



Intro. Computer Control Systems: F3

Time response, feedback and PID-control

Dave Zachariah

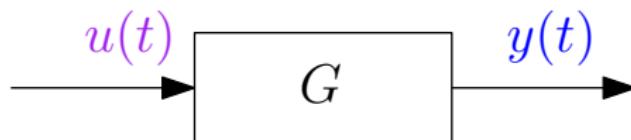
Dept. Information Technology, Div. Systems and Control

F2: Quiz!

- 1) Systems with **impulse response** $g(t) = \mathcal{L}^{-1}[G(s)]$, where $G(s)$ is rational, are all
- a Products of sinusoidal functions ↑
 - b Linear combinations of exponential functions ↑
 - c Stable ↓

Poles and time responses

Step response

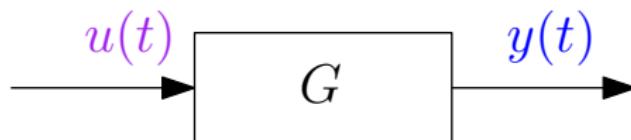


Model $Y(s) = G(s)U(s)$ with transfer function

$$G(s) = \frac{b_0 s^m + \cdots + b_m}{s^n + a_1 s^{n-1} + \cdots + a_n}.$$

Poles and time responses

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$$G(s) = \frac{b_0 s^m + \cdots + b_m}{s^n + a_1 s^{n-1} + \cdots + a_n}.$$

When we use a step as input

$$u(t) = \begin{cases} u_0 & (\text{const.}) \quad \text{f\"or } t \geq 0, \\ 0 & \quad \quad \quad \text{f\"or } t < 0, \end{cases} \quad \xleftrightarrow{\mathcal{L}} \quad U(s) = \frac{u_0}{s}$$

what is the **step response** $y(t)$?

Poles and time responses

Poles distance from the origin \leftrightarrow quickness

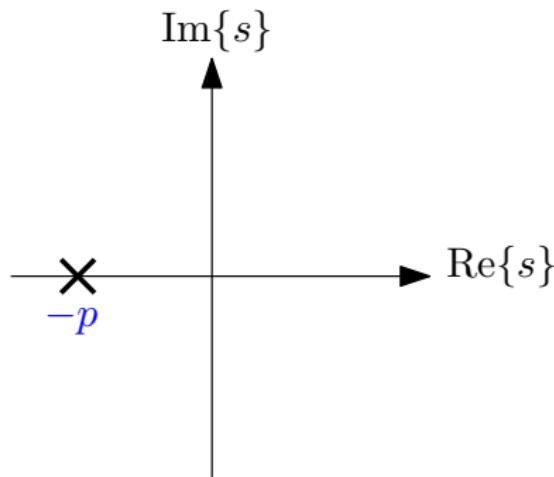
Ex. 1st-order system:

$$G(s) = \frac{p}{s + p}$$

Pole at:

$$s = -p$$

Pole-zero diagram:

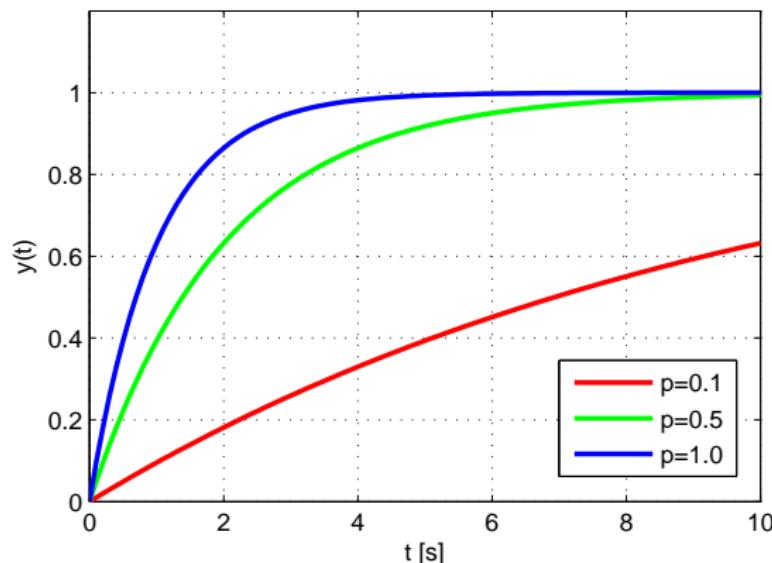


Poles and time responses

Poles distance from the origin \leftrightarrow quickness

Ex. 1st-order system:

