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Design Of Fuzzy – Pid Controller For Continuous Stirred Tank Reactor Plant

Dr. K. Prabhu, P. Dharani, Dr. S. Vijayachitra, C. Kavya

1 Department of EIEKongu Engineering College Erode, India.prabhu.eie@kongu.edu
2 Department of EIEKongu Engineering College Erode, India.dharaniukl@gmail.com
3 Department of EIEKongu Engineering College Erode, India.dr.svijayachitra@gmail.com
4 Department of EIE Kongu Engineering College Erode, India. kavyasekar17@gmail.com

Abstract—

The industrial continuous stirred tank reactor (CSTR) exhibits nonlinear and time-varying behavior. The control valve wears and maintains its service life. These problems must be solved by designing an optimized controller. The role of an intelligent controller with working parameters is very important. The focus of the current project is some possible effective methods to control the parameters of the CSTR and meet the required specifications and achieve stability. Comparative analysis is to use PID controller and fuzzy controller from CSTR for temperature control. Compared with PID, fuzzy provides better transient response. Time domain parameters have been improved. Therefore, compared with the traditional PID controller, the performance of CSTR in fuzzy control has been improved. The main goal is to use hybrid technology to obtain the optimal value of PID parameters, and to obtain the dynamic behavior of the process and analyze its time domain parameters. Various control techniques are used to study the performance of nonlinear CSTR systems. Various control techniques are used to study the performance of nonlinear CSTR systems. Keep the temperature (T) of the reaction mixture constant.

Keywords—PID controller, Modified PID controller, Fuzzy logic controller, CSTR.

I. INTRODUCTION

A Continuous Stirred Tank Reactor (CSTR) could be a response vessel in which reagents, reactants, and regularly solvents stream into the reactor whereas the items of the response concurrently exits the vessel. In this way, the tank reactor is considered to be a important device for ceaseless chemical handling. Continuous stirred-tank reactors (CSTRs) are open frameworks, where fabric is free to enter or exit the framework, that work on a steady-state premise, where the conditions within the reactor do not alter with time. Reactants are persistently presented into the reactor, while products are ceaselessly evacuated. In chemical building the title CSTR is regularly utilized to allude to an idealized disturbed tank reactor utilized to show operation factors required to accomplish a indicated yield. The Persistent Stirred-Tank Reactor (CSTR), may be a common culminate reactor sort in chemical designing. The dynamic behaviour of a CSTR can be portrayed by mass, component and energy balance equations [1].

The numerical show of this particular CSTR is delineated by the set of two nonlinear Ordinary Differential Conditions which are built with the utilize of fabric and warm equalizations. In making strides the execution of the CSTR, an fitting controller is required. A basic period in arranging a control methodology is suitable modelling of the framework to controlled. An correct framework appear ought to provide yield reactions comparative to the real framework [12-13]. The complexity of most physical frameworks, in any case, meets any challenges in making the precise models. In case the show and parameters are obscure, fitting strategies can be associated to overcome those confinements[2]. For the foremost portion, standard PID calculations with settled parameters may perform incapably when the strategy choose up changes significantly with working conditions caused due to the non-linearity of the CSTR. In this case, distinctive sets of controller parameters have to be utilized for particular working conditions, or, something else nonlinear control such as self-tuning control ought to be utilized. [4]. As of late the fuzzy logic control has been successfully investigated and utilized,like the fuzzy PID controller, which combines the advantages of conventional and fuzzy auto-tuning direct fuzzy control to control force and cross-regulation of fuzzy and PID. The formatter must create these components and adhere to the following applicable standards [11].

II. PROBLEM FORMULATION

The industrial continuous stirred tank reactor (CSTR) exhibits a non-linear and time-varying behavior of the control valve wears and maintains its service life. These problems must be solved by designing an optimized controller. The role of an intelligent controller with working parameters is very important. The focus of the current project is some possible effective methods to control CSTR parameters and meet the required specifications and achieve stability.

III. OBSERVATIONS

Maintain the temperature by tuning the various controllers.

PID: The system with PID Controller is reached set point with more overshoot and oscillations. Hence PID controller does not efficiently control the temperature of the plant.

Fuzzy tuned PID: Comparative investigation is made with PID controller and fuzzy controller of CSTR for the control of temperature. Fuzzy provides better transient response characteristics compared with PID[10]. The time domain parameters are improved. Hence the performance of the CSTR was improved in Fuzzy control when compared with the conventional PID controller[5][9].

