Robust Performance of PID Controller by using Artificial Intelligence

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Received 10 March 2018, Accepted 15 May 2018, Available online 17 May 2018, Vol.8, No.3 (May/June 2018)

Abstract

This paper is meant to design method for determining the optimal proportional-integral-derivative (PID) controller parameters of plant system using the particle swarm optimization (PSO) algorithm and bacterial Foraging Optimization (BFO). There are several methods which are used to tune the controller parameters. They are categorized into two types known as classical methods and modern methods. In this paper the use of PSO method tuned the PID parameter to make them more general and to achieve the steady state error limit, also to improve the dynamic behaviour of the system. The performance and design criteria of automatic selection of controller constants are discussed below.

Keywords: Plant system, PID controller, PSO and BFO Optimization.

1. Introduction

During the past decades, the process control techniques in the industry have made great advances. Numerous control methods such as adaptive control, neural control, and fuzzy control have been studied. Among them, the best known is the proportional-integral-derivative (PID) controller, which has been widely used in the industry because of its simple structure and robust performance in a wide range of operating conditions. Unfortunately, it has been quite difficult to tune properly the gains of PID controllers because many industrial plants are often burdened with problems such as high order, time delays, and nonlinearities. For these reasons, it is highly desirable to increase the capabilities of PID controllers by adding new features. Many artificial intelligence (AI) techniques have been employed to improve the controller performances for a wide range of plants while retaining their basic characteristics. AI techniques such as neural network, fuzzy system, and neural-fuzzy logic have been widely applied to proper tuning of PID controller parameters PID controller consists of Proportional, Integral and Derivative gains. The PID feedback control system is illustrated in Fig. where r, e, y are respectively the reference, error and controlled variables (Dingyu Xue et al, 1993). Where Kp is proportional gain, Ki is integral gain and Kd is derivative gain.

A PID controller is described by the following transfer function in the continuous s-domain:

\[ G_c = P + I + D \]
\[ G_c = K_p + \frac{K_i}{s} + K_d s \]
\[ G_c = K_p \left(1 + \frac{1}{T_i s} + T_d s\right) \]

The PID control scheme is named after its three correcting terms, whose sum constitutes the manipulated variable (mv). The proportional, integral, and derivative terms are summed to calculate the output of the PID controller. Defining \( u(t) \) as the controller output, the final form of the PID algorithm is:

\[ u(t) = MV(t) = K_p e(t) + K_i \int_0^t e(\tau) d\tau + K_d \frac{de(t)}{dt} \]
Where,

- $K_p$: Proportional gain, a tuning parameter
- $K_i$: Integral gain, a tuning parameter
- $K_d$: Derivative gain, a tuning parameter
- $e$: Error $SP - PV$
- $SP$: Set Point
- $PV$: Process Variable
- $t$: Time or instantaneous time (the present)
- $t_0$: Variable of integration; takes on values from time $0$ to the present $t$.

Equivalently, the transfer function in the Laplace Domain of the PID controller is:

$$L(s) = K_p + \frac{K_i}{s} + K_ds$$

Where:

- $s$: Complex number frequency

2. **Swarm topology**

Each particle $i$ (total number of particles) has its neighbourhood $N_i$ (a subset of $P$). The arrangement of the neighbourhoods is called the swarm topology, which can be represented by a graph. Usual topologies are: Fully connected topology, Circle topology and single sighted topology.

**Characteristics of particle $i$ at iteration $t$**

- $x_i(t)$ - the position
- $p_i(t)$ - the individual best position
- $l_i(t)$ - the local best position of the neighbouring particles
- $v_i(t)$ - the velocity of the particle

At the beginning of the algorithm, the particle positions are randomly initialized, and the velocities are set to 0, or to small random values.

**Algorithm parameters**

- $w(t)$ - Inertia weight; a damping factor, usually decreasing from around 0.9 to around 0.4 during the computation
- $\Omega_1$, $\Omega_2$ - Acceleration coefficients; usually between 0 and 4

**Manipulating its velocity**

Many versions of the particle speed update exist, for example:

$$v_i(t+1) = \omega v_i(t) + \Omega_1 (p_i(t) - x_i(t)) + \Omega_2 (l_i(t) - x_i(t))$$  \hspace{1cm} (2)

The symbols $u_1$ and $u_2$ represent random variables with the $Q(0,1)$ distribution. The first part of the velocity formula is called inertia, the second one the cognitive (personal) component, the third one is the social (neighbourhood) component. Position of particle $i$ changes according to

$$x_i(t+1) = x_i + v_i(t+1).$$  \hspace{1cm} (3)

3. **PSO Algorithm**

PSO is optimization algorithm based on evolutionary computation technique. The basic PSO is developed from research on swarm such as fish schooling and bird flocking. After it was firstly introduced in 1995, a modified PSO was then introduced in 1998 to improve the performance of the original PSO.