$$G(s) = \frac{p}{s + p}$$



Poles and time responses

Complex conjugated poles describe system oscillations

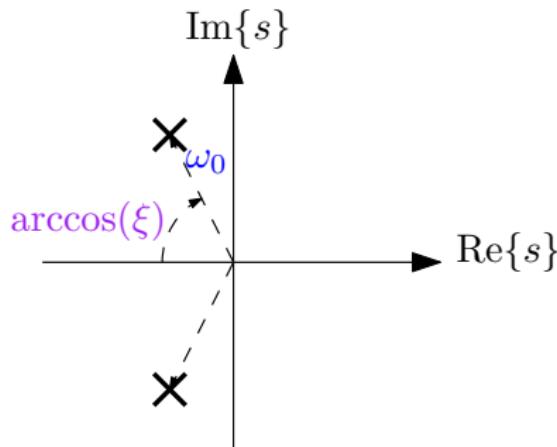
Ex. 2nd-order system:

$$G(s) = \lceil \text{alt. form} \rceil = \frac{\omega_0^2}{s^2 + 2\xi\omega_0 s + \omega_0^2}$$

Poles at:

$$s = -\omega_0\xi \pm i\omega_0\sqrt{1 - \xi^2}$$

Pole-zero diagram:

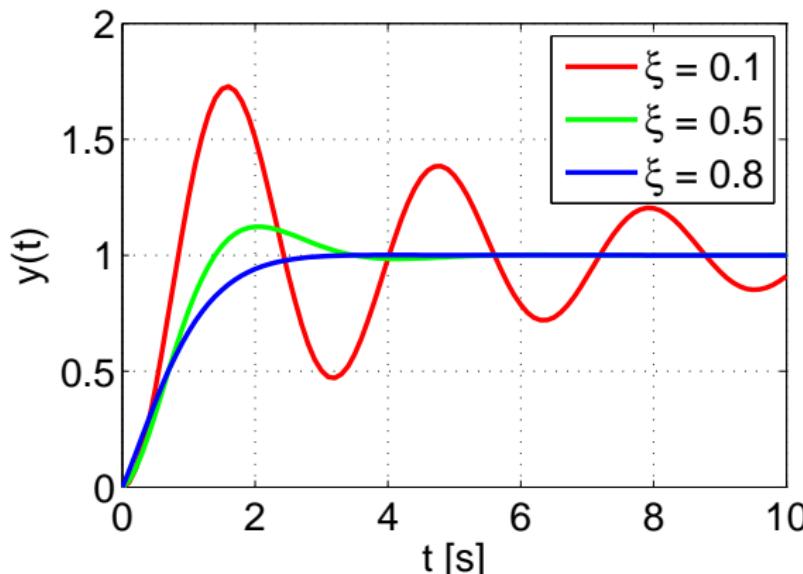


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Poles and time responses

Dominating pole = poles which is closest to the origin

Ex.: 3rd-order system

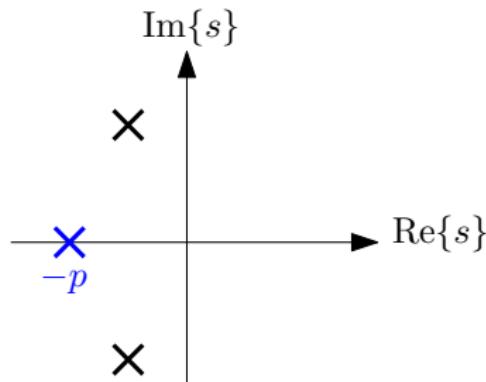
$$G(s) = \frac{p}{s + p} \cdot \frac{\omega_0^2}{s^2 + 2\zeta\omega_0 s + \omega_0^2}$$

with $\omega_0 = 1$ and $\zeta = \sqrt{0.5}$.

