

# DOUBLE FUZZY-PI CONTROLLER BASED SPEED CONTROL OF PERMANENT MAGNET SYNCHRONOUS MOTOR

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## ABSTRACT

*In high performance industrial application, Permanent Magnet Synchronous Motor (PMSM) becomes the main competitor for AC motor. PMSM has some advantages such as high efficiency, small size, high power density, large torque to inertia ratio, and low maintenance. PMSM is also very popular compared to DC motors in applications of machine tools, servo and robots, electric vehicle, and ship propulsions. Speed control of PMSM widely uses the conventional proportional integral (PI) controller, but PI controller has difficulty in speed changes, parameter variations and load disturbances. This paper presents double fuzzy logic controllers to tune the parameters of PI controller applied in the speed control of PMSM. Double fuzzy-PI (DFPI) controller is verified using simulation process for normal and disturbance conditions. DFPI controller has better performance compared to the conventional PI controller during change of operating condition. Simulation results of DFPI controller show that PMSM quickly achieve the speed reference, has small steady state error, no overshoot and reduce the speed oscillation during load disturbance condition.*

**Keywords:** *Permanent Magnet Synchronous Motor, Speed Control, PI, Double Fuzzy Logic*

## 1. INTRODUCTION

Permanent Magnet Synchronous Motors (PMSM) are becoming the main competitor to other types of AC motors in high performance motor drives applications. PMSM have some advantages such as high efficiency, small size, high power density, large torque to inertia ratio, and low maintenance. PMSM are also very popular compared to DC motors in applications of machine tools, servo and robots, electric vehicle, and ship propulsions [1,2]. Some criteria of high performance motor drives applications are insensitivity to parameter variation, fast speed responses, and quick speed achievement to a speed reference during load disturbance occurs. The conventional proportional integral (PI) controller has been widely employed as speed controller for PMSM drives. In order to obtain the best results of speed control, the axial reactance parameters of the d-q PMSM should be correctly known. However, the conventional PI controller has difficulty in speed changes, parameter variations and load disturbances [1-6].

To solve these disadvantages of PI controller, various artificial intelligent (AI) techniques have been applied in motor drives systems to control the speed of motor. Fuzzy logic controller (FLC) can be considered to improve the performance of conventional PI controller. FLC can provide nonlinear control action by selecting the appropriate parameters. In this way, the success key of designing an FLC is to define well its parameters such as knowledge base, rule base and scale factor (3-9). Nowadays, a method of control at the base of double fuzzy controller and a proportional integral (PI) controller has been developed [10, 11].

This paper presents the usage of AI methods especially double fuzzy logic (FL) to tune the parameters of PI controller applied in the speed control of PMSM. The effectiveness of the proposed systems is verified by simulation process using SIMULINK-MATLAB. Therefore, performance of Double Fuzzy-PI controller is compared with the conventional PI controller during change of operating condition based on the performance of induction motor.

## 2. SPEED CONTROL OF PMSM

Block diagram of PMSM drives system used in this paper is shown in Figure 1. PMSM is connected to pulse width modulation (PWM) inverter using current control. PMSM currents are decomposed into  $i_d$  and  $i_q$  components. These components represent flux and torque components in d-q coordinate system.

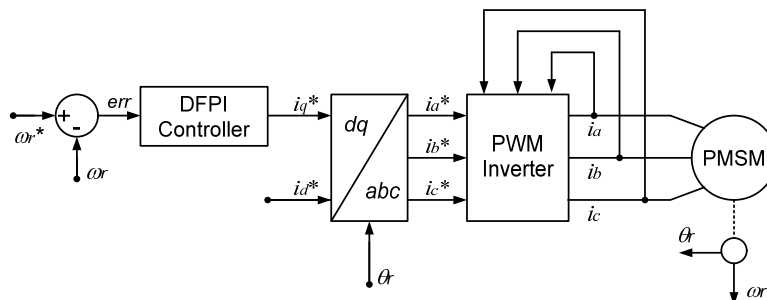


Figure 1. Block Diagram of PMSM Speed Control with DFPI Controller.

### 3. MATHEMATIC MODEL OF PMSM

The d-q model of the wound rotor synchronous machines is simply adapted to learn the dynamic performance of PMSM [1,2,4]. Back e.m.f. produced by permanent magnet is equal to produced by excited coil. Therefore, the d-q model of PMSM in the rotor reference frame can be seen in Equation (1).

$$\begin{bmatrix} u_d \\ u_q \end{bmatrix} = R_s \begin{bmatrix} i_d \\ i_q \end{bmatrix} + \frac{d}{dt} \begin{bmatrix} \phi_d \\ \phi_q \end{bmatrix} + \omega_r \begin{bmatrix} -\phi_q \\ \phi_d \end{bmatrix} \quad (1)$$

where  $u_d, u_q, i_d, i_q, \omega_r, R_s, \phi_d$  and  $\phi_q$  are stator voltage and current, in d-q frame, rotor speed, stator resistance, flux linkage in d-q frame, respectively.

Dynamic behaviour and electromagnetic torque of PMSM can be expressed in Equation (2) and Equation (3).

$$\frac{J}{p} \frac{d\omega_r}{dt} + \frac{f}{p} \omega_r = T_{em} - T_L \quad (2)$$

$$T_{em} = \frac{3}{2} p \{ \phi_f i_q + (L_d - L_q) i_d i_q \} \quad (3)$$

where  $J, p, f, L_d, L_q, T_{em}$ , and  $T_L$  are rotor inertia, pole number, reactance linkage d-q frame, electromagnetic torque and load torque, respectively.

