Motor Modeling and Position Control Lab
Week 3: Closed Loop Control

1. Review

In the first week of motor modeling lab, a mathematical model of a DC motor from first principles was derived to obtain a first order system. The open and closed loop (proportional-derivative) control was implemented specifically for this motor model. In the second week, a physical DC motor (Quanser SRV-02) was used for open-loop control implementation and the first order transient characteristics were observed. Based on the model response, DC motor parameters (time constant) were estimated both by hand-calculations as well as using MATLAB. You should have also observed in the open loop control of actual DC motor that the motor positions start to drift over time indicating continuous accumulation of error within the system. Another observation that should have been made is that there is no way to enforce the output of the motor to track the input voltage in the absence of any feedback loop.

In the final week of this lab, you will try to address some of these issues by realizing the benefits of closed-loop control of DC motor. In particular, you will:

1. study transient characteristics of a typical second order system and evaluate model or system responses using these specifications.
2. extend the closed loop control implemented in the first week of this lab to the actual DC motor
3. analyze the effects of proportional-, derivative- and integral- control individually and in combination on the closed loop response of motor
4. solve a position control problem by calculating PD controller gains analytically and validate the control by monitoring the motor response for different desired trajectories
5. design a PID controller for the actual DC motor using Ziegler-Nichols' method and compare the performance with that of the PD controller

2. DC Motor Model

We derived the mathematical model of DC motor earlier and obtained the following first order transfer function that relates the motor velocity (rad/s) to input voltage (V) as:

$$\frac{\Omega_l(s)}{V_m(s)} = \frac{K}{\tau s + 1}. \tag{1}$$

where τ is the mechanical time constant of the system, and K is the steady state gain(also known as DC gain).

Since, angular position can be obtained by integration of angular velocity, the open loop transfer function between angular position (rad) and input voltage (V) can be obtained from (1) as in (2):

$$\frac{\Theta_l(s)}{V_m(s)} = \frac{K}{s(\tau s + 1)} = \frac{K}{\tau s^2 + s} = \frac{a}{s^2 + bs} \quad \because \Theta_l(s) = \frac{1}{s}\Omega_l(s) \tag{2}$$

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Sabine Zange

Motor Modeling And Position Control Lab Week 3 Closed:

New Realities, Mobile Systems and Applications Michael E. Auer,Thrasyvoulos Tsiatsos,2022-04-08 This book devotes to new approaches in interactive mobile technologies with a focus on learning Interactive mobile technologies are today the core of many if not all fields of society Not only the younger generation of students expects a mobile working and learning environment And nearly daily new ideas technologies and solutions boost this trend To discuss and assess the trends in the interactive mobile field are the aims connected with the 14th International Conference on Interactive Mobile Communication Technologies and Learning IMCL2021 which was held online from 4 to 5 November 2021 Since its beginning in 2006 this conference is devoted to new approaches in interactive mobile technologies with a focus on learning Nowadays the IMCL conferences are a forum of the exchange of new research results and relevant trends as well as the exchange of experiences and examples of good practice Interested readership includes policy makers academics educators researchers in pedagogy and learning theory school teachers learning Industry further education lecturers etc **Report summaries** United States. Environmental Protection Agency,1983 Youth's Companion ,1925 Illuminating Engineering ,1954-07

Energy Research Abstracts ,1993 **Motor Age** ,1910 **Wireless World** ,1983 *Canned Goods Trade* ,1923

Canning Trade ,1923 **Aerial Age Weekly** ,1922 The Canner ,1946 *Flight* ,1913 **EPA Reports Bibliography** United States. Environmental Protection Agency,1980 **Scientific American** ,1920 Monthly magazine devoted to topics of general scientific interest Proceedings of the IEEE 1976 National Aerospace and Electronics Conference, NAECON '76, Held at the Dayton Convention Center, May 18, 19, 20, 1976 ,1976 *Popular Science* ,1945-01 Popular Science gives our readers the information and tools to improve their technology and their world The core belief that Popular Science and our readers share The future is going to be better and science and technology are the driving forces that will help make it better **The Wall Street Journal** ,1975 *Innovations in Engineering Education* ,2005 **The Wall Street Journal Index** ,1975 Electrical Times ,1964

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