Poles at:

$$s = -p \quad \text{och} \quad s = -\omega_0\xi \pm i\omega_0\sqrt{1 - \xi^2}$$

Pole-zero diagram:



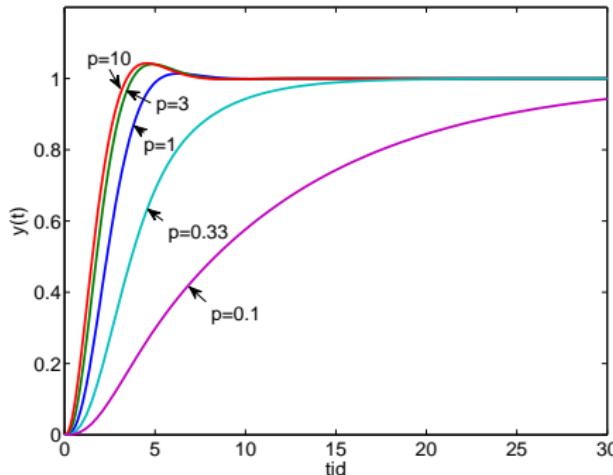
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Step response and static gain

Assume stable system $Y(s) = G(s)U(s)$ with

$$u(t) = \begin{cases} u_0 \text{ (const.)} & \text{für } t \geq 0, \\ 0 & \text{für } t < 0, \end{cases} \quad \xleftrightarrow{\mathcal{L}} \quad U(s) = \frac{u_0}{s}$$

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Final value of step response $y(t)$ can be computed using [final value theorem](#):

$$y_f = \lim_{t \rightarrow \infty} y(t) = \lim_{s \rightarrow 0} sY(s) = \lim_{s \rightarrow 0} sG(s) \frac{u_0}{s} =$$

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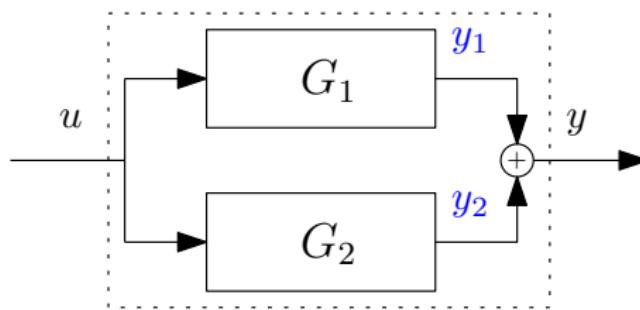
$$y_f = \lim_{t \rightarrow \infty} y(t) = \lim_{s \rightarrow 0} sY(s) = \lim_{s \rightarrow 0} sG(s)\frac{u_0}{s} = G(0)u_0$$

The system static gain is therefore $G(0)$.

Connected and feedback systems

Transfer function obtained using Laplace + added help signals

Ex.: Parallel-connected systems



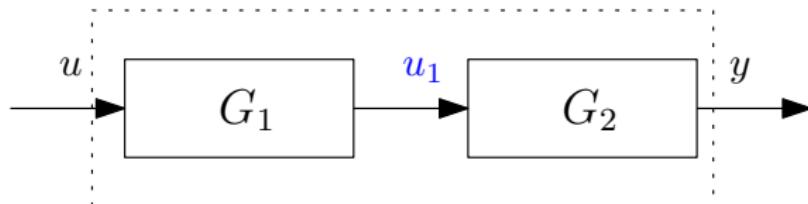
With added help signals:

$$\begin{aligned} Y(s) &= Y_1(s) + Y_2(s) = G_1(s)U(s) + G_2(s)U(s) \\ &= (G_1(s) + G_2(s))U(s) \end{aligned}$$

Connected and feedback systems

Transfer function obtained using Laplace + added help signals

Ex.: Serial-connected systems



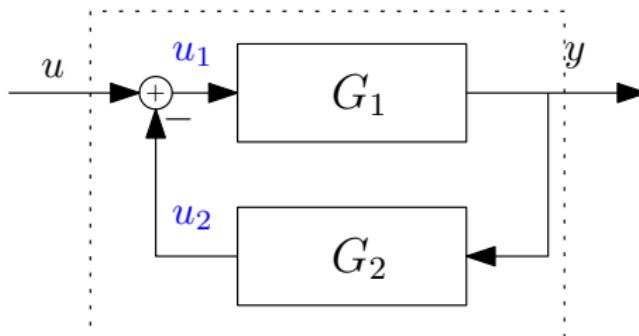
With added help signals:

$$\begin{aligned} Y(s) &= G_2(s)U_1(s) = G_2(s)(G_1(s)U(s)) \\ &= G_2(s)G_1(s)U(s) \end{aligned}$$