**Basic Fundamentals of PSO Algorithm**

The basic fundamentals of the PSO algorithm technique are stated and defined as follows.

- **Particle $X(i)$**: A candidate solution represented by a $k$-dimensional real-vector, where $k$ is the number of optimized parameters; at iteration $i$, the $j$th particle $X(i,j)$ can be described as:

$$X(i,j) = [x_{j,1}(i); x_{j,2}(i); \ldots \ldots; x_{j,k}(i); \ldots; x_{j,d}(i)]$$  \hspace{1cm} (4)

Where: $x_i$ are the optimized parameters

- **Population**: This is the set or say population of $n$ particles at iteration $i$.

$$\text{Pop}(i) = [X_{0,i}; X_{1,i}; \ldots \ldots; X_{n,i}]^T$$  \hspace{1cm} (5)

Where $n$ represent the number of individual solutions.

- **Swarm**: As the name swarm defines the group of particles, it is a disorganized population of moving particles that tends to cluster together and each particle seems to moving in a random direction with their velocity.

- **Particle velocity $V(i)$**: The velocity of the moving particles represented by a $d$-dimensional real-valued vector; at iteration $i$, the $j$th particle $V(i)$ can be described as:

$$V(i,j) = [v_{1,j}(i); v_{2,j}(i); \ldots \ldots; v_{k,j}(i); \ldots; v_{d,j}(i)]$$  \hspace{1cm} (6)

Where $d$ represents the number of control variables.

**Weight factor $w(i)$**: This is a control parameter and sometimes it is called as inertia weight factor. The inertia factor decreases linearly from about 0.9 to 0.4 during a continuous run.

In general, this factor is set according to following equation:

$$W = w_{\text{max}} - (w_{\text{max}} - w_{\text{min}})/\text{iter}_{\text{max}} \times \text{iter}$$  \hspace{1cm} (7)
Individual best $X'(i)$: The best position that is associated with the best fitness encountered thus far is called individual best $X'(i)$. For each particle in the swarm, $X'(i)$ can be determined and updated during the search. For the $j^{th}$ particle, individual best can be expressed as:

$$X'(i) = [x_{1,i}^*(j), x_{2,i}^*(j), \ldots, x_{d,i}^*(j)]^T$$

(8)

In a minimization problem with only one objective function $f$, the individual best of the $j^{th}$ particle $X'^*(i)$ is updated. Otherwise individual best solution of the $j^{th}$ particle will be kept as in the previous iteration.

Global best $X'^*(t)$: This is the best position among all of the individual best positions achieved so far.

Stopping Criteria: The search process will be terminated whenever one of the following criteria is satisfied (Yogendra Kumar Soni et al, 2013).

Step 3 Reproduction loop: $k=k+1$

The cycle of the bacteria formation will be continuing and they will try to make the swarm size constant up to a certain value [4]. The least healthy bacteria sooner or later dies but the healthier bacteria splits up to two bacteria two maintain the swarm size constant.

Step 4 Chemotaxis loop

Chemotaxis loop: $j=j+1$

[a] For $i = 1, 2... S$ take a chemotactic step for bacterium $i$ as the iteration for the value of swarm.

[b] Compute fitness function, $J( j, k, l)$.

Suppose $(j, k, l)$ $i_q$ represents $i^{th}$ bacterium at $j^{th}$ chemotactic, $k^{th}$ reproductive and $l^{th}$ elimination-dispersal step. $C(i)$ is the size of the step taken in the random direction specified by the tumble (run length unit).

[c] Let $J_{last}$ = Last value $J( j, k, l)$ to save this value since we may find a better cost via a run.

[d] Tumble: generate a random vector

[e] Move: Let

$$\theta_{i,(j+1,k,l)} = \theta_{i,(j,k,l)} + C(i) \left[ \frac{d(i)}{d(i) \cdot d(i)} \right]^{1/2}$$

(9)

These results in a step of size $C(i)$ in the direction of the tumble for bacterium $i$.

[f] Compute $J(j+1,k,l)$ for finding the new position of bacterium.

