Department of Electrical Engineering

Delhi Technological University (Formerly Delhi College of Engineering)



CERTIFICATE

This is to certify that the project entitled, "INVESTIGATIONS ON HYBRID FUZZY PI CONTROLLERS FOR BLDC MACHINES", submitted by Ms. Renu Bhardwaj, University Roll No. 07/C&I/2010, student of Master of Technology (Control and Instrumentation) in Electrical Engineering department from Delhi Technological University (Formerly Delhi college of Engineering), is a dissertation work carried out by her under my guidance during session 2011-2012 towards the partial fulfillment of the requirements for the award of the degree of Master of Technology in Control & Instrumentation.

I wish her all the best in her endeavors.

Date: July 2012

Dr. VISHAL VERMA ASSOCIATE PROFESSOR, Electrical Engineering Department Delhi Technological University Shahbad daulatpur, Bawana road Delhi- 110042.

ACKNOWLEDGEMENT

This report in the present profile is a result of continuous enthusiasm and eternal effort putted, to make it of scholarly level. I would like to take this opportunity to show my gratitude towards various people from the university who had helped in the cause.

First of all I would like to thank my honorable guide Dr. VISHAL VERMA, Associate Professor, Department of Electrical Engineering, Delhi Technological University (formerly Delhi College of Engineering) for his constant guidance and persistent encouragement throughout the development of this project. It is a matter of immense pride for me to have worked under him, who has such a great zeal toward research and teaching. It in itself was a source of inspiration for me to complete the project with great enthusiasm, energy and determination. I would like to extent my special thanks to him for dedicating his valuable time whenever I needed to discuss the project work.

I would also like to thank Dr. NARENDRA KUMAR, Head of the Department, Electrical Engineering Department, Delhi Technological University (formerly Delhi College of Engineering) for being a visionary and supporting the concept of the project.

I am very thankful to all the faculty members of the department and Mr. Anil Butola (Lab assistant, Simulation Lab) for sharing their knowledge, to aid in the concern. Finally, I would like to thank my fellow student Amritesh Kumar, Girish Gowd and Shrinivas Amanchi for their support throughout the project work.

Date: July 2012 Renu Bhardwaj Roll no. 07/C&I/2010 M.tech (Control & instrumentation)

ABSTRACT

The permanent magnet brushless DC motor (PMBLDCM) is widely used in many industrial and domestic applications such as hybrid vehicles, consumer appliances, medical equipments, automation industries and robotics applications. With the advancement in the power electronics, integrated circuits, microcontrollers and embedded system a huge demand is created for application specific intelligent portable devices for control. The area of motor drives is also witnessing an increased attention focused especially on cost effective embedded intelligent control.

Hardware requirements for implementation of intelligent control strategy like fuzzy logic, neural network, neuro-fuzzy and genetic algorithm are stringent. Digital signal processors (DSP) or fast microcontroller are capable of fast computation and are generally being employed. Embedded system implementations using microcontroller and DSP or field programmable array (FPGA) or application specific integrated circuit (ASIC) presents a good alternative. These techniques have to be applied with limitations of low computing power and memory availability. So, a control code optimization with different measures is needed to be done for embedded system development.

The thesis deals with speed control of PMBLDC motor drive using various controllers to ascertain their relative performance with different applications. The conventional PI and non conventional fuzzy logic controller (FLC) are investigated primarily and later hybrid controller reaping the benefits of PI and FLC and avoiding the shortcoming of both is proposed in two configurations. Series hybrid in which FLC work as a precompensator for modifying reference speed and Parallel hybrid in which FLC tunes the gains of PI controller is presented for speed control of PMBLDC motor. After ascertaining the benefits of hybrid controller focus was done to reduce the size and computation requirements typically in terms of rules used in FLC. Reduced rule base hybrid controller is also developed and simulated both the configurations. The reduction in term of applicable size of the code and complexity is achieved. The modeling and simulation of these speed controllers is done on MATLAB/Simulink environment for PMBLDCM drive. The performance comparison is done based in terms of several performance measures under all operating conditions.