Connected and feedback systems

Transfer function obtained using Laplace + added help signals

Ex.: Feedback systems

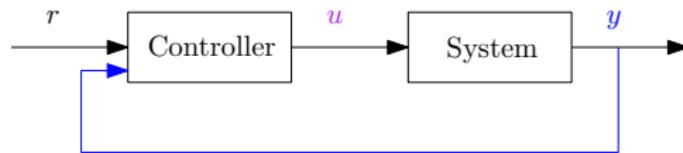


[Board: derive transfer function $u \rightarrow y$]

Feedback control based on error signal

PID-control

Feedback control:



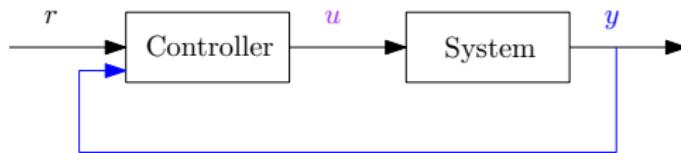
A *simple* strategy: Control using the control error

$$e(t) \triangleq r(t) - y(t)$$

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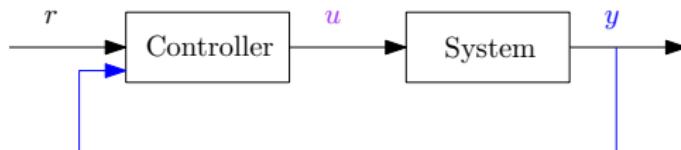
Determine input $u(t)$ based on:

- ▶ current error: $\propto e(t)$ (Proportional)

Feedback control based on error signal

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Feedback control:



A *simple* strategy: Control using the control error

$$e(t) \triangleq r(t) - y(t)$$

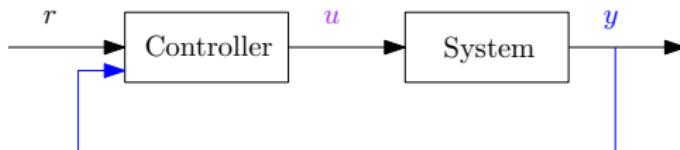
Determine input $u(t)$ based on:

- ▶ current error: $\propto e(t)$ (Proportional)
- ▶ past error: $\propto \int_{\tau=0}^t e(\tau)d\tau$ (Integral)

Feedback control based on error signal

PID-control

Feedback control:



A *simple* strategy: Control using the **control error**

$$e(t) \triangleq r(t) - y(t)$$

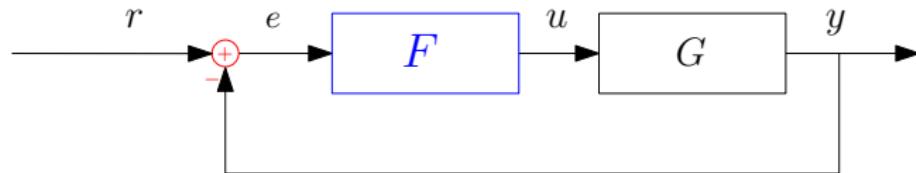
Determine input $u(t)$ based on:

- ▶ *current* error: $\propto e(t)$ (Proportional)
- ▶ *past* error: $\propto \int_{\tau=0}^t e(\tau)d\tau$ (Integral)
- ▶ *change in* error: $\propto \dot{e}(t)$ (Derivative)

Ideal PID-controller

Controller with user parameters:

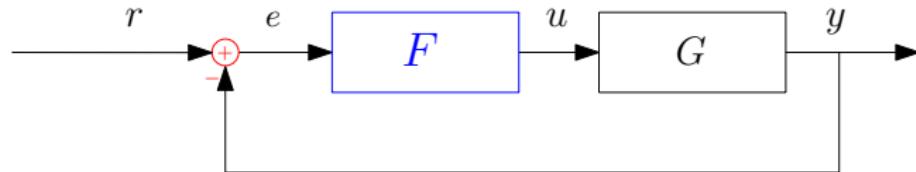
$$u(t) = \underbrace{K_p e(t)}_{P} + \underbrace{K_i \int_{\tau=0}^t e(\tau) d\tau}_{I} + \underbrace{K_d \dot{e}(t)}_{D}$$