[g] Swim

I. Let $n=0$ (which is the counter for swim length)

II. While $n<N_s$ (not gone to the higher level)

- Let $n=n+1$
- If $J(j+1,k,l) < J_{last}$ (if doing better)
- $J_{last} = J(j+1,k,l)$ and let

$$\theta_{i,(j+1,k,l)} = \theta_{i,(j,k,l)} + C(i) \left[ \frac{d(i)}{d(i) \cdot d(i)} \right]^{1/2}$$

(10)

And use this $\theta_{i,(j+1,k,l)}$ to compute the new values of $J$ which will be iterated by their respected nature.
5. Simulation and results

As the figure shows that manipulating the values of gain by PSO PID technique or PSO BFO technique it gives the required results. In both PSO as well as in BFO there are two important factors i.e. alpha and beta which is the base of the gain values. Alpha and Beta are the two constant terms which provide system stability.

Matlab modelling of plant model using controller

Fig.4 Matlab modelling for plant with PID controller

Functions are used for designing PID controller ISE, IAE, ITAE and ITSE. We set the following parameters:

- Dimension of search space = 3;
- The number of bacteria = 10;
- Number of chemotactic steps = 10;
- Limits the length of a swim = 4;
- The number of reproduction steps = 4;
- The number of elimination-dispersal events = 2;
- The number of bacteria reproductions per generation = s/2;
- The probability that each bacterium will be eliminated/dispersed = 0.25;
- c(:,1) = 0.5*ones(s,1); the run length.

We use the following PSO parameters:

- $C_1 = 1.2$;
- $C_2 = 0.5$;
- $W = 0.9$;

Output for the comparison of PSO and BFO with PID

This section describes about the comparison of PSO and BFO for tuning of PID controller.

Table 5.1 Comparison of PSO and BFO for 50 iterations with alpha = 10 and beta = 5.

<table>
<thead>
<tr>
<th>S.No</th>
<th>Gen.</th>
<th>$\alpha$</th>
<th>$\beta$</th>
<th>$K_p$</th>
<th>$K_i$</th>
<th>$K_d$</th>
<th>Mp%</th>
<th>$T_s$</th>
<th>$T_r$</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>50</td>
<td>10</td>
<td>0.96</td>
<td>0.85</td>
<td>0.67</td>
<td>22.52</td>
<td>9.27</td>
<td>1.48</td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>50</td>
<td>10</td>
<td>0.88</td>
<td>0.67</td>
<td>0.67</td>
<td>8.17</td>
<td>8.31</td>
<td>1.69</td>
<td></td>
</tr>
</tbody>
</table>

The response in Fig.5.1 shows that the comparison of PSO and BFO when the number of iteration is 50 and alpha = 10 and beta = 5 in such a condition that the output response of the system gives the value of maximum overshoot, rise time, settling time, and also the value of the gain i.e. the proportional gain and the integral gain.
Fig. 5.1 Output response for comparison of PSO and BFO

When \( n=50 \) (i.e. number of iteration denoted by generation) in this case considering the value of Beta to be 5 and Alpha to be 10, which will give the value of \( K_p = 0.9682 \) and \( K_d = 0.854 \) for PSO algorithm and similarly for BFO the value of \( K_p \) and \( K_d \) is \( 0.8809 \) and 0.6724 respectively. From the figure it is also clear that the maximum overshoot and settling time of PSO is greater than that of BFO, and the rise time is smaller than that of BFO.

Table 5.2 Comparison of PSO and BFO for 50 iterations with alpha = 10 and beta = 5

<table>
<thead>
<tr>
<th>S. No</th>
<th>1</th>
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</thead>
<tbody>
<tr>
<td>Gen.</td>
<td>50</td>
<td>50</td>
</tr>
<tr>
<td>( \alpha )</td>
<td>10</td>
<td>10</td>
</tr>
<tr>
<td>( \beta )</td>
<td>10</td>
<td>10</td>
</tr>
<tr>
<td>( K_p )</td>
<td>0.7463</td>
<td>0.8043</td>
</tr>
<tr>
<td>( K_i )</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>( K_d )</td>
<td>0.8605</td>
<td>0.779</td>
</tr>
<tr>
<td>( M_p% )</td>
<td>0.663</td>
<td>2.3438</td>
</tr>
<tr>
<td>( T_s )</td>
<td>7.0386</td>
<td>8.1187</td>
</tr>
<tr>
<td>( T_r )</td>
<td>2.0542</td>
<td>1.6221</td>
</tr>
</tbody>
</table>

The response in Fig.5.2 shows that the comparison of PSO and BFO when the number of iteration is 50 and alpha =10 and beta =10 in such a condition the output response of the system gives the value of maximum overshoot, rise time, settling time, and also the value of the gain i.e. the proportional gain and the integral gain.

Fig. 5.2 Output response for comparison of PSO and BFO

When \( n=50 \) (i.e. number of iteration denoted by generation) in this case considering the value of Alpha to be 10 and Beta to be 10, which will give the value of \( K_p = 0.7463 \) and \( K_d = 0.8605 \) for PSO algorithm and similarly for BFO the value of \( K_p \) and \( K_d \) is \( 0.8403 \) and 0.7790 respectively. From the figure it is also clear that the maximum overshoot and settling time of BFO is greater than that of PSO, and the rise time is smaller than that of PSO.