Certificatei
Acknowledgementii
Abstractiii
Table of Contentsiv
List of Figuresviii
List of Tablesxi
Chapter I: Introduction
1.1 General1
1.2 Drive system of PM Brushless DC motor2
1.2.1 Operational Principle of PMBLDC motor
1.2.2 The PMBLDC Drive
1.2.3 Advantage of PMBLDC motor over induction motor
1.3 Paradigm and theory of controllers
1.3.1 Conventional types of controllers
1.3.1.1 The 'P' controller
1.3.1.2 The 'PI' controller
1.3.1.3 The 'PD' controller
1.3.1.4 The 'PID' controller
1.3.2 Non-Conventional types of controllers
1.3.2.1 Fuzzy Logic controller
1.3.3 The hybrid controller11
1.3.3.1 The series hybrid PI (Fuzzy precompensated PI) controller
1.3.3.1 The parallel hybrid PI (Self tuning PI) controller
1.3.4 The reduced rule base hybrid controllers
1.4 Scope of the work14

Table of Contents

1.5 Thesis outline15
Chapter II: Literature survey
2.1 Introduction
2.2 Literature review
2.3 Conclusion
Chapter III: Modeling of controllers and drive for PMBLDC motor
3.1 General
3.2 System configuration21
3.2.1 Mathematical model of PMBLDCM
3.2.2 Hysteresis current controller
3.2.3 Reference current block
3.3 Speed controllers25
3.3.1 Classical PI controller
3.3.2 Fuzzy logic controller
3.3.3. Hybrid controllers
3.3.3.1 The series hybrid controller
3.3.3.2 The parallel hybrid controller
3.3.4 Reduced rule base hybrid controllers
3.3.4.1 Reduced rule base series hybrid PI controller
3.3.4.2 Reduced rule base parallel hybrid PI controller
3.4 Modeling using Simulink
3.4.1 Simulink model of the PMBLDC drive
3.4.2 Simulink model of speed controllers
3.5 Conclusion

Chapter IV: Results from simulation and discussion

4.1 General
4.2 Response of the drive with a PI speed controller
4.2.1 Response of the drive on starting and load perturbation
4.2.2 Response of the drive during speed direction reversal
4.3 Response of the drive with a fuzzy logic speed controller
4.3.1 Response of the drive on starting and load perturbation
4.3.2 Response of the drive during speed direction reversal
4.4 Response of the drive with a Series hybrid PI controller (Fuzzy precompensated
PI)55
4.4.1 Response of the drive on starting and load perturbation
4.4.2 Response of the drive during speed direction reversal
4.5 Response of the drive with a Parallel hybrid PI controller (Self tuning PI)57
4.5.1 Response of the drive on starting and load perturbation
4.5.2 Response of the drive during speed direction reversal
4.6 Response of the drive with a reduced rule base series hybrid PI controller
4.6.1 Response of the drive on starting and load perturbation
4.6.2 Response of the drive during speed direction reversal
4.7 Response of the drive with a reduced rule base parallel hybrid PI controller
4.7.1 Response of the drive on starting and load perturbation
4.7.2 Response of the drive during speed direction reversal
4.8 Discussion on results62
4.9 Conclusion

Chapter V: Main conclusion and suggestion for further work

Appendix	
References	71
5.3 Suggestion for further work	70
5.2 Main conclusion	68
5.1 General	68