MPC – PID: The MPC controller incorporates a way better reaction in terms of minimizing overshoot and following the temperature required by the system. Even in the event of a failure, a CSTR with an MPC controller provides better response behaviour than a CSTR with a PID controller. Compared with traditional control technology, is the optimal value of the controller parameters generated[4].

IV. OBJECTIVES

Utilize different control procedures to consider the execution of nonlinear CSTR frameworks. To Keep the temperature (T) of the response blend steady at the specified esteem. Utilize different procedures to get ideal values of PID parameters, obtain energetic exhibitions of the method and explore its time domain parameters.

V. PERFORMANCE ANALYSIS

A. PID CONTROLLER

The only controller is PID sort, which is broadly utilized in industry since of its basic structure and moo fetched. PID implies Proportional-Integral-Derivative, which alludes to the three things that act on the blunder flag to create a controlled flag. On the off chance that the control question is non-linear, the PID controller cannot give proficient control performance. The PID controller could be a straight sort and the foremost commonly utilized criticism controller. The PID controller persistently calculates the blunder esteem as the distinction between the measured handle variable and the specified setting focuses. Over time, the controller tries to decrease the blunder by changing the controlled variable. The following figure shows the system block diagram with PID[6][7].

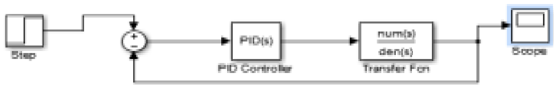

Fig 1. Simulink model for PID controller

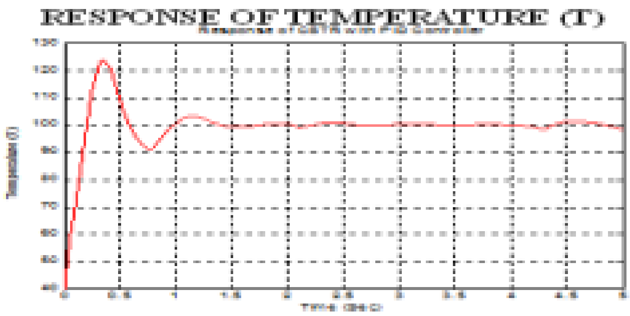

Fig 2. Response of PID controller

From the open loop response the response of the system is settled at 1.5 sec and rise at 1 sec.

B. MODIFIED PID CONTROLLER

A simple PID controller processes the error signal directly, which will produce a large overshoot of in the process response due to proportional and inferred gain. The process is unstable. In order to overcome the influence of proportional and derivative gains, you can consider using an improved PID structure called IPD. In the IPD structure, the integral term responds to errors, and the P+D term responds to the measured process performance. The figure shows the response from the CSTR with the modified PID controller.

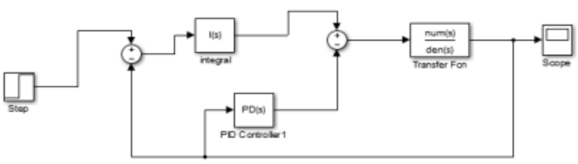

Fig 3. Simulink of modified PID controller

For conventional PID controllers, changes within the set esteem will cause sudden changes within the beat flag or controller yield and yield behavior. Such spikes within the controller yield are called relative or subordinate values. Controller yield is given to actuators, such as control valves, motors, or electronic circuits, where spikes are a genuine issue. But within the IPD controller, the corresponding term and the inferred term only affect the alter of the method variable, not the blunder, since these terms are indicated within the input way. This structure can dispose of the relative and subordinate values amid each set point alter.

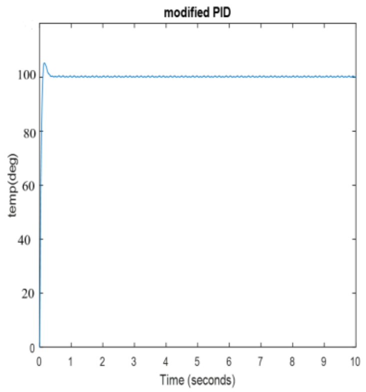

Fig 4. Response of modified PID controller

C. FUZZY TUNED PID CONTROLLER

Self-tuning fuzzy PID controller alludes to the utilize of fuzzy tuner to tune the three parameters Kp, Ki and Kd of the PID controller. The coefficients of conventional PID controllers more often than not cannot accurately coordinate the nonlinear framework with eccentric parameter changes. Subsequently, it is essential to naturally alter the PID parameters. Here e (t) is the mistake between the required position set point and the yield, and de (t) is the subsidiary of the blunder. PID parameters are coordinated utilizing fluffy induction. Fuzzy induction gives a non-linear mapping from mistake and mistake of to PID parameters. The figure appears the structure of the fuzzy coordinating PID controller.

