

July 2013

IMPLEMENTATION OF MODEL PREDICTIVE CONTROL AND AUTO TUNING BASED PID FOR EFFECTIVE TEMPERATURE CONTROL IN CSTR

CHENIMINENI KISHORE

Electronics and Control Engineering, Sree Vidyanikethan Engineering College, Tirupathi, India,
Kishore.chenimineni@gmail.com


T. VANDHANA

Electronics and Control Engineering, Sree Vidyanikethan Engineering College, Tirupathi, India,
Tvandhana188@gmail.com

SHEEREEN HUSSAIN

Electronics and Control Engineering, Sree Vidyanikethan Engineering College, Tirupathi, India,
Sheereenhussain44@gmail.com

For this and additional works at: <https://www.interscience.in/gret>

 **S. SRINIVASULU** *Part of the Aerospace Engineering Commons, Business Commons, Computational Engineering Commons, Electrical and Computer Engineering Commons, Industrial Technology Commons, Mechanical Engineering Commons, and the Physical Sciences and Mathematics Commons*
Part of the Aerospace Engineering Commons, Business Commons, Computational Engineering Commons, Electrical and Computer Engineering Commons, Industrial Technology Commons, Mechanical Engineering Commons, and the Physical Sciences and Mathematics Commons
srinu85raju@gmail.com

Recommended Citation

KISHORE, CHENIMINENI; VANDHANA, T.; HUSSAIN, SHEEREEN; and RAJU, S. SRINIVASULU (2013) "IMPLEMENTATION OF MODEL PREDICTIVE CONTROL AND AUTO TUNING BASED PID FOR EFFECTIVE TEMPERATURE CONTROL IN CSTR," *Graduate Research in Engineering and Technology (GRET)*: Vol. 1 : Iss. 1 , Article 19.

DOI: 10.47893/GRET.2013.1018

Available at: <https://www.interscience.in/gret/vol1/iss1/19>

This Article is brought to you for free and open access by the Interscience Journals at Interscience Research Network. It has been accepted for inclusion in Graduate Research in Engineering and Technology (GRET) by an authorized editor of Interscience Research Network. For more information, please contact sritampatnaik@gmail.com.

IMPLEMENTATION OF MODEL PREDICTIVE CONTROL AND AUTO TUNING BASED PID FOR EFFECTIVE TEMPERATURE CONTROL IN CSTR

CHENIMINENI KISHORE¹, T.VANDHANA², SHEEREEN HUSSAIN³ & S.SRINIVASULU RAJU⁴

^{1,2,3&4}Electronics and Control Engineering, Sree Vidyanyikethan Engineering College, Tirupathi, India
Kishore.chenimineni@gmail.com, Tvandhana188@gmail.com, Sheereenhussain44@gmail.com
& Srinu85raju@gmail.com

Abstract- Continuous Stirrer Tank Reactor (CSTR) is an important topic in process control and offering a diverse range of researches in the area of chemical and control engineering. A simulation on mathematical model has several advantages over the experiment on a real model or system, which is used for steady state analysis and dynamic state analysis. The main objective is to control the temperature of CSTR in the presence of disturbance. Various control approaches have been applied on CSTR to control its parameters through PID control and MODEL PREDICTIVE CONTROL (MPC). Model design and simulation are done in MATLAB SIMULINK.

Keywords- CSTR, Model response, Relay feedback, PID control, Model predictive control (MPC)

I. INTRODUCTION

The problem of controlling the temperature of CSTR is considered as a challenging issue especially for a control engineer corresponding to its non linear dynamics. Most of the traditional controllers are restricted just for linear time invariant system application. But in real world, the non linear characteristics of system and their function parameter changes due to wear and tear, that's why these changes can't be neglected. One of the most important controllers both in academic and industrial application is PID. PID controller has been applied in feedback loop mechanism and extensively used in industrial process control since 1950's. Easy implementation of PID controller made it more popular in Control System application. Basically PID tries to correct the error between measured outputs and desired outputs of the process in order to improve the transient and steady state response as much as possible.

Model Predictive Control is the only advanced control technique, which has been very successful in particular applications. MPC refers to a class of computer controlled algorithms that utilize and explicit process model to predict the future response of the plant. At each control interval, an MPC algorithm attempts to optimize future plant behavior by computing a sequence of future manipulated variable adjustments. The first input in the optimal sequence is then sent into the plant and entire calculation is repeated at subsequent control intervals.