LIST OF FIGURES

Fig. no.	Title of the figure	Page no.
1.1	The construction of Hall sensors embedded PMBLDC motor	2
1.2	Position feedback in grey code and energizing sequence of phase winding	3
1.3	Back emf, phase current and output power waveforms	3
1.4	Block diagram of PMBLDC drive	4
1.5	Block diagram of a fuzzy logic controller	9
3.1	Detailed block diagram of PMBLDCM drive	21
3.2	The equivalent circuit of the PMBLDC motor	23
3.3	The Block Diagram of PI controller	25
3.4	Membership functions for both the inputs for fuzzy logic controller	26
3.5	Membership function for output of fuzzy logic controller	27
3.6	Control surface of fuzzy logic controller	28
3.7	Block diagram series configuration of hybrid controller	30
3.8	Control surface of fuzzy precompensator	33
3.9	Block diagram of parallel hybrid controller	34
3.10	Membership function for error e(n) input for parallel hybrid	35
3.11	Membership function for change in error $\Delta e(n)$ input for parallel hybrid	35
3.12	Membership function of Proportional gain (K _p)	36
3.13	Membership function of Integral gain (K _I)	36
3.14	Control surface for proportional gain (K_P) for parallel hybrid	38

3.15	Control surface for Integral gain (K _I) for parallel hybrid	38
3.16	Membership function for inputs of FLC precompensator with reduced rule base	40
3.17	Membership function for output of FLC precompensator with reduced rule base	40
3.18	Control surface of fuzzy precompensator with reduced rule base	42
3.19	Membership function for error e(n) input	43
3.20	Membership function for change in error $\Delta e(n)$ input	43
3.21	Control surface for proportional gain (K _P) for reduced rule base parallel hybrid controller	45
3.22	Control surface for Integral gain (K _I) for reduced rule base parallel hybrid controller	46
3.23	Simulink model of the PMBLDCM drive	47
3.24	Simulink model for a PI controller	48
3.25	The Simulink block for the fuzzy logic controller	49
3.26	The Simulink block for the series hybrid PI controller	49
3.27	The Simulink block for the parallel hybrid PI controller	49
4.1	Response of the drive with the PI controller on starting and load perturbation	51
4.2	Response of the drive with the PI controller on reversal of speed direction	52
4.3	Response of the drive with the fuzzy logic controller on starting and load perturbation	53
4.4	Response of the drive with the fuzzy logic controller on reversal of speed direction	54
4.5	Response of the drive with the series hybrid PI controller on starting and load perturbation	55

- 4.6 Response of the drive with the series hybrid PI controller on reversal 56 of speed direction
- 4.7 Response of the drive with the Parallel hybrid PI controller on 57 starting and load perturbation
- 4.8 Response of the drive with the Parallel hybrid PI controller on 58 reversal of speed direction
- 4.9 Response of the drive with the reduced rule base series hybrid PI 59 controller on starting and load perturbation
- 4.10 Response of the drive with the reduced rule base series hybrid PI 60 controller on reversal of speed direction
- 4.11 Response of the drive with the reduced rule base Parallel hybrid PI 61 controller on starting and load perturbation
- 4.12 Response of the drive with the reduced rule base Parallel hybrid PI 62 controller on reversal of speed direction
- 4.13 Response of drive on starting and load perturbation for all the 63 controllers at 1000RPM
- 4.14 Response of drive on starting and load perturbation for the PI, FLC, 63 reduced rule base series hybrid and parallel hybrid controller at 1000RPM

LIST OF TABLES

Table no.	Title of the table	Page no.
1.1	Comparison between PMBLDC motor and induction motor	5
3.1	Reference current input and output logic	24
3.2	Rule Base of fuzzy logic controller	27
3.3	Rule table for fuzzy precompensator	32
3.4	Rule Base of proportional gain (K_p) for parallel hybrid controller	37
3.5	Rule Base of integral gain (K_I) for parallel hybrid controller	37
3.6	Rule table of fuzzy precompensator for reduced rule base series hybrid	41
3.7	Rule Base of proportional gain (K _p)	44
3.8	Rule table of integral gain (K _I)	44
4.1	Comparison of response at starting	64
4.2	Comparison of response on load perturbation	65
4.3	Comparison of controller based on computational and memory requirement	66