

Simulink[®] Control Design[™] 3

Getting Started Guide

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Simulink® Control Design™ Getting Started Guide

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Product Overview

1

Steady-State Operating Points

2

What Is a Steady-State Operating Point?	2-2
Steady-State Operating Points (Trimming) From Specifications	2-3
magball Simulink Model	2-9

Linearization

3

Applications of Linearization	3-2
Open-Loop Response of Control System for Stability Margin Analysis	3-3
Bode Response of Simulink Model	3-7
watertank Simulink Model	3-12

4

Automated Tuning of Simulink PID Controller

Block 4-2

Introduction 4-2

Introduction of the PID Tuner 4-2

Opening the Model 4-3

Design Overview 4-3

Opening the PID Tuner 4-3

Initial PID Design 4-4

Displaying PID Parameters 4-5

Adjusting PID Design in the PID Tuner 4-7

Completing the Design in the Extended Design Mode 4-8

Writing the Tuned Parameters to PID Controller Block .. 4-12

Completed Design 4-12

Designing a PID Controller Using Robust-Response-Time Tuning Algorithm and Bode Graphical Design 4-14

About This Tutorial 4-14

PID Control Design Using Robust-Response-Time Tuning Algorithm 4-19

PID Control Design Using Bode Graphical Tuning 4-28

Closed-Loop Simulation of Simulink Model 4-32

Examples

A

Getting Started A-2

Automated Tuning of Simulink PID Controller

Block A-2

Index

Product Overview

Simulink® Control Design™ lets you design and analyze control systems modeled in Simulink. You can automatically tune the gains of the Simulink PID Controller block to meet performance requirements. With this product you can also non-intrusively find trim points and compute exact linearizations of Simulink models at various operating conditions. Simulink Control Design provides tools for computing simulation-based frequency responses without modifying your model. A graphical user interface lets you design and analyze arbitrary control structures modeled in Simulink, such as cascaded, pre-filter, regulation, and multi-loop architectures.

[Learn More](#)

Steady-State Operating Points

- “What Is a Steady-State Operating Point?” on page 2-2
- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3
- “magball Simulink Model” on page 2-9

What Is a Steady-State Operating Point?

A *steady-state operating point* of the model, also called equilibrium or *trim* condition, includes state variables that do not change with time.

A model might have several steady-state operating points. For example, a hanging pendulum has two steady-state operating points. A *stable steady-state operating point* occurs when a pendulum hangs straight down. That is, the pendulum position does not change with time. When the pendulum position deviates slightly, the pendulum always returns to equilibrium; small changes in the operating point do not cause the system to leave the region of good approximation around the equilibrium value.

An *unstable steady-state operating point* occurs when a pendulum points upward. As long as the pendulum points *exactly* upward, it remains in equilibrium. However, when the pendulum deviates slightly from this position, it swings downward and the operating point leaves the region around the equilibrium value.

When using optimization search to compute operating points for a nonlinear system, your initial guesses for the states and input levels must be in the neighborhood of the desired operating point to ensure convergence.

When linearizing a model with multiple steady-state operating points, it is important to have the right operating point. For example, linearizing a pendulum model around the stable steady-state operating point produces a stable linear model, whereas linearizing around the unstable steady-state operating point produces an unstable linear model.

Examples and How To

- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3
- “Steady-State Operating Points From Simulation”

More About

- “Steady-State Operating Point (Trimming)”
- “Operating Point Object Includes a Subset of Simulink® Model States”

Steady-State Operating Points (Trimming) From Specifications

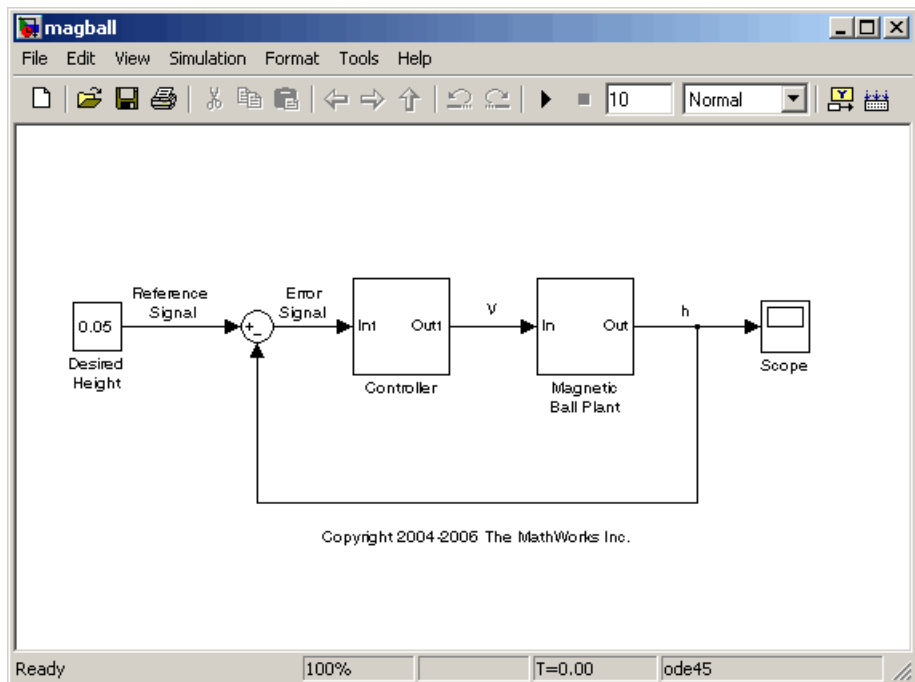
This example shows how to compute a steady-state operating point, or equilibrium operating point, by specifying known (fixed) equilibrium states and minimum state values.

Code Alternative

Use `findop` to find operating point from specifications. For examples and additional information, see the `findop` reference page.

- 1 Open Simulink model.

```
sys = 'magball';  
open_system(sys)
```

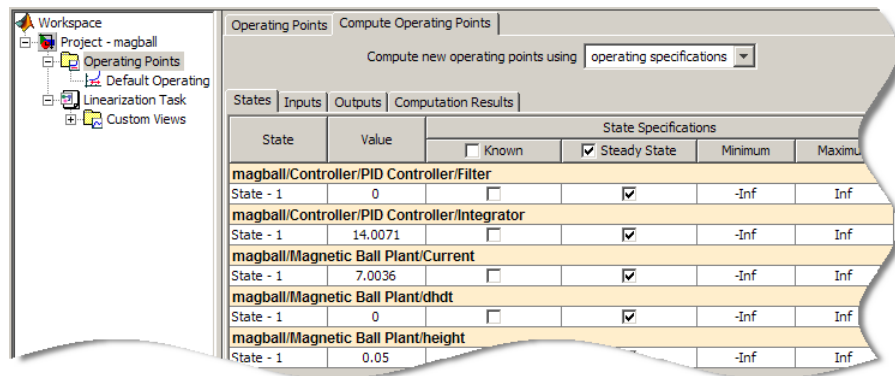


- 2 In the Simulink model window, select **Tools > Control Design > Linear Analysis**.

This action starts a new project in the Control and Estimation Tools Manager.

- 3 Select **Operating Points** and click the **Compute Operating Points** tab.

By default, all model states are specified to be at equilibrium (**Steady State**). The **Inputs** and **Outputs** tabs are empty because this model does not have root-level input and output ports, respectively.



The screenshot shows the 'Compute Operating Points' interface. The 'States' sub-tab is selected, showing a table of state specifications. The table has columns for State, Value, and State Specifications (Known, Steady State, Minimum, Maximum). The 'Steady State' checkbox is checked for all states.

State	Value	State Specifications			
		<input type="checkbox"/> Known	<input checked="" type="checkbox"/> Steady State	Minimum	Maximum
magball/Controller/PID Controller/Filter					
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Controller/PID Controller/Integrator					
State - 1	14.0071	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Magnetic Ball Plant/Current					
State - 1	7.0036	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Magnetic Ball Plant/dhdt					
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Magnetic Ball Plant/height					
State - 1	0.05	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf

- 4 In the **States** tab, select **Known** for the **height** state.

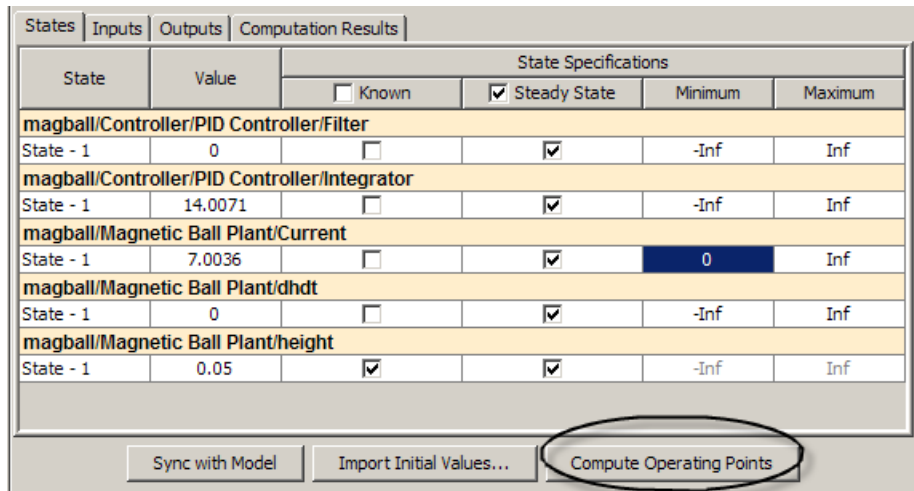
The height of the ball should match the reference signal height. This height value should remain fixed during the optimization.

States Inputs Outputs Computation Results						
State	Value	State Specifications				
		<input type="checkbox"/> Known	<input checked="" type="checkbox"/> Steady State	Minimum	Maximum	
magball/Controller/PID Controller/Filter						
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Controller/PID Controller/Integrator						
State - 1	14.0071	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Magnetic Ball Plant/Current						
State - 1	7.0036	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Magnetic Ball Plant/dhdt						
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Magnetic Ball Plant/height						
State - 1	0.05	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	

5 Enter 0 for the minimum bound of the **Current** state.

States Inputs Outputs Computation Results						
State	Value	State Specifications				
		<input type="checkbox"/> Known	<input checked="" type="checkbox"/> Steady State	Minimum	Maximum	
magball/Controller/PID Controller/Filter						
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Controller/PID Controller/Integrator						
State - 1	14.0071	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Magnetic Ball Plant/Current						
State - 1	7.0036	<input type="checkbox"/>	<input checked="" type="checkbox"/>	0	Inf	
magball/Magnetic Ball Plant/dhdt						
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	
magball/Magnetic Ball Plant/height						
State - 1	0.05	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf	

6 Click **Compute Operating Points**.

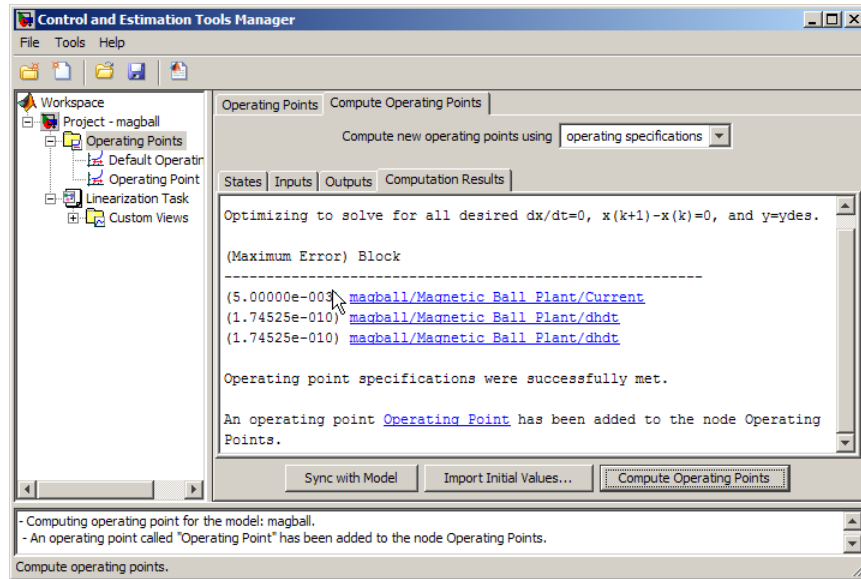


States		Inputs	Outputs	Computation Results	
State	Value	State Specifications			
		<input type="checkbox"/> Known	<input checked="" type="checkbox"/> Steady State	Minimum	Maximum
magball/Controller/PID Controller/Filter					
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Controller/PID Controller/Integrator					
State - 1	14.0071	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Magnetic Ball Plant/Current					
State - 1	7.0036	<input type="checkbox"/>	<input checked="" type="checkbox"/>	0	Inf
magball/Magnetic Ball Plant/dhdt					
State - 1	0	<input type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf
magball/Magnetic Ball Plant/height					
State - 1	0.05	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	-Inf	Inf

Buttons: Sync with Model, Import Initial Values..., **Compute Operating Points**

This action uses numerical optimization to find the operating point that meets your specifications.

The **Computation Results** tab shows that the optimization algorithm terminated successfully. The (Maximum Error) Block area shows the progress of reducing the error of a specific state or output during the optimization.



7 Click **Operating Point** to evaluate whether the resulting operating point values meet the specifications.

The **Actual dx** values are near zero (**Desired dx**), which indicates that the operating point meets the steady state specification.

The **Actual Value** of the states falls within the **Desired Value** bounds.