The most important advantage of MPC algorithms is the fact that they have the unique ability to take into account constraints imposed on process inputs (manipulated variables) and outputs (controlled

variables) or state variables which usually determine the quality, economic efficiency and safety of production. MPC techniques have been recognized as efficient approaches to improve operating efficiency and profitability. It has become the accepted standard for complex controlled problems in the process control. This paper, CSTR has been used for the production of Propylene Glycol by Hydrolysis of Propylene Oxide with Sulphuric acid as catalyst. Water is supplied in excess, so reaction is of first order.

A proportional-integral-derivative controller (PID Controller) [4] is a common feedback loop component used for control system. In this paper a PID controller is implemented to track the set point and also to reject the disturbance occurs in the process. Relay feedback test is conducted to carry out the tuning parameters of PID controller to satisfy the servo and regulatory responses.

II. MODELLING OF CSTR

The examined reactor has real background and graphical diagram of the CSTR reactor as shown in fig I. The mathematical model of this reactor comes from balances inside the reactor. Notice that a jacket surrounding the reactor also has feed and exit streams. The jacket is assumed to be perfectly mixed at lower temperature than the reactor. Energy passes through the reactor walls into jacket removing the heat generated by reaction. .

The control objective is to keep the temperature of the reacting mixture T, constant at desired value. The only manipulated variable is the coolant flow rate.

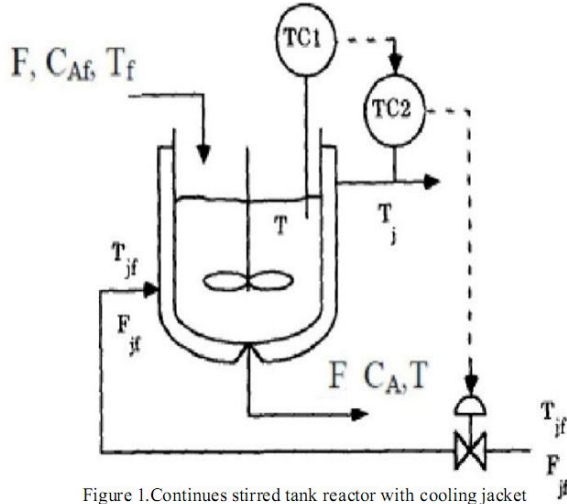


Figure 1. Continues stirred tank reactor with cooling jacket

TABLE I. VALUES FOR REACTOR PARAMETERS

Parameter	Values	Unit
Ea	32.400	Btu/lbmol
Ko	16.96*10 ¹²	Hr ⁻¹
U	75	Btu/hrft ² °F
Pc _p	53.25	Btu/ft ³ °F
R	1.987	Btu/lbmol °F
F	340	ft ³ /hr
V	8.5	ft ³
V _j /V	0.25	-
T _{jf}	0	°F
P _j c _{pj}	55.6	Btu/ft ³ °F
Ca _f	0.132	Lbmol/ft ³
T _f	60	°F

1. Steady State Solution

The steady state solution is obtained when

$$\frac{dCA}{dt} = 0, \frac{dT}{dt} = 0, \frac{dT_j}{dt} = 0$$

That is

$$\begin{aligned} f_1(C_A, T, T_j) &= \frac{dC_A}{dt} = 0 \\ &= F/V(C_{Af} - C_A) - K_0 \exp(-E/RT)C_A \end{aligned}$$

$$\begin{aligned} f_2(C_A, T, T_j) &= \frac{dT}{dt} = 0 \\ &= F/V(T_f - T) + (-\Delta H/\rho C_p)K_0 \exp(-E/RT)C_A \\ &\quad - UA/V\rho C_p(T - T_j) \end{aligned}$$

$$\begin{aligned} f_3(C_A, T, T_j) &= \frac{dT_j}{dt} = 0 \\ &= F_j/V_j(T_{jf} - T_j) + UA(T - T_j)/(V_j \rho_j c_{pj}) \end{aligned} \quad (1)$$

2. Linearization

The goal of the linearization procedure is to find a model with the form

$$\dot{X} = Ax + Bu \quad (2)$$

$$y = Cx + Du \quad (3)$$

Where the states, inputs and output are in deviation variable. Using the parameters given in above table we can find the State space model for PID controller design

$$A = \begin{bmatrix} -7.9909 & -0.013674 \\ 2922.9 & 4.5564 \end{bmatrix}$$

$$B = \begin{bmatrix} 0 \\ 1.4582 \end{bmatrix}$$

$$C = [0 \quad 1]$$

$$D = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

Hence transfer function for PID control will be (T/T_j)

$$G_P = \frac{1.458s + 11.65}{s^2 + 3.434s + 3.557} \quad (4)$$

III. CONTROLLER METHODS

A. PID Controllers

When the characteristics of a plant are not suitable, they can be changed by adding a compensator in the control system. One of the simple and useful compensators feedback control design is described in this section. In this paper, the control method is designed based on the time-dimension performance specifications of the system, such as settling time, rise time, peak overshoot, and steady state error and so on.