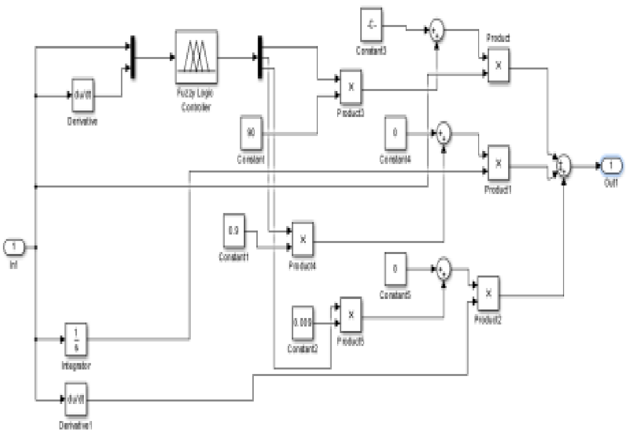

Fig 5. Simulink model fuzzy -PID controller

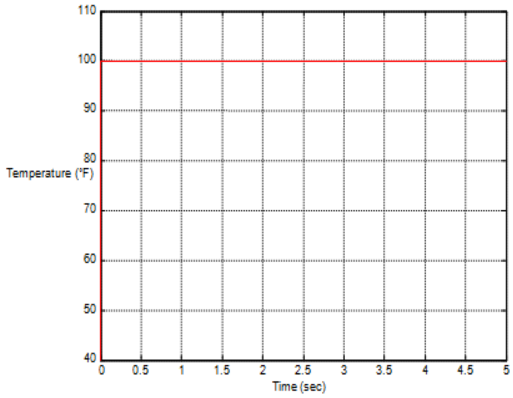

Fig 6. Response fuzzy - PID controller

V. RESULT AND DISCUISSION

TABLE 1 COMPARISION OF DIFFERENT CONTROLLERS

PID	Modified PID	FUZZY
peak time is 0.3550 sec.	peak time is 0.2 sec.	Rise Time (Sec) is 0.056 sec
Rise time is 0.1600 sec.	Rise time is 0.1 sec.	Overshoot (%) is 0.1807 %
Settling time is1.5875 sec.	Settling time is 0.5sec.	Peak Time (Sec) is 0.02 sec
Overshoot is 5.7864 %	Overshoot is 4.35%	Settling Time (Sec) is 0.005 sec

It has been clearly shown that the system is reached set point with more overshoot. Hence, results show that PID controller does not efficiently control. Again, the plant is analyzed with the fuzzy controller to ensure the dynamic performance of the CSTR. It is observed from the temperature responses that it reaches perfectly the final steady state value without any error and oscillations. Hence the time domain parameters are improved. Table 1shows the comparison of different controllers and it is observed that the time domain parameters of the temperature response of the CSTR plant such as tr, mp tr, and ts of the fuzzy controllers have been improved.

VI. CONCLUSION

The modeling is done on CSTR, and the fuzzy PID controller is effectively proposed. Numerical modeling employments Taylor courses of action to get a direct discrete representation of the reactor framework. The Fuzzy Self Tuned controller is associated to the to alter the values of Kp, Ki and Kd of the PID controller. Perform a few recuperation tests on the framework by employing a square wave flag and a step input flag. The response of the framework appears that, compared with the conventional PID controller, the control of the temperature framework is progressed and realized. The adaptive, self-adjusting fuzzy PI + fuzzy ID controller is fast, and effectively calculates online, reducing continuity errors. The simulation is obviously about the proposed control scheme that does not improve the fast follow-up execution, but it also increases the intensity of the process plant. Therefore, Fuzzy PID cannot be applied to the specific preparation of the controller, so to speak, because the results show that it can be connected to various other applications such as medical robots, industrial test and measurement for precise control.

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