The screenshot shows the 'States' tab of the 'Compute Operating Points' dialog. The table below displays the desired and actual values for various states of the magnetic ball plant model.

State	Desired Value	Actual Value	Desired dx	Actual dx
magball/Controller/PID Controller/Filter				
State - 1	[-Inf, Inf]	0	0	0
magball/Controller/PID Controller/Integrator				
State - 1	[-Inf, Inf]	14.0071	0	0
magball/Magnetic Ball Plant/Current				
State - 1	[0, Inf]	7.0036	0	4.2064e-011
magball/Magnetic Ball Plant/dhdt				
State - 1	[-Inf, Inf]	0	0	-1.7453e-010
magball/Magnetic Ball Plant/height				
State - 1	0.05	0.05	0	0

- 8** (Optional) Select **File > Generate MATLAB Code** to automatically generate a MATLAB® script.

This script contains all commands for the most recent **Compute Operating Points** operation in Control and Estimation Tools Manager.

Tip Alternatively, click  to generate code.

Related Examples

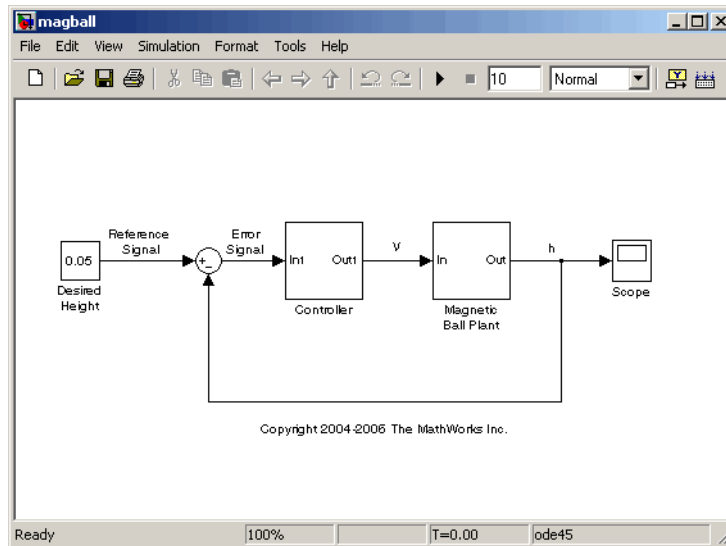
- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3
- “Steady-State Operating Points From Simulation”

More About

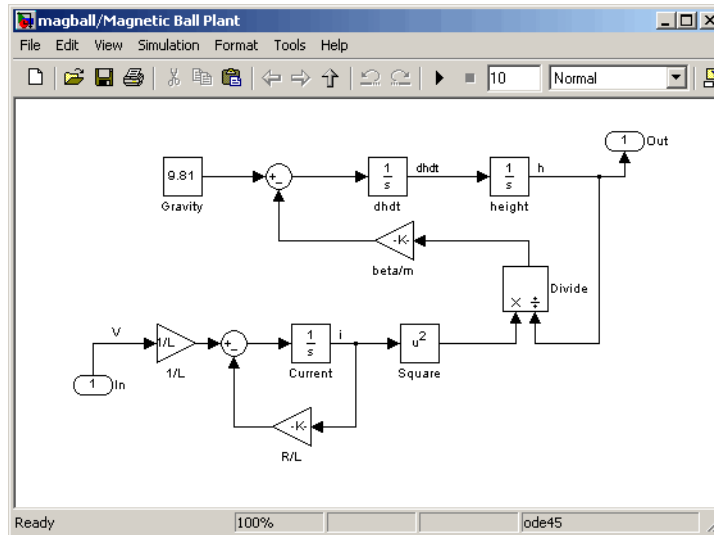
- “magball Simulink Model” on page 2-9
- “Steady-State Operating Point (Trimming)”

magball Simulink Model

The Simulink model magball includes the nonlinear Magnetic Ball Plant in a single-loop feedback system.



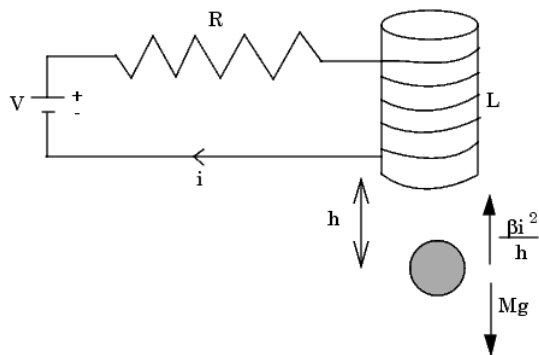
The Magnetic Ball Plant subsystem is shown in the following figure.



The Magnetic Ball Plant model represents an iron ball of mass M . This ball moves under the influence of the gravitational force, Mg , and an induced

magnetic force, $\frac{\beta i^2}{h}$. The presence of the squared term in the induced magnetic force results in a nonlinear plant.

The inductor in the electric circuit, shown in the following figure, causes the induced magnetic force. This circuit also includes a voltage source and a resistor.



The following table describes the variables, parameters, differential equations, states, inputs, and outputs of the Magnetic Ball Plant subsystem.

Variables	<p>h is the height of the ball.</p> <p>i is the current.</p> <p>V is the voltage in the circuit.</p>
Parameters	<p>M is the mass of the ball.</p> <p>g is the gravitational acceleration.</p> <p>β is a constant related to the magnetic force.</p> <p>L is the inductance of the coil.</p> <p>R is the resistance of the circuit.</p>
Differential equations	<p>The height of the ball, h, is described in the following equation:</p> $M \frac{d^2 h}{dt^2} = Mg - \frac{\beta i^2}{h}$ <p>The current in the circuit, i, is described in the following equation:</p> $L \frac{di}{dt} = V - iR$
States	<p>h</p> <p>dh/dt</p> <p>i</p>
Inputs	V
Outputs	h

Examples and How To

“Steady-State Operating Points (Trimming) From Specifications” on page 2-3

Linearization

- “Applications of Linearization” on page 3-2
- “Open-Loop Response of Control System for Stability Margin Analysis” on page 3-3
- “Bode Response of Simulink Model” on page 3-7
- “watertank Simulink Model” on page 3-12

Applications of Linearization

Linearization is useful in model analysis and control design applications. After you linearize a Simulink model at a specific operating point, you can use your linear model to:

- Compute the Bode response of the Simulink model.
- Evaluate loop stability margins by computing open-loop response.
- Obtain linear state-space, transfer-function, or zero-pole-gain representation of the combined Simulink model that contains only linear blocks.
- Analyze and compare plant response near different operating points.
- Design linear controller

Classical control system analysis and design methodologies require linear, time-invariant models. Simulink Control Design automatically linearizes the plant when you tune your compensator. See “PID Control Design Using Robust-Response-Time Tuning Algorithm” on page 4-19.

- Analyze closed-loop stability.
- Measure the size of resonances in frequency response by computing closed-loop linear model for control system.
- Generate controllers with reduced sensitivity to parameter variations and modeling errors (requires Robust Control Toolbox™).

Examples and How To

- “Open-Loop Response of Control System for Stability Margin Analysis” on page 3-3
- “Bode Response of Simulink Model” on page 3-7
- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3

More About

“Linearizing Nonlinear Models”

Open-Loop Response of Control System for Stability Margin Analysis

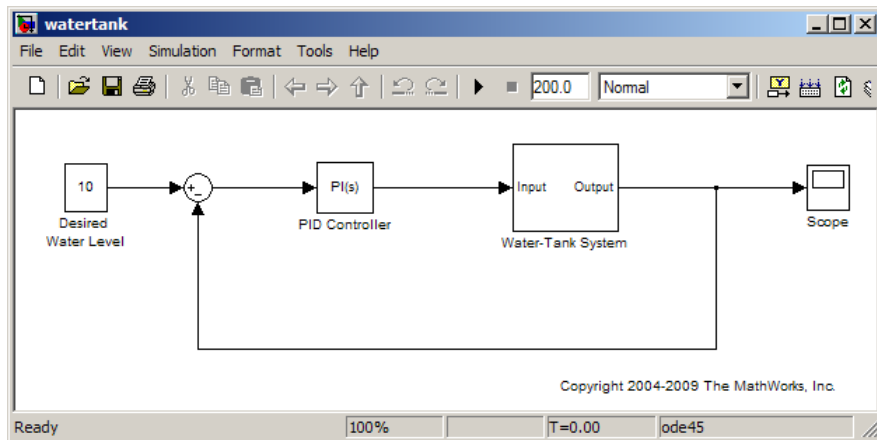
This example shows how to use Control and Estimation Tools Manager to analyze the open-loop response of a control system.

You compute a linear model of the combined controller-plant system without the effects of the feedback signal. A Bode plot of the resulting linear model shows the open-loop response.

1 Open Simulink model.

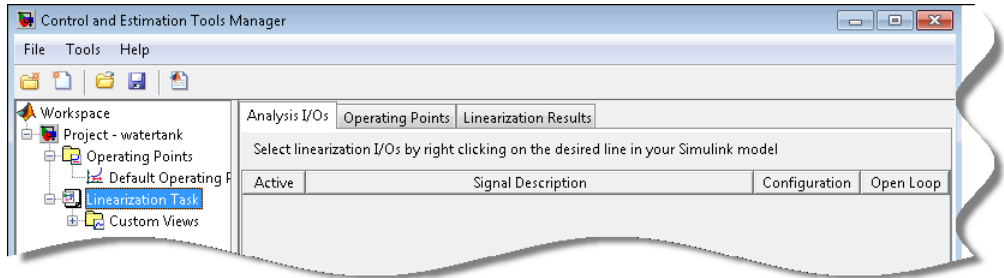
```
sys = 'watertank';  
open_system(sys)
```

The Water-Tank System block represents the plant in this control system and contains all of the system nonlinearities.



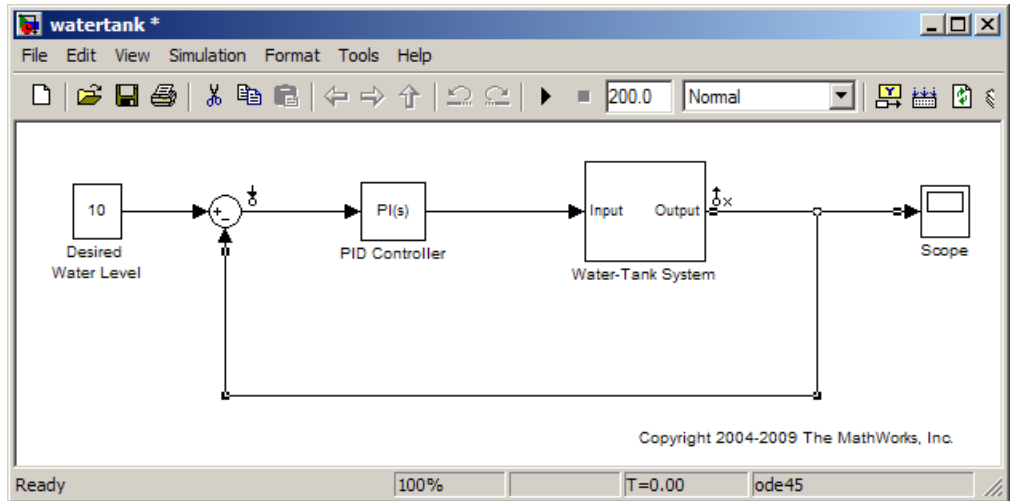
2 In the Simulink model window, select **Tools > Control Design > Linear Analysis**.

This action starts a new project in the Control and Estimation Tools Manager.



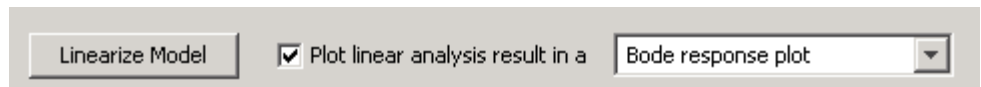
3 In the Simulink model window, define the portion of the model to linearize:

- Right-click the PID Controller block input signal (the output of the Sum block). Select **Linearization Points > Input Point**.
- Right-click the Water-Tank System output signal, and select **Linearization Points > Output Point**.
- Right-click the Water-Tank System output signal and select **Linearization Points > Open Loop**.



Note Do not open the loop by manually removing the feedback signal from the model. Removing the signal manually changes the model operating point.

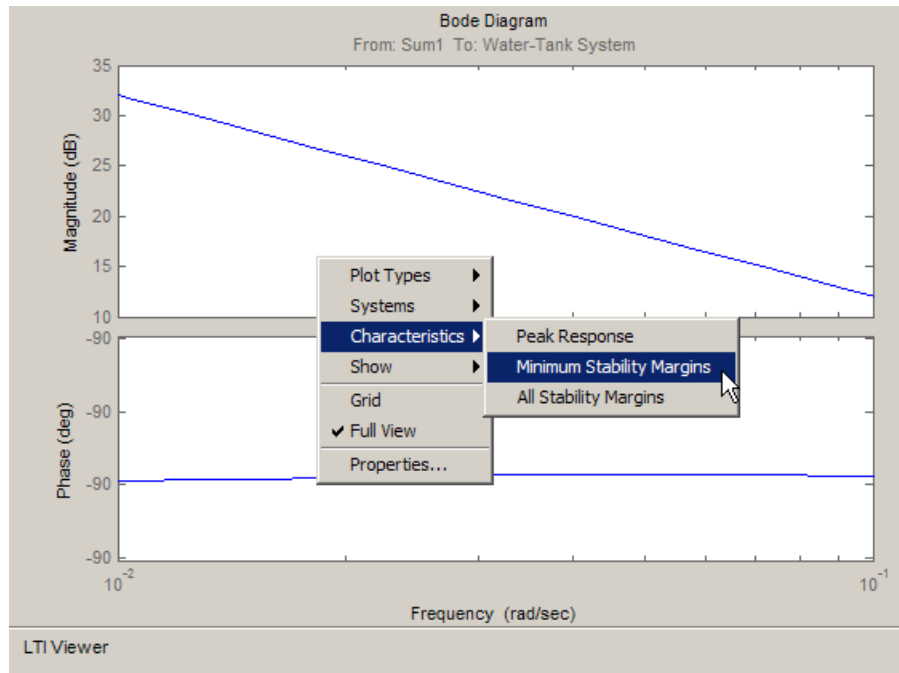
- 4 In the **Plot linear result in a** list, select Bode response plot.