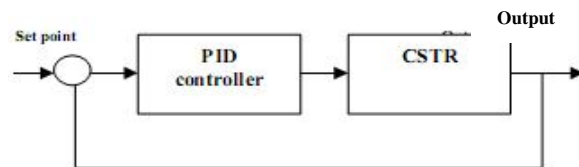


Figure 2 : Block diagram of a closed loop system

A PID controller calculates an "error" value as the difference between a measured process variable and a desired set point. The controller attempts to minimize the error by adjusting the process control inputs.

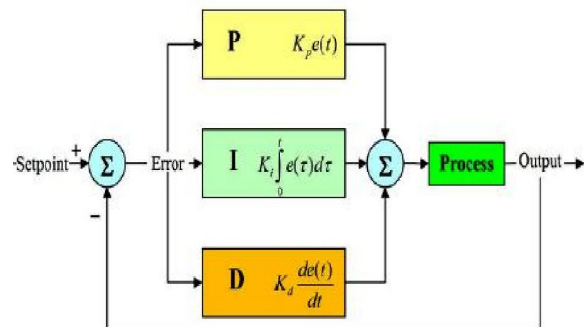


Figure 3 Block diagram of PID controller

Three parameters K_d , K_p and K_i must be adjusted in the PID controller. In guaranteeing stability, performance and shaping the closed-loop response, it is important to select a suitable compensator.

$$K_u = \frac{4\tau_i}{\pi\omega_c} \tag{5}$$

$$W_u = \frac{2\pi}{P_u} \tag{6}$$

I. *PROPORTIONAL GAIN K_p :*

Large proportional control can increase response, speed and reduce the steady state error, but will lead to oscillation of the system.

II. *INTEGRAL GAIN K_i :*

Integral control is favourable for diminishing the steady state error but it will lengthen the transient response. This paper attempts to design optimal values for controller parameters. Then it obtain the value of PID gains by Ziegler and Nichols Method. Ziegler and Nichols provided a technique for selecting the PID gains that works for a large class of industrial systems.

III. *RELAY FEEDBACK TEST:*

The Astrom and Hagglund relay feedback test is based on the Observation that, when the output lags behind the input by π radians, the closed loop system can oscillate with a period of P_u . The block diagram of Relay feedback test is shown in Fig.4. The output response of relay feedback test is shown in Fig.5. From the response we can find the parameters are ultimate gain and ultimate period by using equations 4 & 5.

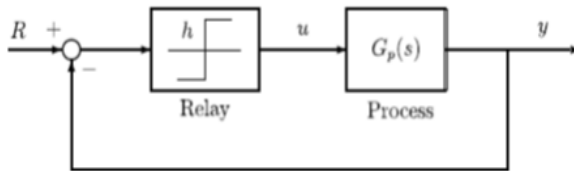


Figure. 4 Block diagram of Relay feedback test.

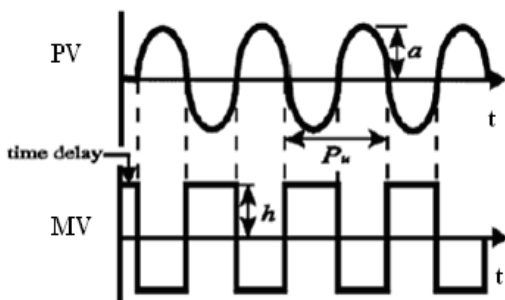


Figure. 5: Output response of relay feedback test.

A Relay of magnitude h is inserted in the feedback loop. Initially, the input $u(t)$ is increased by h . Once the output $y(t)$ starts increasing after a time delay (D), the relay switches to the opposite direction, $u(t)-h$. Because there is a phase lag of $-\pi$, a limit cycle of amplitude a is generated, as shown in fig 5. The period of the limit cycle is the ultimate period, P_u . The approximate ultimate gain, K_u , and the ultimate frequency, w_u are

IV. *MODEL PREDICTIVE CONTROLLER*

The Model Predictive Control problem is formulated as solving on-line a finite horizon open loop optimal control problem subject to system dynamics and constraints involving states and controls. Fig (6) shows the basic principle of model predictive control. Based on measurements obtained at time t , the controller predicts the future dynamic behavior of the system over a prediction horizon T_p and determines (over a control horizon) the input such that a predetermined open-loop performance object function is optimized.