Ideal PID-controller

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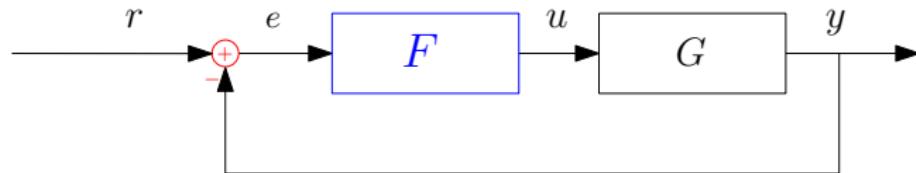
Laplace domain:

$$\begin{aligned} U(s) &= K_p E(s) + K_i \frac{1}{s} E(s) + K_d s E(s) \\ &= \underbrace{\left(K_p + \frac{K_i}{s} + K_d s \right)}_{\text{controller } F(s)} E(s). \end{aligned}$$

Ideal PID-controller

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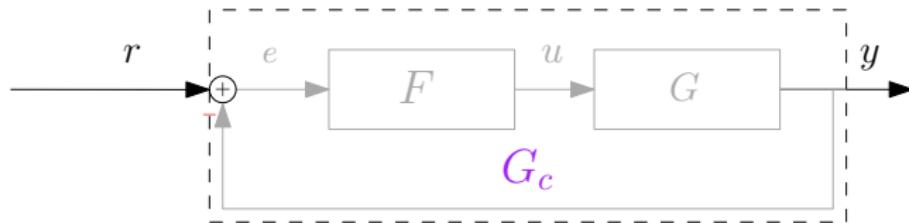
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Simple feedback control system

Open and closed-loop systems

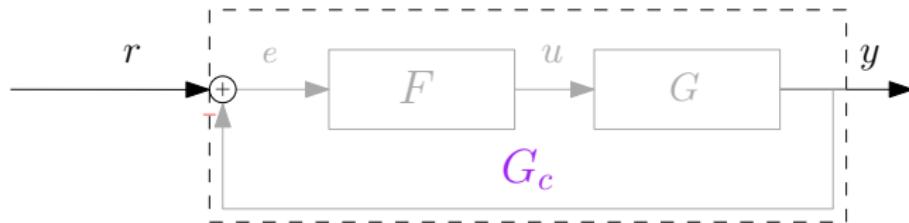
- ▶ Open-loop system from e to y : $G_o(s) \triangleq G(s)F(s)$
- ▶ Closed-loop system from r to y : $G_c(s)$



Simple feedback control system

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- ▶ Closed-loop system from r to y : $G_c(s)$



[Board: derive closed-loop system G_c]

Note: We can design the poles of G_c !

Accuracy: stationary control error

Using a step as reference signal r

- ▶ Assume stable $G_c(s)$ with reference (step):

$$r(t) = \begin{cases} r_0 & \text{för } t \geq 0, \\ 0 & \text{för } t < 0, \end{cases} \quad \xleftrightarrow{\mathcal{L}} \quad R(s) = \frac{r_0}{s}$$

Final value of error $e(t) \quad \xleftrightarrow{\mathcal{L}} \quad E(s) = R(s) - Y(s)$:

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$$\begin{aligned} e_f &= \lim_{t \rightarrow \infty} e(t) = \lim_{s \rightarrow 0} sE(s) = \lim_{s \rightarrow 0} s \frac{1}{1 + G_0(s)} \frac{r_0}{s} \\ &= \lim_{s \rightarrow 0} \frac{r_0}{1 + G(s)\color{blue}{F(s)}} = 0? \end{aligned}$$

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- ▶ Stationary error e_f approaches 0 if $G(0)\color{blue}{F(0)} = \infty$.
- ▶ Accomplished if e.g. $\color{blue}{F(s)}$ contains $\frac{1}{s}$, i.e. integration.

Summary and recap

- ▶ Relation between poles and system time-response
- ▶ The transfer function for connected and feedback systems
- ▶ Simple feedback control and ideal PID-controller
- ▶ Control accuracy: stationary error