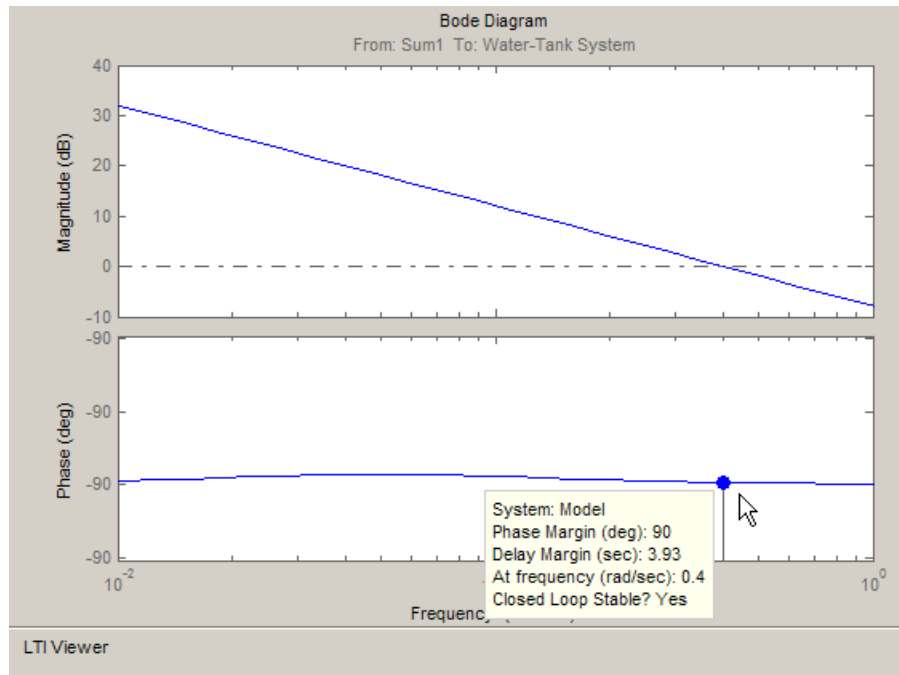
- 5 Click **Linearize Model**.

The Bode plot of the open-loop response appears in the LTI Viewer window.

- 6 Right-click the plot and select **Characteristics > Minimum Stability Margins**.



The Bode plot displays the phase margin marker. Click the marker to show a data tip that contains the phase margin value.



7 Close Simulink model.

```
bdclose(sys);
```

Related Examples

- “Bode Response of Simulink Model” on page 3-7
- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3

More About

- “Linearizing Nonlinear Models”
- “watertank Simulink Model” on page 3-12

Bode Response of Simulink Model

This example shows how to use Control and Estimation Tools Manager to linearize a model at the operating point specified in the model. The model operating point consists of the model initial state values and input signals.

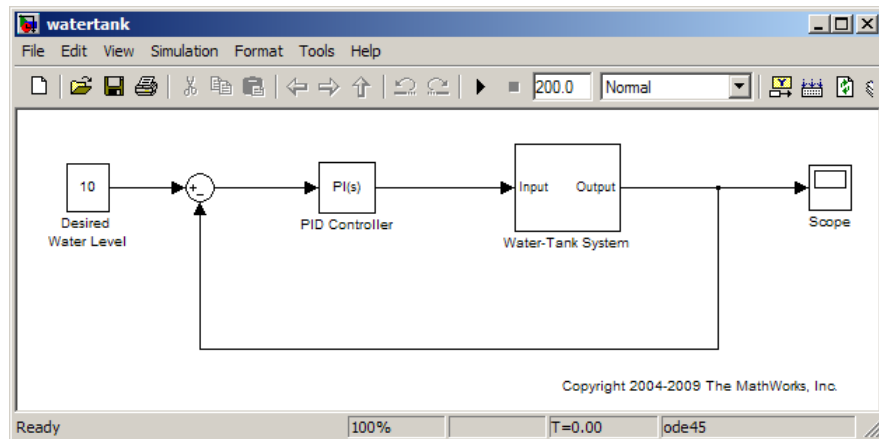
Code Alternative

Use `linearize`. For examples and additional information, see the `linearize` reference page.

- 1 Open Simulink model.

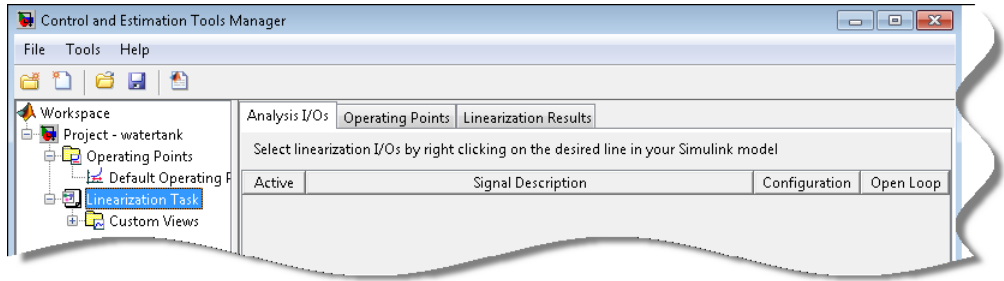
```
sys = 'watertank';  
open_system(sys)
```

The Water-Tank System block represents the plant in this control system and includes all of the system nonlinearities.



- 2 In the Simulink model window, select **Tools > Control Design > Linear Analysis**.

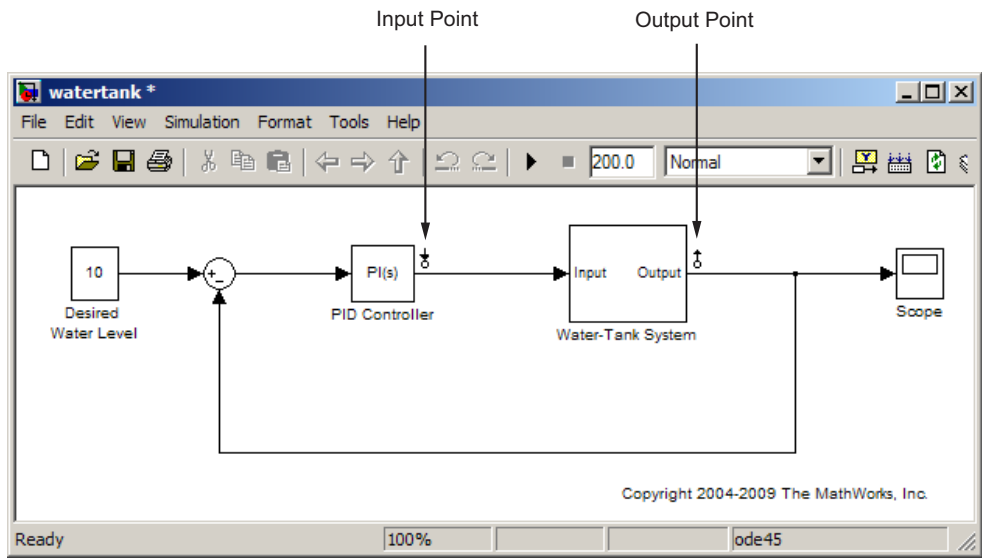
This action starts a new project in the Control and Estimation Tools Manager.



3 In the Simulink model window, define the portion of the model to linearize:

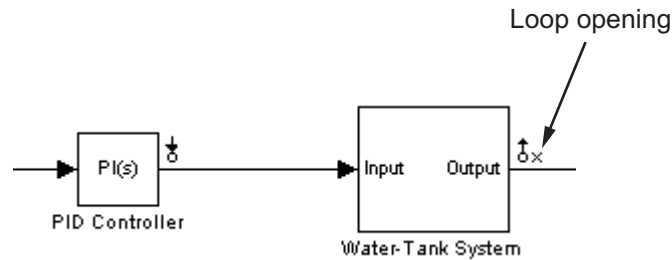
- Right-click the PID Controller block output signal, which is the input to the plant. Select **Linearization Points > Input Point**.
- Right-click the Water-Tank System output signal, and select **Linearization Points > Output Point**.

The linearization I/O markers appear in the model.

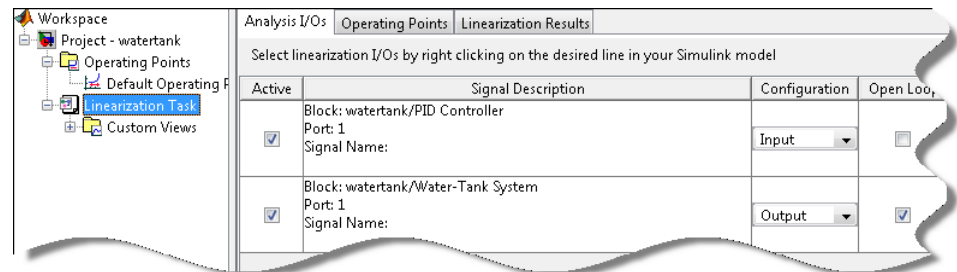


4 Right-click the Water-Tank System output signal and select **Linearization Points > Open Loop**.

This command removes the effects of the feedback signal on the linearization without changing the model operating point. The loop opening marker appears in the model.



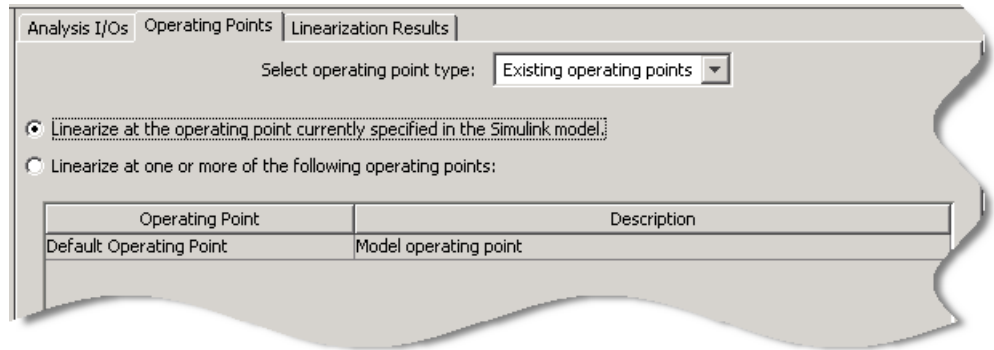
The **Analysis I/Os** tab of the Control and Estimation Tools Manager updates to show linearization input and output points.



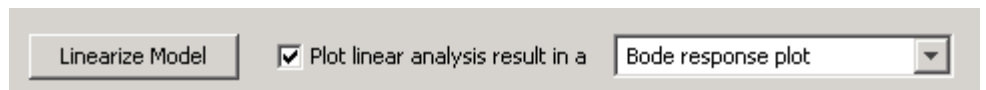
Note Do not open the loop by manually removing the feedback signal from the model. Removing the signal manually changes the operating point of the model.

5 Click the **Operating Points** tab.

The model operating point is already selected.

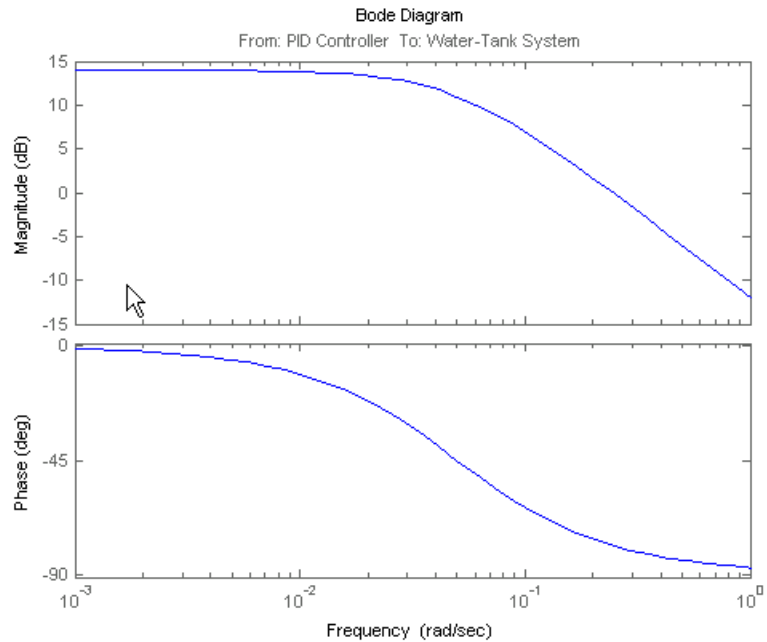


6 In the **Plot linear result in a** list, select Bode response plot.



7 Click **Linearize Model**.

The Bode plot of the linearized system appears in the LTI Viewer window. This Bode plot looks like a stable first-order response, as expected.