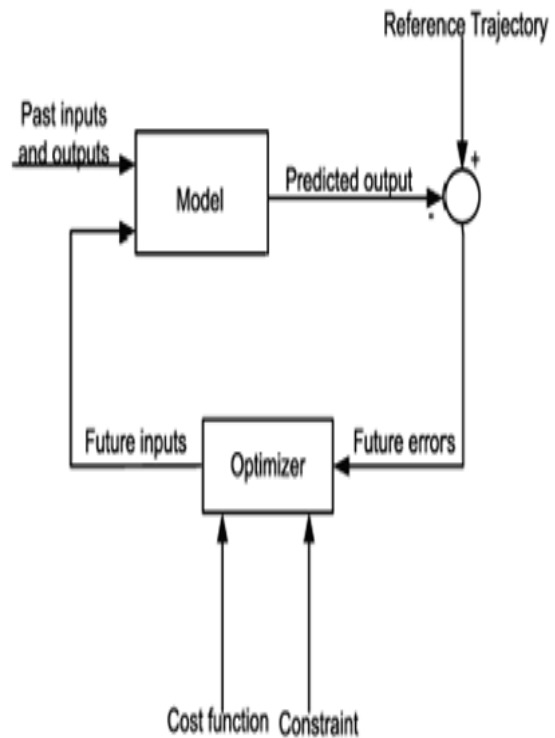


Figure6: Block diagram of MPC controller.

IV. *OPTIMIZATION FUNCTION:*

A mathematical description of the cost function used by the controller to optimize control moves over the control horizon is given, values of set points, measured disturbances, and constraints are specified over a finite horizon of future sampling instants, $k+1, k+2, \dots, k+P$, Where P is the prediction horizon and the controller computes M moves $u_k, u_{k+1}, \dots, u_{k+M-1}$, where M is the control horizon as shown in Fig.7. For conical tank system, consider the predictive horizon $P=20$ and control horizon $M=3$, to track the servo and regulatory response under multi set point tracking system. The cost function / optimization equation to reduce the error is shown below.

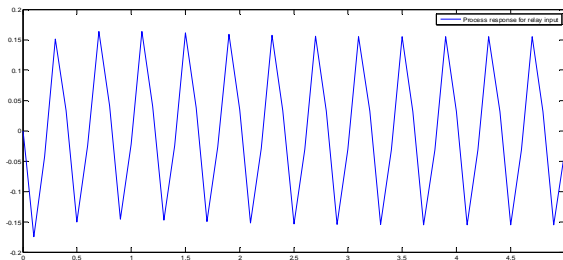


Figure 11: Process response for relay feedback test.

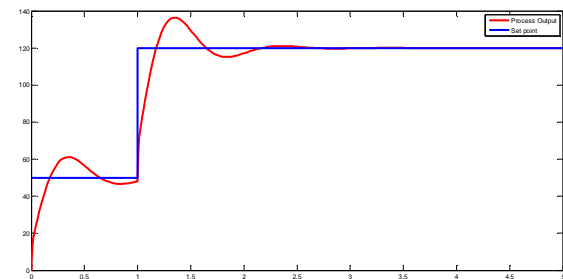


Figure 12: Servo response for Temperature control of CSTR process.

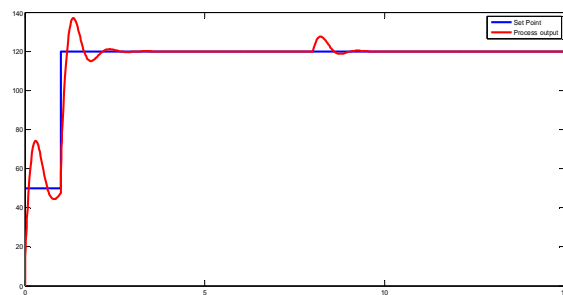


Figure 13: Servo response and regulatory response for Temperature control of CSTR Process.

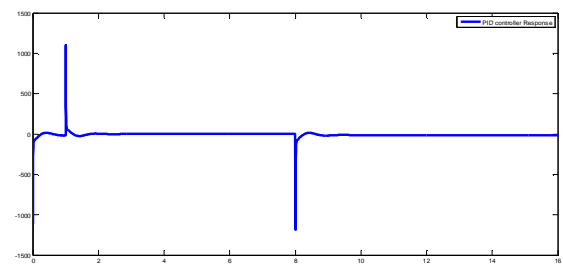


Figure 14: PID controller response for CSTR for servo and regulatory response.