Table 5.3 Comparison of PSO and BFO for 50 iterations with alpha = 10 and beta = 15

<table>
<thead>
<tr>
<th>S.No</th>
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<tbody>
<tr>
<td>Gen.</td>
<td>50</td>
<td>50</td>
</tr>
<tr>
<td>( \alpha )</td>
<td>10</td>
<td>10</td>
</tr>
<tr>
<td>( \beta )</td>
<td>15</td>
<td>15</td>
</tr>
<tr>
<td>( K_p )</td>
<td>0.8188</td>
<td>0.8747</td>
</tr>
<tr>
<td>( K_i )</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>( K_d )</td>
<td>0.8333</td>
<td>0.8108</td>
</tr>
<tr>
<td>( M_p% )</td>
<td>1.9454</td>
<td>5.7273</td>
</tr>
<tr>
<td>( T_s )</td>
<td>6.89</td>
<td>8.31</td>
</tr>
<tr>
<td>( T_r )</td>
<td>1.88</td>
<td>1.74</td>
</tr>
</tbody>
</table>

The response in Fig.5.3 shows that the comparison of PSO and BFO when the number of iteration is 50 and alpha =10 and beta =15 in such a condition the output response of the system gives the value of maximum overshoot, rise time, settling time, and also the value of the gain i.e. the proportional gain and the integral gain.

Fig. 5.3 Output response for comparison of PSO and BFO

When \( n=50 \) (i.e. number of iteration denoted by generation) in this case considering the value of Alpha to be 10 and Beta to be 15, which will give the value of \( K_p = 0.8188 \) and \( K_d = 0.8333 \) for PSO algorithm and similarly for BFO the value of \( K_p \) and \( K_d \) is \( 0.8747 \) and 0.8108 respectively. From the figure it is also clear that the maximum overshoot and settling time of BFO is greater than that of PSO, and the rise time is smaller than that of PSO.
Table 5.4 Comparison of PSO and BFO for 50 iterations with alpha = 10 and beta = 20

<table>
<thead>
<tr>
<th>S.No</th>
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<th>2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gen.</td>
<td>50</td>
<td>50</td>
</tr>
<tr>
<td>α</td>
<td>10</td>
<td>10</td>
</tr>
<tr>
<td>β</td>
<td>20</td>
<td>20</td>
</tr>
<tr>
<td>Kp</td>
<td>0.5631</td>
<td>0.9762</td>
</tr>
<tr>
<td>Ki</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Kd</td>
<td>0.8155</td>
<td>0.4032</td>
</tr>
<tr>
<td>Mp%</td>
<td>0</td>
<td>23.08</td>
</tr>
<tr>
<td>Ts</td>
<td>7.1185</td>
<td>9.3541</td>
</tr>
<tr>
<td>Tr</td>
<td>3.2207</td>
<td>1.4851</td>
</tr>
</tbody>
</table>

The response in Fig.5.4 shows that the comparison of PSO and BFO when the number of iteration is 50 and alpha =10 and beta =20 in such a condition the output response of the system gives the value of maximum overshoot, rise time, settling time, and also the value of the gain i.e. the proportional gain and the integral gain.

Fig. 5.4 Output response for comparison of PSO and BFO

When n=50 (i.e. number of iteration denoted by generation) in this case considering the value of Beta to be 20 and alpha to be 10, which will give the value of $K_p = 0.5361$ and $K_d = 0.8155$ for PSO algorithm and similarly for BFO the value of $K_p$ and $K_d$ is 0.9762 and 0.4032 respectively. From the figure it is also clear that the maximum overshoot and settling time of BFO is greater than that of PSO, and the rise time is smaller than that of PSO.

Conclusion

From the closed discussion it is seen that by applying PSO algorithm it provides optimal values for PID parameters for better system performance. Using PSO it can be seen that the best overshoot is achieved many times along with good rise time as well as settling time.

BFO algorithm is next optimization technique applied for optimization of PID parameters for stability enhancement of plant model. Overshoot, rise time and settling time are achieved in specified range but as compare to PSO it is not.

Acknowledgment

I would like to express my sincere gratitude to Mr. Mahesh Singh, Sr. Assistant Professor, SSTC (SSGI), Bilhai, Mr. Kushal Tiwari, Project Coordinator, CREDA, Raipur & Mr. Chaman Yadav, Project Officer, ECBC Cell, CREDA, Raipur who have contributed, directly or indirectly, in the accomplishment of this paper.

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