8 Close Simulink model.

```
bdclose(sys);
```

Related Examples

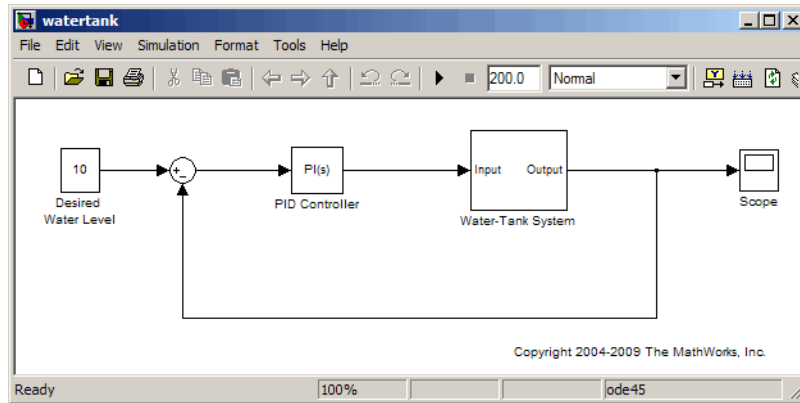
- “Open-Loop Response of Control System for Stability Margin Analysis” on page 3-3
- “Steady-State Operating Points (Trimming) From Specifications” on page 2-3

More About

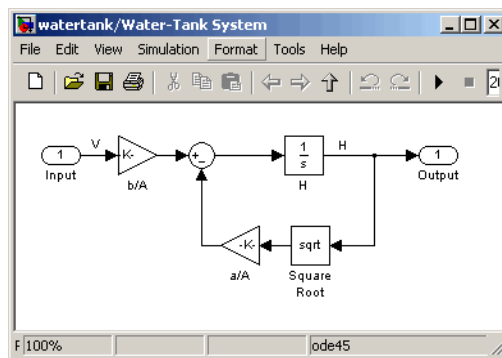
- “Linearizing Nonlinear Models”
- “watertank Simulink Model” on page 3-12

watertank Simulink Model

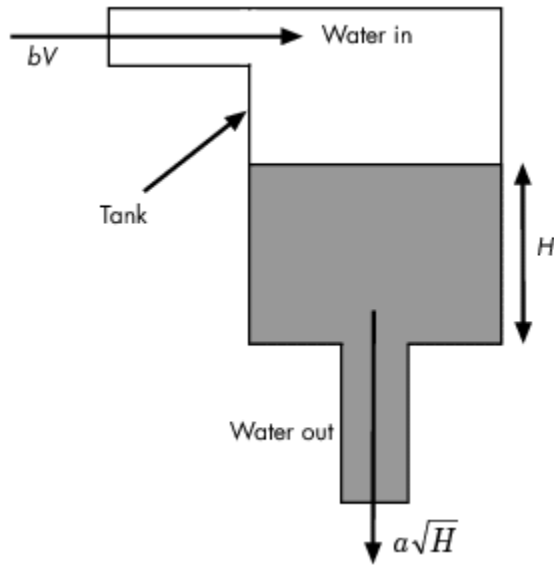
The Simulink model `watertank` model includes the nonlinear Water-Tank System plant and a PI controller in a single-loop feedback system.



The Water-Tank System is shown in the following figure.



Water enters the tank from the top at a rate proportional to the voltage, V , applied to the pump. The water leaves through an opening in the tank base at a rate that is proportional to the square root of the water height, H , in the tank. The presence of the square root in the water flow rate results in a nonlinear plant.



The following table describes the variables, parameters, differential equations, states, inputs, and outputs of the Water-Tank System.

Variables	<p>H is the height of water in the tank.</p> <p>Vol is the volume of water in the tank.</p> <p>V is the voltage applied to the pump.</p>
Parameters	<p>A is the cross-sectional area of the tank.</p> <p>b is a constant related to the flow rate into the tank.</p> <p>a is a constant related to the flow rate out of the tank.</p>

Differential equation	$\frac{d}{dt} Vol = A \frac{dH}{dt} = bV - a\sqrt{H}$
States	H
Inputs	V
Outputs	H

PID Control Design

- “Automated Tuning of Simulink PID Controller Block” on page 4-2
- “Designing a PID Controller Using Robust-Response-Time Tuning Algorithm and Bode Graphical Design” on page 4-14

Automated Tuning of Simulink PID Controller Block

In this section...

“Introduction” on page 4-2
“Introduction of the PID Tuner” on page 4-2
“Opening the Model” on page 4-3
“Design Overview” on page 4-3
“Opening the PID Tuner” on page 4-3
“Initial PID Design” on page 4-4
“Displaying PID Parameters” on page 4-5
“Adjusting PID Design in the PID Tuner” on page 4-7
“Completing the Design in the Extended Design Mode” on page 4-8
“Writing the Tuned Parameters to PID Controller Block” on page 4-12
“Completed Design” on page 4-12

Introduction

Introduction of the PID Tuner

PID Tuner provides a fast and widely applicable single-loop PID tuning method for the Simulink PID Controller blocks. With this method, you can tune PID parameters to achieve a robust design with the desired response time.

A typical design workflow with the PID Tuner involves the following tasks:

- (1) Launch the PID Tuner. When launching, the software automatically computes a linear plant model from the Simulink model and designs an initial controller.
- (2) Tune the controller in the PID Tuner by manually adjusting design criteria in two design modes. The tuner computes PID parameters that robustly stabilize the system.

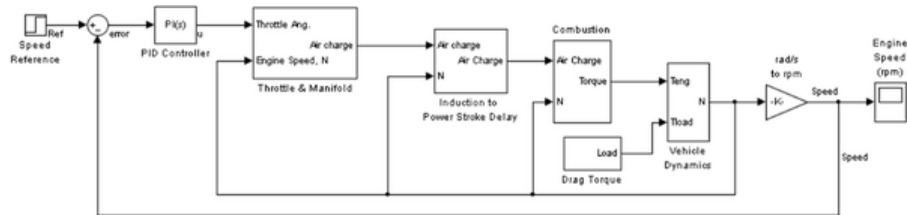
(3) Export the parameters of the designed controller back to the PID Controller block and verify controller performance in Simulink.

Opening the Model

Take a few moments to explore the model.

Open the engine speed control model with PID Controller block

```
open_system('scdspeedctrlpidblock');
```



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Design Overview

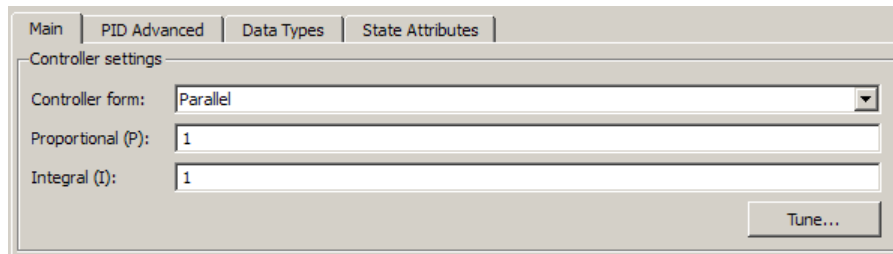
In this demo, you design a PI controller in an engine speed control loop. The goal of the design is to track the reference signal from a Simulink step block `scdspeedctrlpidblock/Speed Reference`. The design requirements are:

- Settling time under 5 seconds
- Zero steady-state error to the step reference input.

In this example, you stabilize the feedback loop and achieve good reference tracking performance by designing the PI controller `scdspeedctrl/PID Controller` in the PID Tuner.

Opening the PID Tuner

To launch the PID Tuner, double-click the PID Controller block to open its block dialog. In the *Main* tab, click *Tune*.

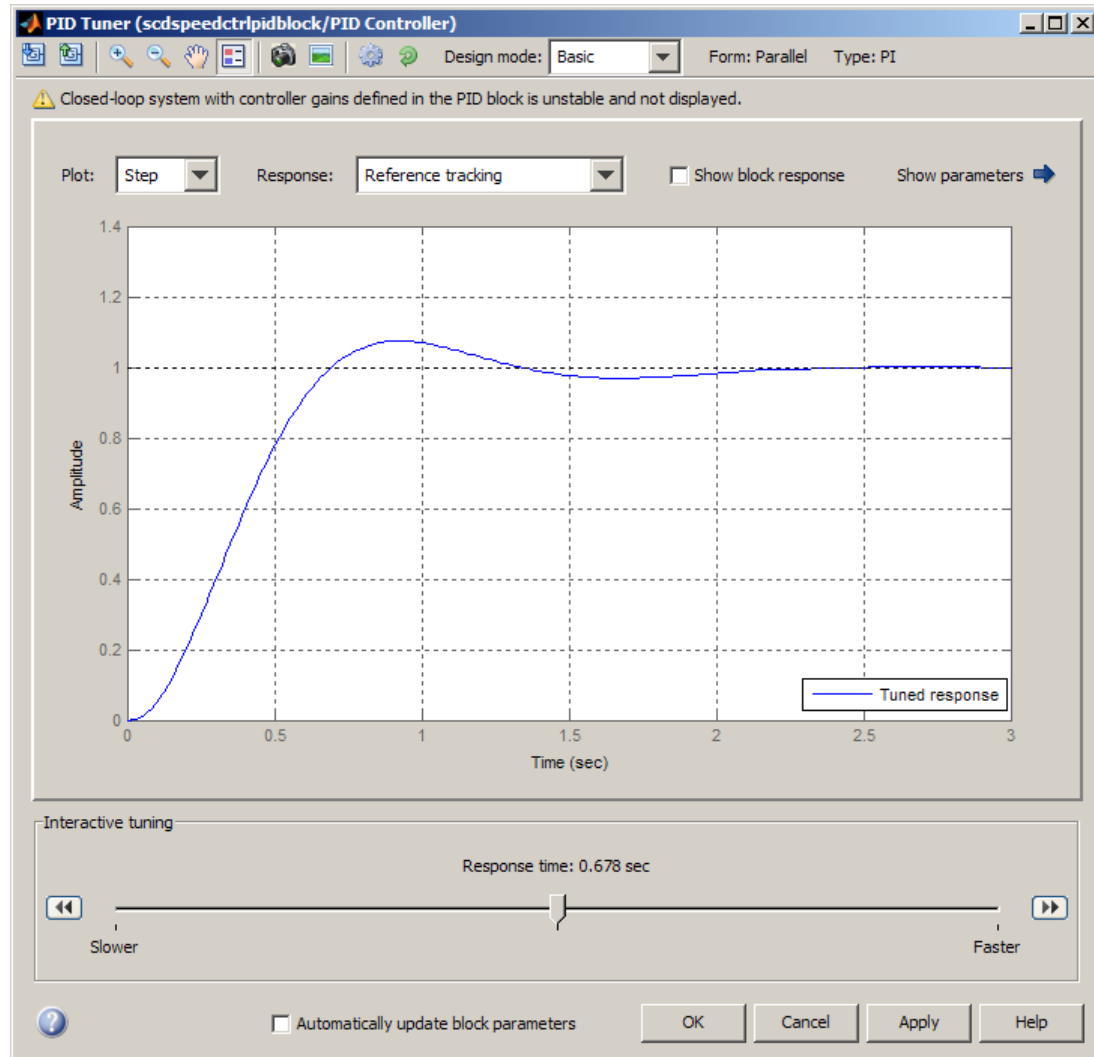


Initial PID Design

When the PID Tuner launches, the software computes a linearized plant model seen by the controller. The software automatically identifies the plant input and output, and uses the current operating point for the linearization. The plant can have any order and can have time delays.

The PID Tuner computes an initial PI controller to achieve a reasonable tradeoff between performance and robustness. By default, step reference tracking performance displays in the plot.

