

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:

$$\frac{\Omega_v(s)}{V_m(s)} = \frac{K}{\tau s + 1} \quad (1)$$

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):

$$\frac{\Theta(s)}{V_m(s)} = \frac{K}{s(\tau s + 1)} = \frac{K}{\tau s^2 + s} = \frac{a}{s^2 + bs} \quad \therefore \Theta_v(s) = \frac{1}{s} \Omega_v(s) \quad (2)$$

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Michael Hoelscher



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Table of Contents Motor Modeling And Position Control Lab Week 3 Closed

1. Understanding the eBook Motor Modeling And Position Control Lab Week 3 Closed
 - The Rise of Digital Reading Motor Modeling And Position Control Lab Week 3 Closed
 - Advantages of eBooks Over Traditional Books
2. Identifying Motor Modeling And Position Control Lab Week 3 Closed
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Motor Modeling And Position Control Lab Week 3 Closed
 - User-Friendly Interface
4. Exploring eBook Recommendations from Motor Modeling And Position Control Lab Week 3 Closed
 - Personalized Recommendations
 - Motor Modeling And Position Control Lab Week 3 Closed User Reviews and Ratings

- Motor Modeling And Position Control Lab Week 3 Closed and Bestseller Lists
- 5. Accessing Motor Modeling And Position Control Lab Week 3 Closed Free and Paid eBooks
 - Motor Modeling And Position Control Lab Week 3 Closed Public Domain eBooks
 - Motor Modeling And Position Control Lab Week 3 Closed eBook Subscription Services
 - Motor Modeling And Position Control Lab Week 3 Closed Budget-Friendly Options
- 6. Navigating Motor Modeling And Position Control Lab Week 3 Closed eBook Formats
 - ePub, PDF, MOBI, and More
 - Motor Modeling And Position Control Lab Week 3 Closed Compatibility with Devices
 - Motor Modeling And Position Control Lab Week 3 Closed Enhanced eBook Features
- 7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Motor Modeling And Position Control Lab Week 3 Closed
 - Highlighting and Note-Taking Motor Modeling And Position Control Lab Week 3 Closed
 - Interactive Elements Motor Modeling And Position Control Lab Week 3 Closed
- 8. Staying Engaged with Motor Modeling And Position Control Lab Week 3 Closed
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Motor Modeling And Position Control Lab Week 3 Closed
- 9. Balancing eBooks and Physical Books Motor Modeling And Position Control Lab Week 3 Closed
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Motor Modeling And Position Control Lab Week 3 Closed
- 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
- 11. Cultivating a Reading Routine Motor Modeling And Position Control Lab Week 3 Closed
 - Setting Reading Goals Motor Modeling And Position Control Lab Week 3 Closed
 - Carving Out Dedicated Reading Time
- 12. Sourcing Reliable Information of Motor Modeling And Position Control Lab Week 3 Closed
 - Fact-Checking eBook Content of Motor Modeling And Position Control Lab Week 3 Closed
 - Distinguishing Credible Sources

13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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