C. MODEL PREDICTIVE CONTROLLER:

The implementation of Model predictive control for temperature control of CSTR process is implemented in Matlab. The MPC is implemented by considering the parameters of Prediction Horizon ($P = 20$), Control Horizon ($M = 2$), Control interval= 0.1 and objective function is Quadratic Objective to minimise the error, to track the multi changes in set point and also the change in load disturbance. The multi set point tracking of temperature of CSTR process by using MPC controller is shown in fig-15. From fig 15 we can observe that no oscillations occurred in the process and also it takes less time to track the changes occur in the input of the CSTR process.

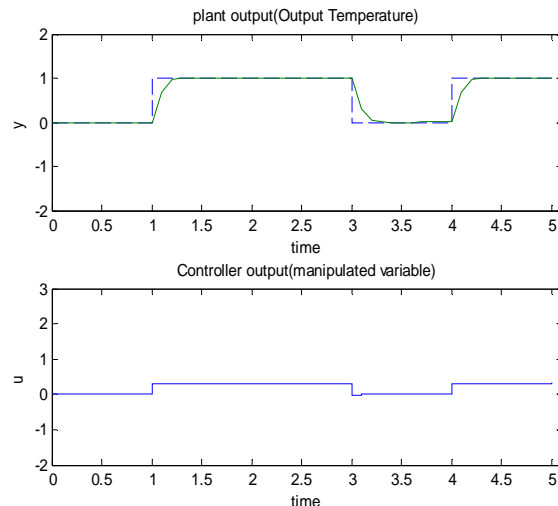


Figure 15: Multi set point tracking using MPC for CSTR.

VI. CONCLUSION:

The CSTR process is identified as a non-linear system. The modeling of CSTR process is implemented with the help of first principle differential equation. MATLAB (Simulink) is used to solve the differential equation. The conventional PID controller is implemented based on the auto tuning method by conducting the Relay Feedback test to track the set point changes in temperature of CSTR process. The relay feedback test conducted to the process to identify the tuning parameters of PID structure. The MPC Controller is implemented to track the servo response and regulatory response. The simulation results proven that the MPC control method is an easy-tuning and more effective way to enhance stability of time domain performance of the temperature control of CSTR process.

VII. FUTURE WORK

The Controlling of CSTR process be implemented by using constraints on Model Predictive Control to track the servo response and regulatory response. The performance comparison will also be carried out by using qualitative and Quantitative analysis. The adaptive Controllers like Self tuning regulator, Model Reference Adaptive Controller etc can be implemented for temperature control of CSTR process for satisfactory desired performance .

REFERENCES

- [1] Balakotiah, V. and D. Luss "Analysis of The Multiplicity Patterns of a CSTR," Chem. Eng. Comm. Vol 13, pp 111-113, 1981.
- [2] Liptk, B.G., "Controlling and Optimizing Chemical Reactors," Chemical Engineering Magazine, pp. 69-8, 1986.
- [3] J.G.Ziegler and N.B.Nichols, Rochester.N.Y, "Optimum Settings for Automatic Controllers," Trans.ASME, 64, 1942, pp.759-765..

- [4] Fried land B. "Advanced Control System Design", Prentice Hall, New Jersey, 1996
- [5] Jiri Vojtesek and Petr Dostal, "Simulation analysis Of CSTR" Tomas Bata University in Zlin, pp.22-45, 1992.
- [6] Åström, K.J., Hägglund, T., "PID Control – Theory, Design and Tuning," Instrument Society of America, Research Triangle Park, NC, 2nd ed., 1995
- [7] Fried land B., "Advanced Control System Design," Prentice Hall, New Jersey, 1996.
- [8] Isidori, A, "Nonlinear control systems". New York, Springer Verlag, pp.12-56, 1995.
- [9] Aidan o'Dwyer, "Hand book of PI and PID controller tuning rules", 3rd edition page no.78.
- [10] V.R.Ravi, T.Thyagarajan, "Application of adaptive control technique to interacting Non Linear Systems", IEEE 2011 pp 386-392.
- [11] Clarke, D.W. "Application of Generalized Predictive Control to Industrial Processes," IEEE Cont. Sys. Mag., 49-55, April (1988).
- [12] SukanyaR.warier, Sivanandamvenkatesh "Design of controller based on MPC for a conical tank system", (ICAESM-2012).