The following figure shows the PID Tuner dialog with the initial design:

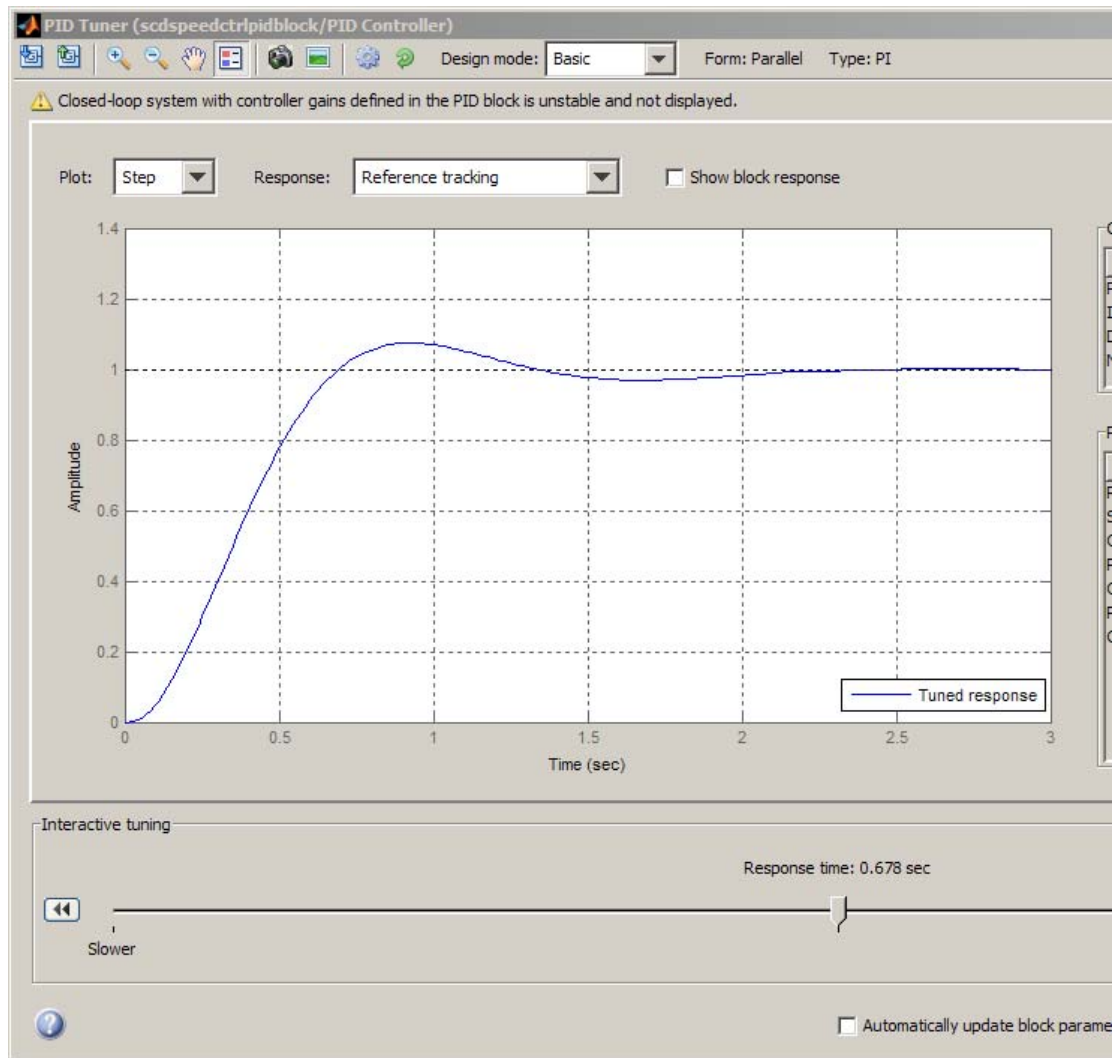


Displaying PID Parameters

Click the *Show parameters* arrow to view controller parameters P and I, and a set of performance and robustness measurements. In this example, the

initial PI controller design gives a settling time of 2 seconds, which meets the requirement.

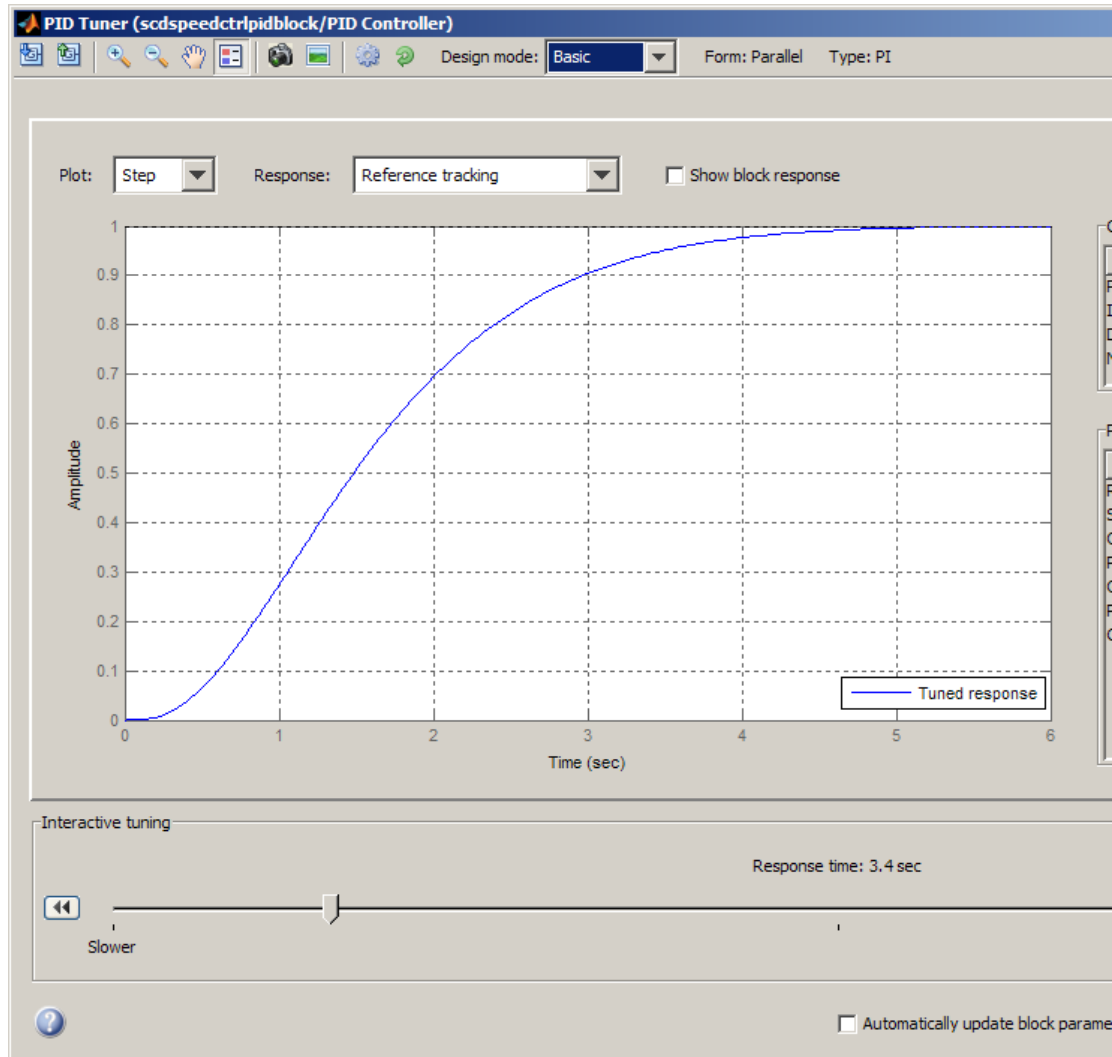
The following figure shows the parameter and performance tables:



Adjusting PID Design in the PID Tuner

The overshoot of the reference tracking response is about 8 percent. Because the response performance is limited in many systems with time delays, you need to slow down response speed to reduce overshoot. Move the response time slider to the left to increase the closed loop response time. Notice that when you adjust response time, the response plot and the controller parameters and performance measurements update.

The following figure shows an adjusted PID design with an overshoot of zero and a settling time of 4 seconds. The designed controller effectively becomes an integral-only controller.

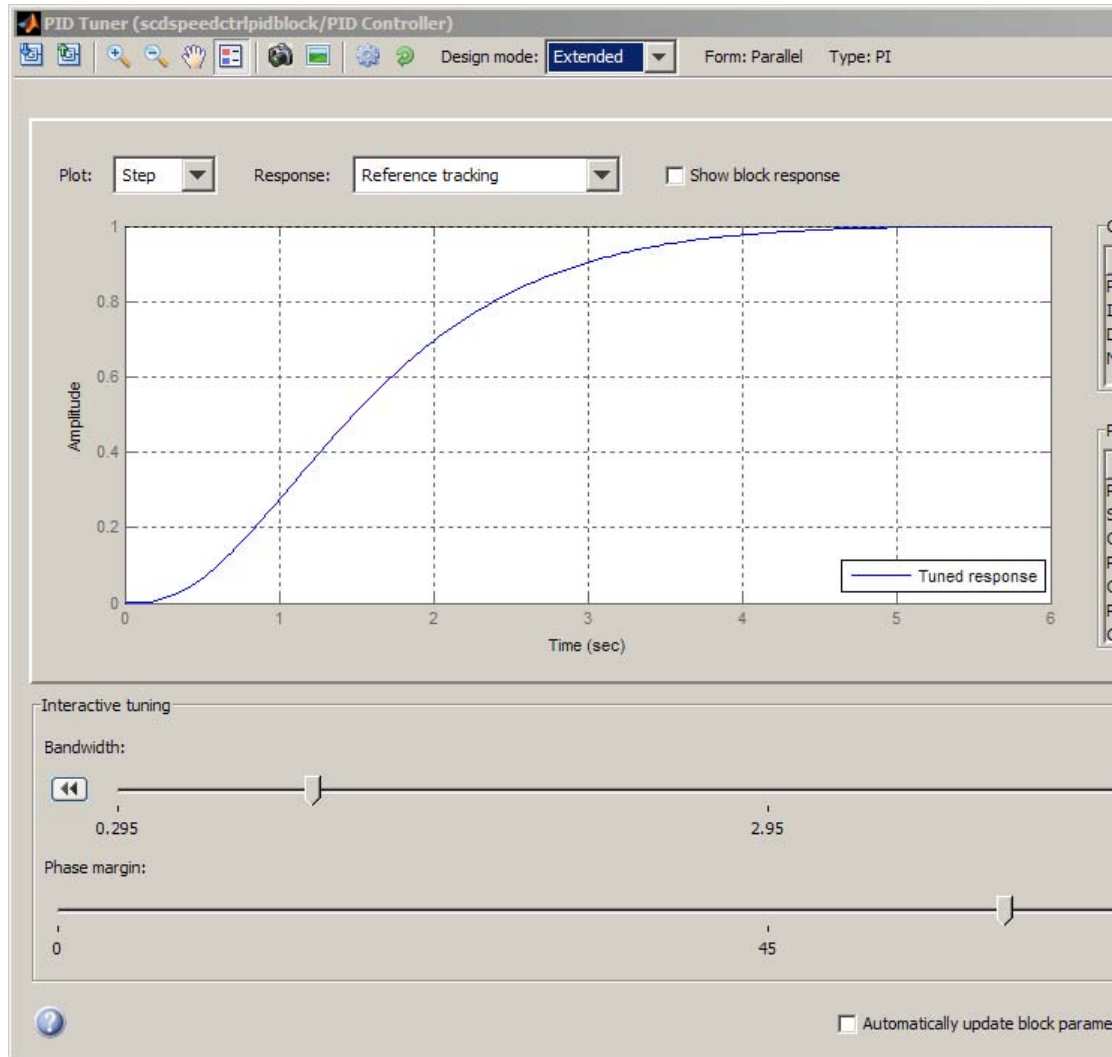


Completing the Design in the Extended Design Mode

To reduce the overshoot while maintaining the settling time of 2 seconds, you must tradeoff between controller performance (measured by settling time)

and robustness (measured by overshoot). You can perform such a trade-off in the *Extended* design mode of the PID Tuner.

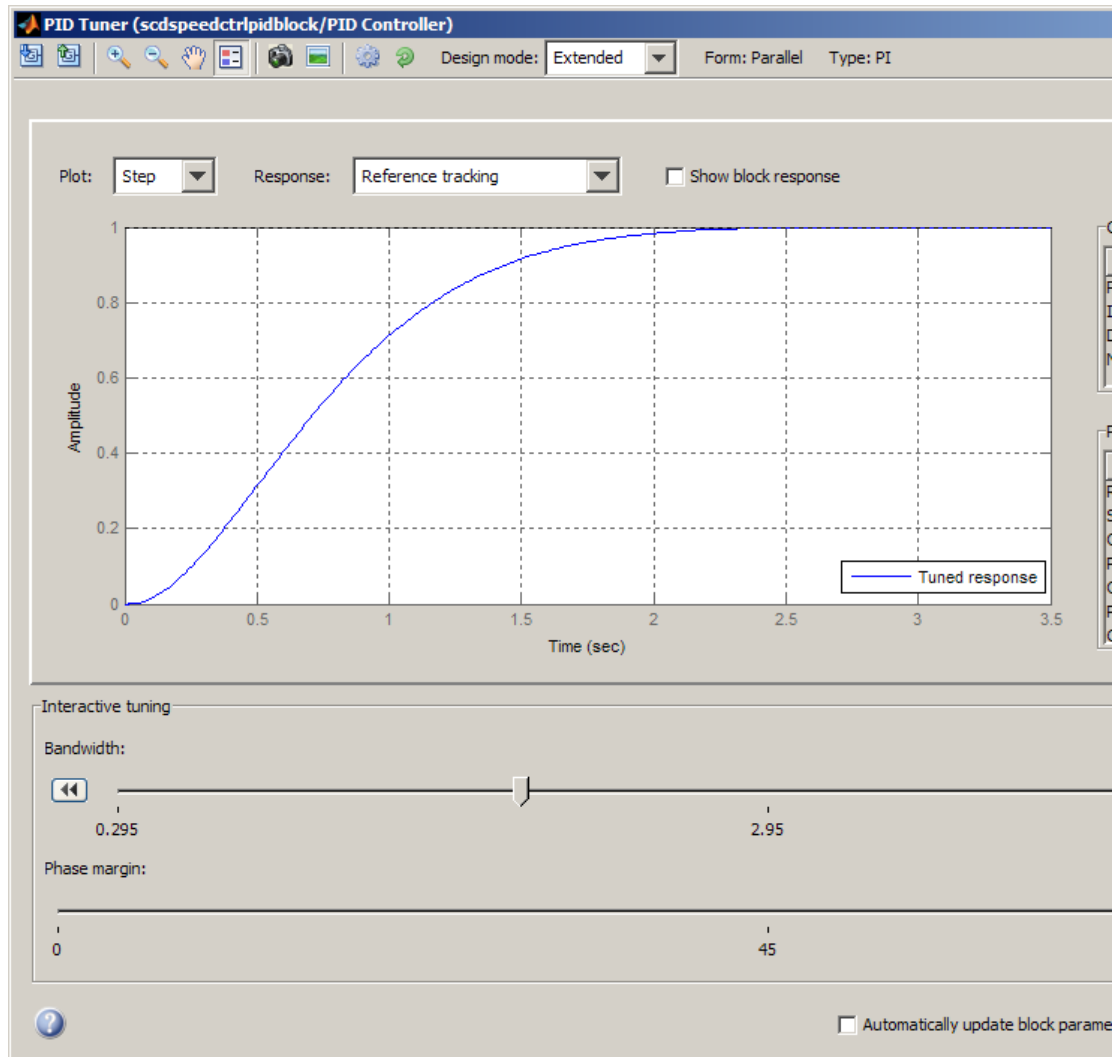
To switch to the *Extended* design mode, select *Extended* in the *Design Mode* dropdown menu in the toolbar. The following figure shows the PID Tuner in the *Extended* design mode with the integral only controller designed in the previous section:



