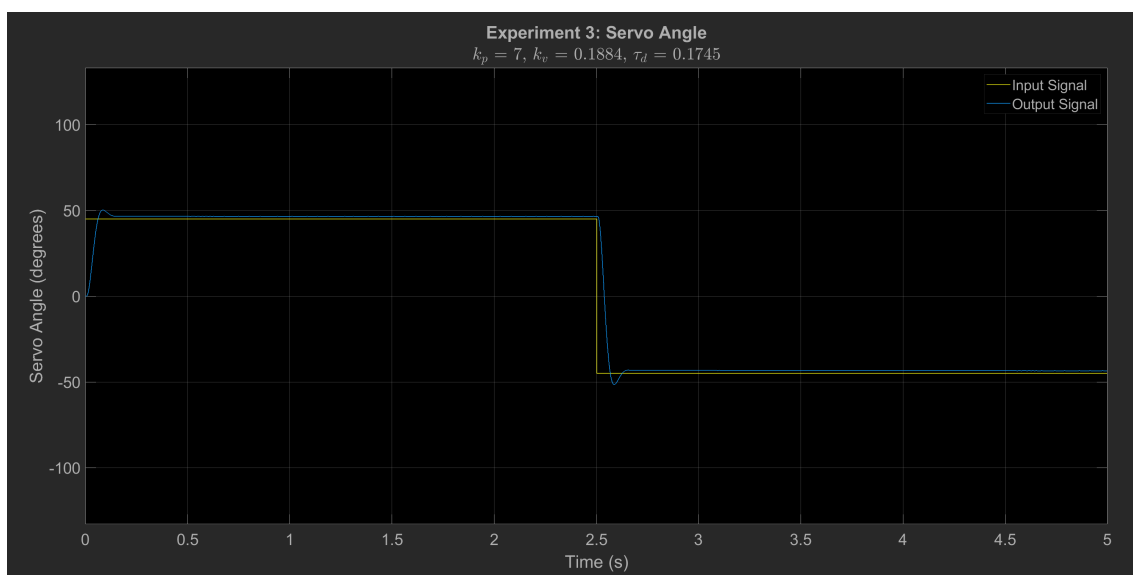


Figure 13: Experiment 3:  $k_p = 7$ ,  $k_v = 0.1884$