There are two sliders in the *Extended* design mode. You can adjust performance with the *Bandwidth* slider. Large bandwidth results in fast response. You can also adjust robustness with the *Phase margin* slider. Large phase margin results in small overshoot. Move around both sliders to achieve the settling time of 2 seconds and zero overshoot. One way to achieve this is

- Bandwidth of 1.23 rad/sec
- Phase margin of 72 degree

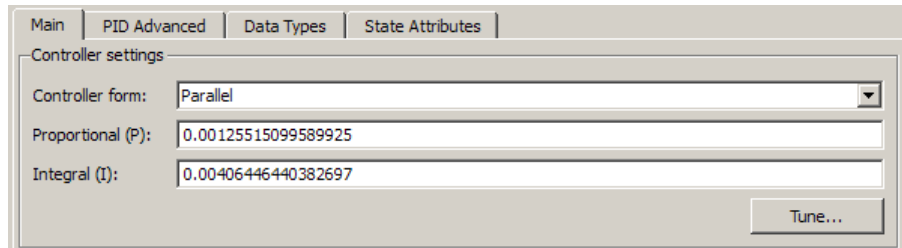
The following figure shows the PID Tuner with these settings:



Writing the Tuned Parameters to PID Controller Block

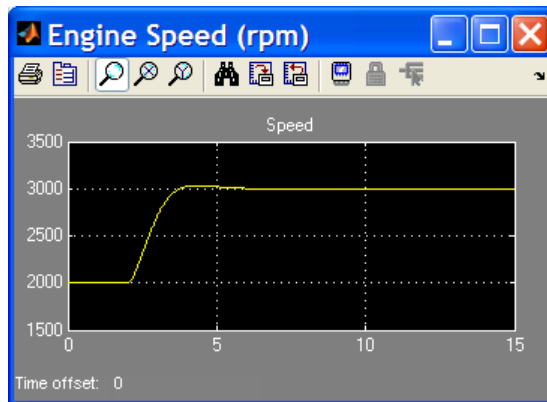
After you are happy with the controller performance on the linear plant model, you can test the design on the nonlinear model. To do this, click *Apply* in the PID Tuner. This action writes the parameters back to the PID Controller block in the Simulink model.

The following figure shows the updated PID Controller block dialog:



Completed Design

The following figure shows the response of the closed-loop system:



The response shows that the new controller meets all the design requirements.

You can also use the SISO Compensator Design Tool to design the PID Controller block. When the PID Controller block belongs to a multi-loop design task. See the demo "Single Loop Feedback/Prefilter Compensator Design".

```
bdclose('scdspeedctrlpidblock')
```

Designing a PID Controller Using Robust-Response-Time Tuning Algorithm and Bode Graphical Design

In this section...
“About This Tutorial” on page 4-14
“PID Control Design Using Robust-Response-Time Tuning Algorithm” on page 4-19
“PID Control Design Using Bode Graphical Tuning” on page 4-28
“Closed-Loop Simulation of Simulink Model” on page 4-32

About This Tutorial

- “Objectives” on page 4-14
- “About the Model” on page 4-14
- “Requirements for the Compensator Design” on page 4-18
- “Overview of the Compensator Design Process” on page 4-18

Objectives

In this tutorial, you learn how to use the Simulink Control Design GUI to design a PID controller for a single-loop feedback system that is operating at the operating conditions specified in the Simulink model. You accomplish the following tasks:

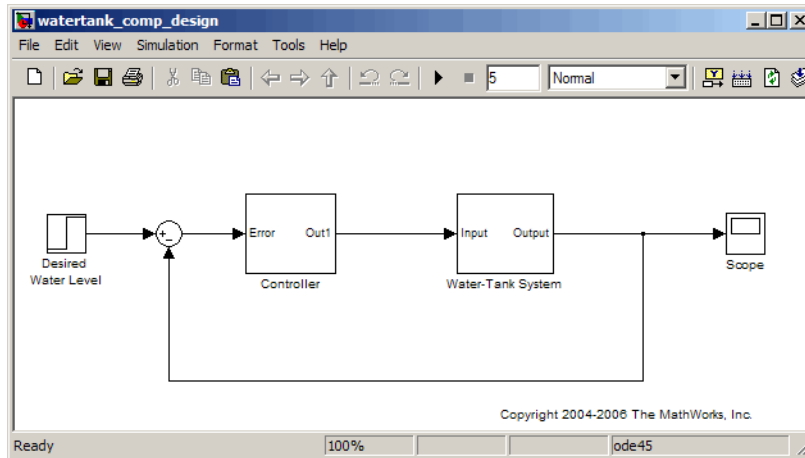
- Configure the model and GUI for compensator design.
- Design a PID compensator using the robust-response-time tuning algorithm and Bode graphical design.
- Simulate the closed-loop nonlinear model.

About the Model

- “watertank_comp_design Simulink Model” on page 4-15
- “Water-Tank Subsystem” on page 4-15

- “Controller Subsystem” on page 4-18

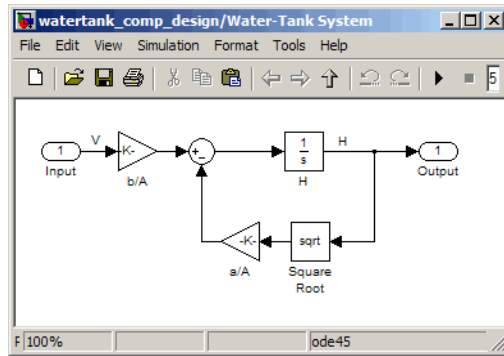
watertank_comp_design Simulink Model. The watertank_comp_design model, shown in the following figure, contains the Water-Tank System plant and a simple proportional-integral-derivative (PID) controller, called Controller, in a single-loop feedback system.



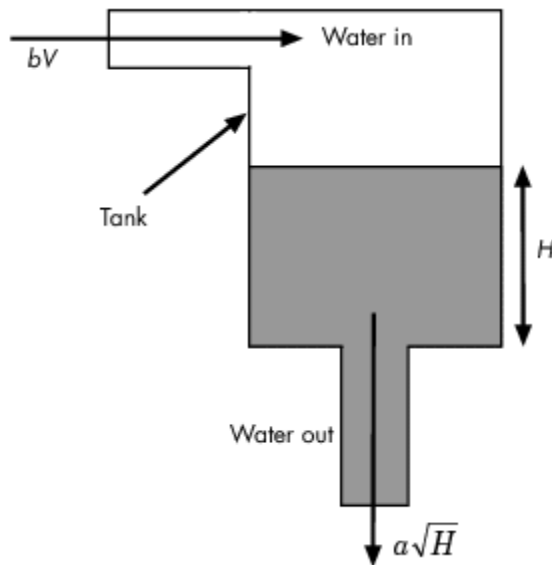
To view the Water-Tank System and the Controller, double-click the corresponding subsystem in the watertank_comp_design model. For descriptions of these subsystems, see the following topics:

- “Water-Tank Subsystem” on page 4-15
- “Controller Subsystem” on page 4-18

Water-Tank Subsystem. The Water-Tank subsystem of the watertank_comp_design model appears in the following figure.



This model represents the water-tank system depicted in the following figure.



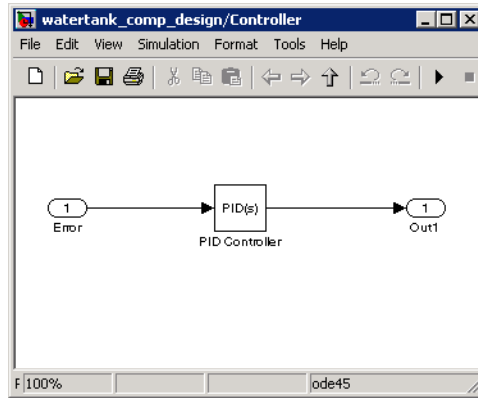
Water enters the tank from the top at a rate proportional to the voltage, V , applied to the pump. The water leaves through an opening in the tank base at a rate that is proportional to the square root of the water height, H , in the tank. The presence of the square root in the water flow rate results in a nonlinear plant.

The following table describes the variables, parameters, differential equations, states, inputs, and outputs of the water-tank system.

Variables	<p>H is the height of water in the tank.</p> <p>Vol is the volume of water in the tank.</p> <p>V is the voltage applied to the pump.</p>
Parameters	<p>A is the cross-sectional area of the tank.</p> <p>b is a constant related to the flow rate into the tank.</p> <p>a is a constant related to the flow rate out of the tank.</p>
Differential equation	$\frac{d}{dt} Vol = A \frac{dH}{dt} = bV - a\sqrt{H}$
States	H
Inputs	V

Outputs	H
---------	-----

Controller Subsystem. The Controller subsystem appears in the following figure.



This model contains a PID Controller block that controls the height of the water in the Water-Tank System.

Requirements for the Compensator Design

The PID controller you design in this tutorial must control the Water-Tank System response such that the:

- Overshoot is less than 5%.
- Rise time is less than 5 seconds.

Overview of the Compensator Design Process

The process for designing a compensator for the Water-Tank System in this tutorial includes the following tasks:

- Configuring the model and GUI for the design.
- Designing a PID compensator using the robust response time tuning algorithm.
- Tuning the compensator using the Bode design technique.

- Simulating the closed-loop Simulink model with the compensator design to analyze the system dynamics.

Simulink Control Design tools work only with linear plant models. Because the Water-Tank System is nonlinear, Simulink Control Design automatically linearizes the model about the model operating point, by default. The linearization provides a valid approximation of the nonlinear model in a region around the operating point. For more information about linearization and how the operating point impacts linearization results, see Chapter 3, “Linearization”.

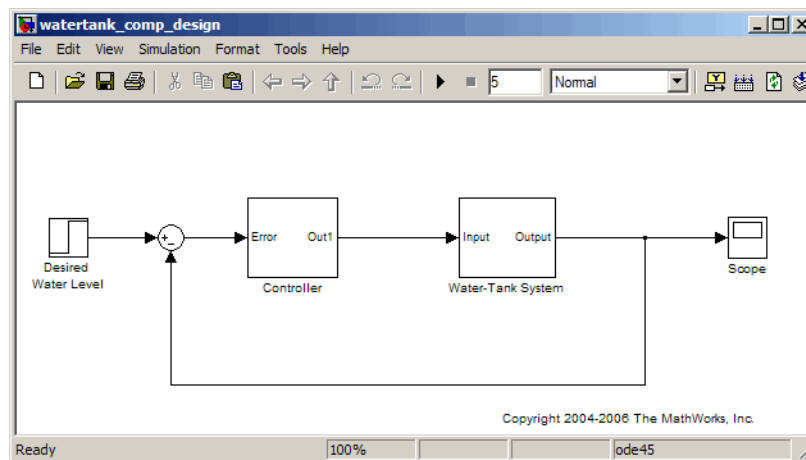
PID Control Design Using Robust-Response-Time Tuning Algorithm

In this portion of the tutorial, you design a compensator using the automated PID robust-response-time tuning algorithm. This tuning method tunes the PID gains to maximize bandwidth and optimize phase margin.

- 1 Open the `watertank_comp_design` model by typing the model name in the MATLAB Command Window:

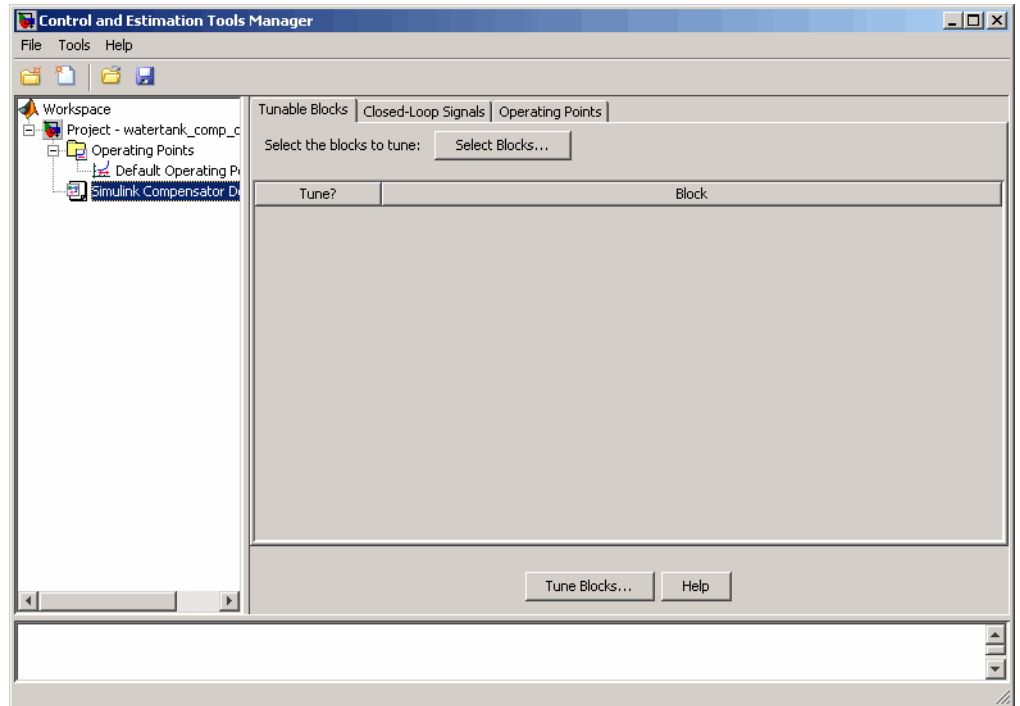
```
watertank_comp_design
```

The command opens the `watertank_comp_design` model in Simulink, as shown in the following figure.



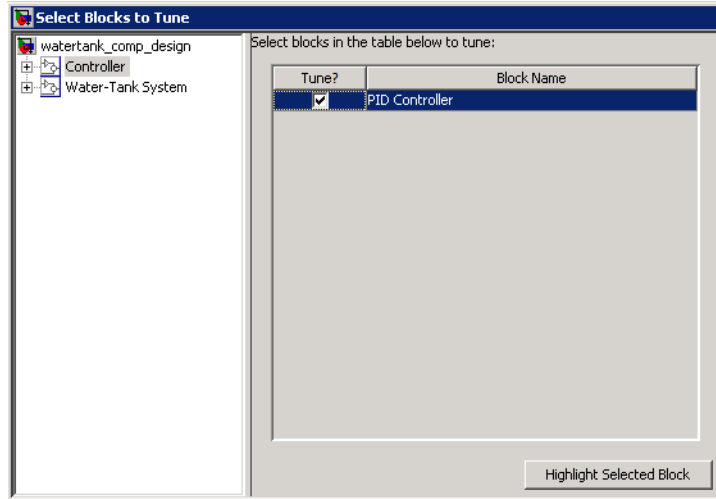
- 2 In the `watertank_comp_design` model window, select **Tools > Control Design > Compensator Design**.

This action opens the Control and Estimation Tools Manager with the **Simulink Compensator Design Task** node selected.



- 3 Select the PID Controller block as the block to tune.
 - a In the **Tunable Blocks** tab, click **Select Blocks**.

This action opens the Select Blocks to Tune window.
 - b In the `watertank_comp_design` tree, select the **Controller** subsystem.
 - c Select the **Tune?** check box for **PID Controller**.



d Click **OK**.

4 Define the closed-loop systems for which you want to analyze the response.

The input and output points of the closed-loop path are already defined in the `watertank_comp_design` model. If you needed to add or define them, you would use the following steps:

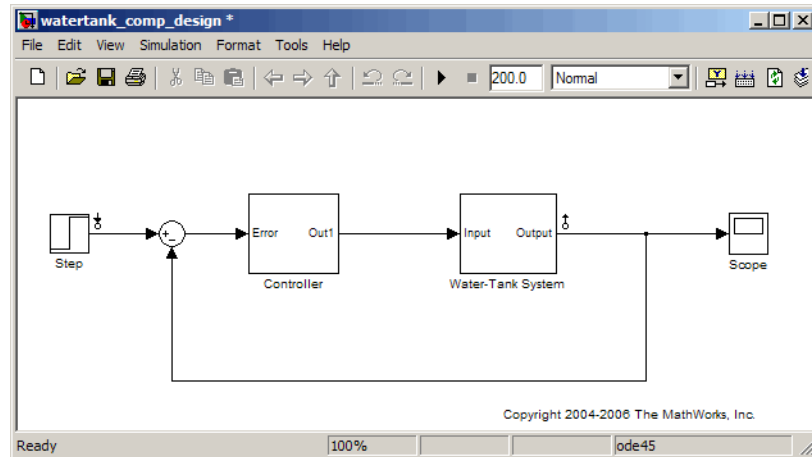
- a In the `watertank_comp_design` model, right-click the output of the Desired Water Level block, and select **Linearization Points > Input Point**.

This action displays the $\frac{1}{s}$ symbol on the signal line. This symbol indicates the input of the closed-loop path.

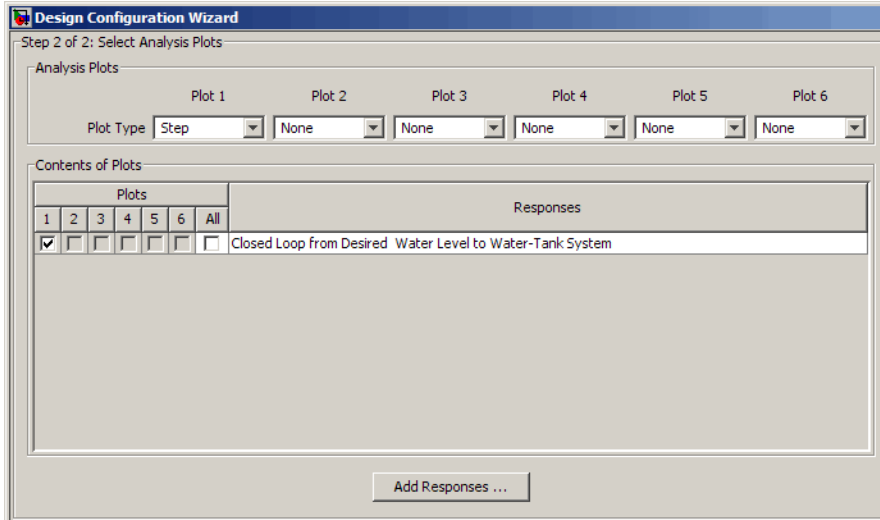
- b Right-click the output signal from the Water-Tank System, and select **Linearization Points > Output Point**.

This action displays the $\frac{s}{1}$ symbol on the signal line. This symbol indicates the output of the closed-loop path.

The Simulink model now resembles the following figure.



- 5 In the Control and Estimation Tools Manager, click **Tune Blocks** to open the Design Configuration Wizard. Click **Next**.
- 6 Step 1 of the Design Configuration Wizard prompts you to select the design plots you will use to tune the controller. Accept the default settings and click **Next**.
- 7 In Step 2 of the Design Configuration Wizard, specify the type of plot for analyzing the response.
 - a In the **Analysis Plots** area, select Step for the **Plot Type** corresponding to **Plot 1**.
 - b In the **Plots** section of the **Contents in Plots** pane, select **1** for **Closed Loop from Desired Water Level to Water-Tank System**.



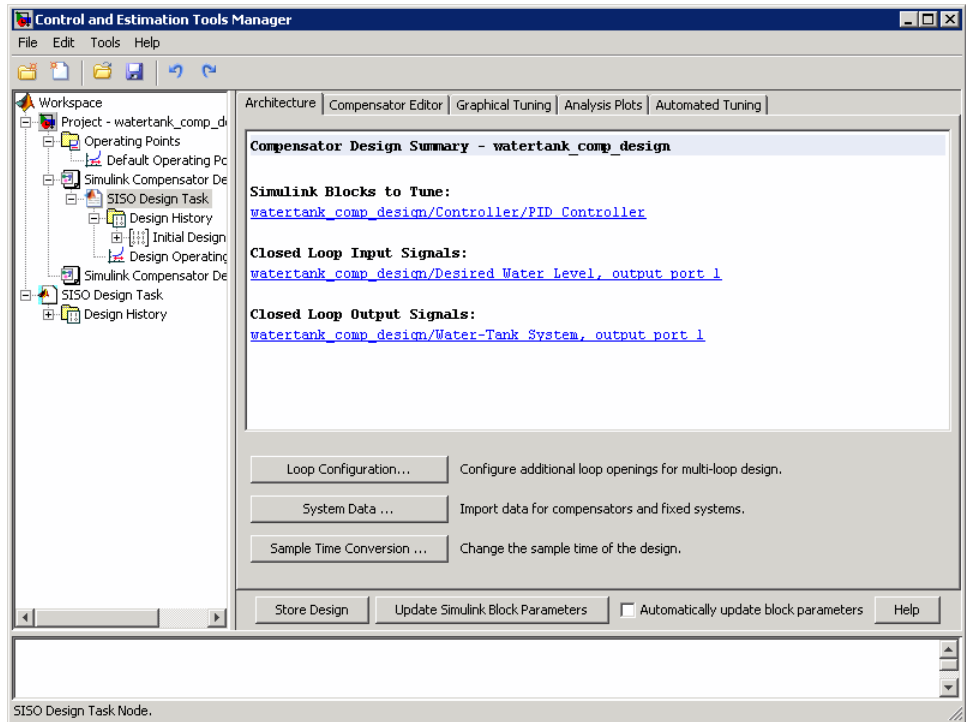
8 Click **Finish**.

The software performs the following actions:

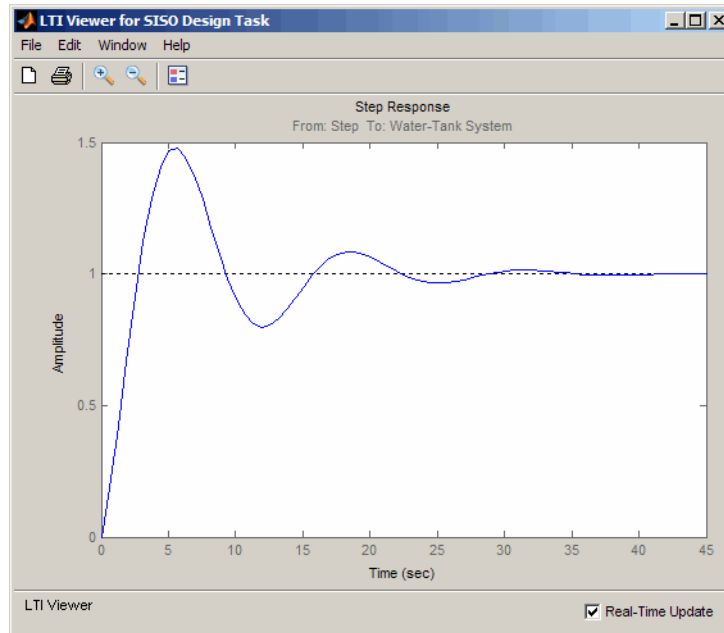
- Linearizes the Simulink model about the operating point specified in the model.
- Creates a **SISO Design Task** node under the **Simulink Compensator Design Task** node.
- Opens the following plot windows:
 - LTI Viewer for SISO Design Task window, which shows the closed-loop Step Response plot of the linearized model
 - SISO Design for SISO Design Task window, which is empty

You do not use in this window in this section of the tutorial. Keep this window open for the next section of the tutorial.

The Control and Estimation Tools manager resembles the following figure.



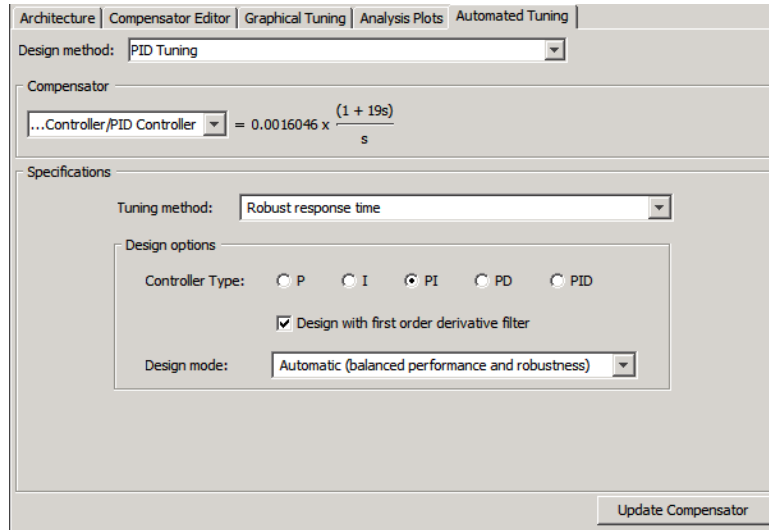
The Step Response plot shows an overshoot that does not meet the overshoot design requirement of less than 5%.



9 In the **Automated Tuning** tab of the **SISO Design Task** node in the Control and Estimation Tools Manager, select PID Tuning as the **Design method**.

10 In the **Specifications** area, select the following options:

- **Controller type:** PI
- **Tuning algorithm:** Robust response time



11 Click Update Compensator.

This action computes the PI values for the compensator using the robust response time tuning algorithm and updates the Step Response plot.

Tip You can view the PI values in the **Parameter** tab of the **Compensator Editor** tab in the **SISO Design Task** node.

12 Evaluate whether the compensator design meets the design requirements by analyzing the overshoot and the rise time, as follows:

a Right-click the Step Response plot and select the following options:

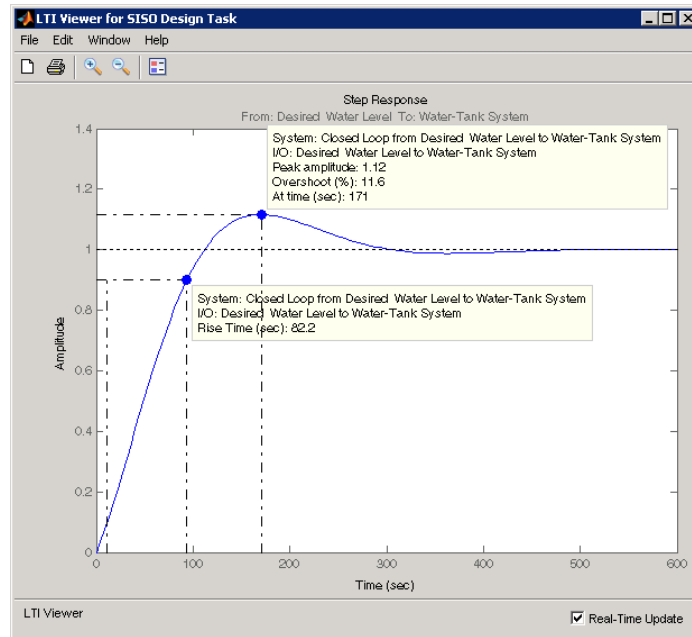
- **Characteristics > Peak Response**
- **Characteristics > Rise Time**

These actions add a plot marker to the plot for each characteristic, shown as blue dots.

b Left-click each blue dot to open the corresponding data marker.

The data markers show the following response characteristics:

- The overshoot is 11.6%.
- The rise time is 82.2 seconds.



This system response with the PID compensator exceeds the maximum allowed overshoot of 5%. The rise time is much slower than the required rise time of 5 seconds.

You decrease the rise time by increasing the gain of the compensator, as described in “PID Control Design Using Bode Graphical Tuning” on page 4-28.

Tip You can also decrease the rise time by adjusting the loop bandwidth. First, select **Interactive** (adjustable performance and robustness) from the **Design Mode** menu. Then, move the **Bandwidth** slider to the right. Finally, click **Update Compensator** to design a new compensator for the new target bandwidth.

PID Control Design Using Bode Graphical Tuning

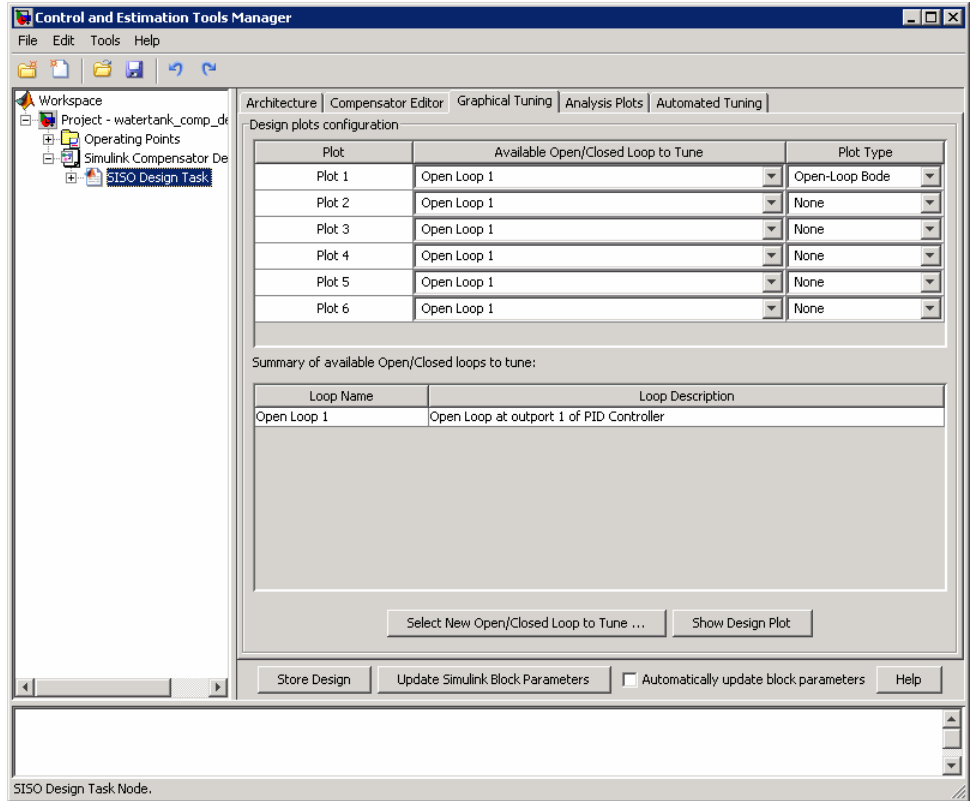
In this example, you decrease the rise time of the Water-Tank System response by increasing the compensator gain using Bode graphical tuning.

Bode graphical tuning lets you design a compensator by manipulating Bode diagrams of the open-loop response. This process is also called loop shaping.

You must have already designed an initial compensator using PID tuning, as described in “PID Control Design Using Robust-Response-Time Tuning Algorithm” on page 4-19.

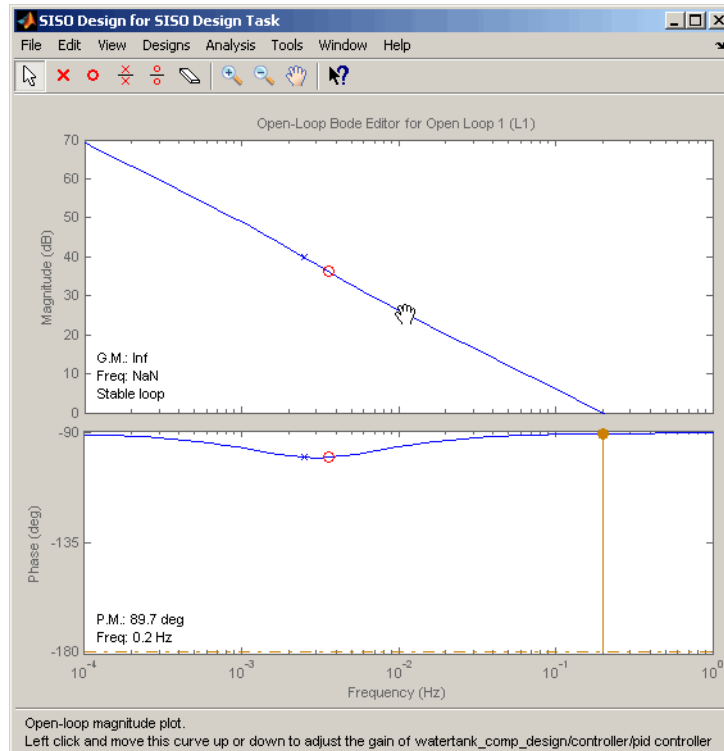
To design a compensator using Bode graphical tuning:

- 1** In the Control and Estimation Tools Manager, select the **Graphical Tuning** tab of the **SISO Design Task** node.
- 2** In the **Plot Type** cell that corresponds to **Plot 1**, select **Open-Loop Bode**.



This action creates an Open-Loop Bode plot in the SISO Design for SISO Design Task window. This plot shows a Bode plot of the linearized model with the compensator designed using automated PID tuning.

- 3 In the SISO Design window, drag the Bode Magnitude line upward to increase the gain. As you adjust the gain, view the affects on the closed-loop response in the Step Response plot.



By increasing the gain, you increase the bandwidth and speed up the response. One possible compensator design that meets the tutorial requirements has the following parameters:

- $P = 5.0368$
- $I = 0.11434$
- $D = 0$

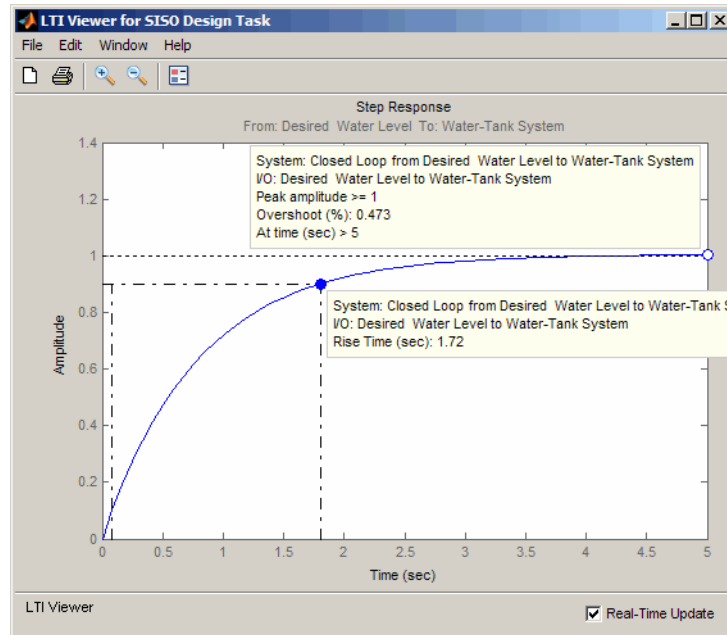
Tip You can view the parameter values corresponding to the gain adjustment you made in the Bode Magnitude plot in the **Compensator Editor** tab of the SISO Design Task. You can also adjust the parameter values in this tab.

- 4** Evaluate whether the compensator design meets the design requirements by analyzing the overshoot and the rise time, as follows:
 - a** Right-click the Step Response plot and select the following options, if you have not done so already:
 - **Characteristics > Peak Response**
 - **Characteristics > Rise Time**

These actions add a plot marker to the plot for each characteristic, shown as blue dots.
 - b** Left-click each blue dot to open the corresponding data marker.

The data markers show the following response characteristics:

 - The overshoot is 0.437%.
 - The rise time is 1.72 seconds.



This compensator design satisfies the design requirements of less than 5% overshoot and less than 5 second rise time.

Closed-Loop Simulation of Simulink Model

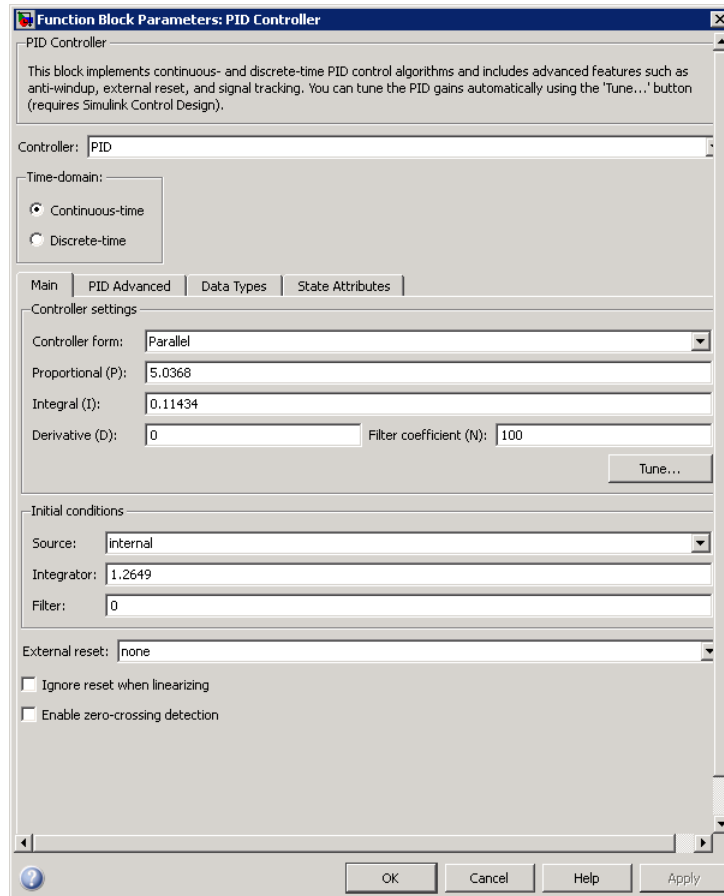
In this example, you simulate the nonlinear closed-loop Simulink model that includes a PID controller to determine how well the design meets the requirements.

You must have already designed the compensator, as described in “PID Control Design Using Bode Graphical Tuning” on page 4-28.



- 1 In the Control and Estimation Tools Manager **SISO Design Task** node, click **Update Simulink Block Parameters**.

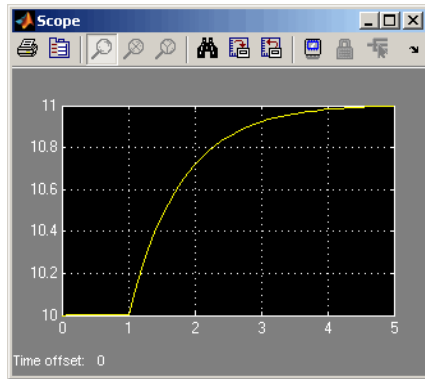
This action writes the compensator parameters into the PID Controller block of the Controller subsystem in the Simulink model.

Tip You can view the PID Controller block parameters in the Function Block Parameters Dialog box. To open this dialog box, double-click the PID Controller block.



2 In the Simulink model, double-click the Scope block to open the Scope block window.

3 In the Simulink model, click  to simulate the model. Then, click  to autoscale the axis.



This action updates the Scope window with the response of the nonlinear model with the compensator design. This simulation shows that the rise time is less than 5 seconds and there is minimal overshoot. Thus, this compensator design meets the requirements of less than 5% overshoot and less than 5 second rise time.

Examples

Use this list to find examples in the documentation.

Getting Started

Chapter 2, “Steady-State Operating Points”

“Open-Loop Response of Control System for Stability Margin Analysis”
on page 3-3

“Bode Response of Simulink Model” on page 3-7

Chapter 4, “PID Control Design”

Automated Tuning of Simulink PID Controller Block

“Automated Tuning of Simulink PID Controller Block” on page 4-2