### 4. DESIGN OF DOUBLE FUZZY PI (DFPI) CONTROLLER

Fuzzy logic controller (FLC) is one of most popular artificial intelligence (AI). FLC is used to solve nonlinear control problem or whenever the system model is unknown or difficult to build. The FLC is built from three steps: fuzzification, control rules evaluation and defuzzification. The fuzzy rules are obtained through knowledge of the process systems which automatically extracted from sample process [3-11]. Figure 2 show the control algorithm of PMSM speed based on a double fuzzy PI controller. The speed of PMSM is compared with the reference to obtain the error speed shown by Equation (4).

$$e(t) = \omega_m^*(t) - \omega_m(t) \quad (4)$$

where  $e(t), \omega_m^*(t)$  and  $\omega_m(t)$  are error speed, reference speed, and motor speed respectively. The change of error speed is given by Equation (5).

$$de(t) = e(t) - e(t-1) \quad (5)$$

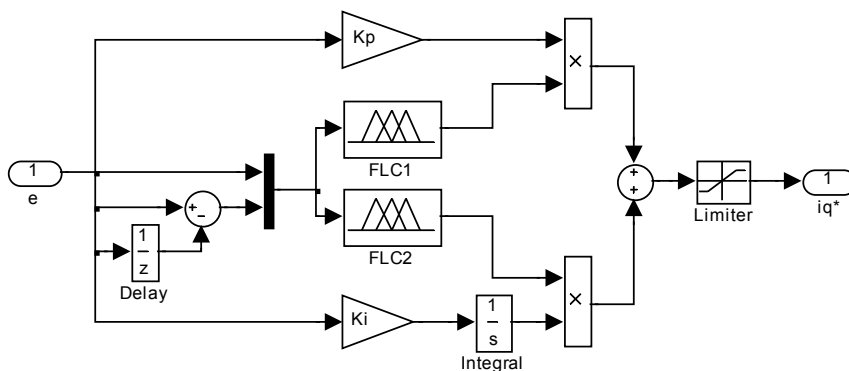


Figure 2. The DFPI Controller for speed control of PMSM

In this paper, FLC has five membership functions (MF) for two inputs and an output. Two inputs and an output are error ( $e$ ), change of error ( $de$ ) and promotional parameter ( $K_p$ ) or integral parameter ( $K_i$ ) respectively. The membership functions are built to represent its input and output value. The fuzzy sets of two input signals are as follows: ZE = Zero, PB = Positive Big, PS = Positive Small, NB = Negative Big and NS = Negative Small respectively. Whereas, the fuzzy sets of an output signals are as follows: S = Small, MS = Medium Small, M = Medium, MB = Medium Big and B = Big, respectively. Figure 3 and Figure 4 show the fuzzy sets and corresponding triangular MF description of two input signals and an output signals. The rule base of the FLC is shown in Table 1. Table 1 show that there may be  $5 \times 5 = 25$  possible rules.

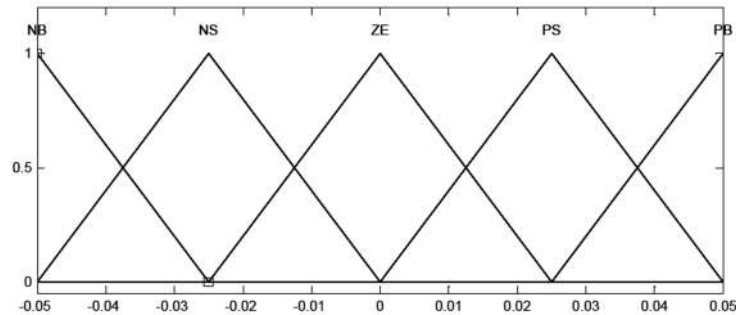


Figure 3. Membership Functions for inputs of FLC

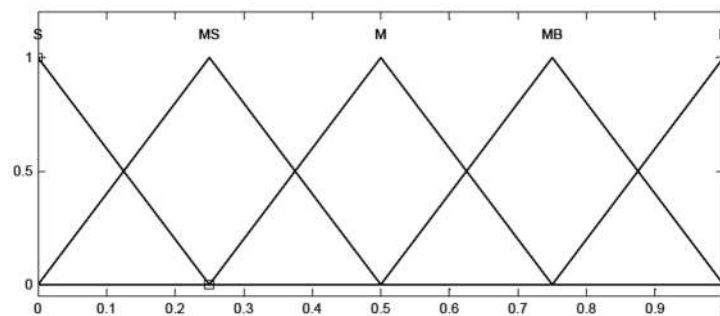


Figure 4. Membership Functions for output of FLC

Table 1. Rule Base of FLC

error ( $e$ )	change of error ( $de$ )				
	NB	NS	ZE	PS	PB
NB	S	S	S	MS	M
NS	S	S	MS	M	MB
ZE	S	MS	M	MB	B
PS	MS	M	MB	B	B
PB	M	MB	B	B	B

## 5. RESULTS

The effectiveness of the proposed Double Fuzzy-PI (DFPI) controller is clarified by simulation process. Simulation process is conducted in conditions of normal and disturbance. The parameters of permanent magnet synchronous motor (PMSM) used in this simulation is as follows: motor power of 1 HP, nominal voltage of 220 V, stator resistance of  $2.875 \Omega$ , direct inductance of 0.0085 H, quadrature inductance of 0.0085 H, 4 poles, inertia moment of  $0.0008 \text{ kg.m}^2$ , friction coefficient of  $8 \times 10^{-5} \text{ N.m.s}$ , motor flux of 0.175 Weber. Figure 5 shows simulation model in SIMULINK-MATLAB.

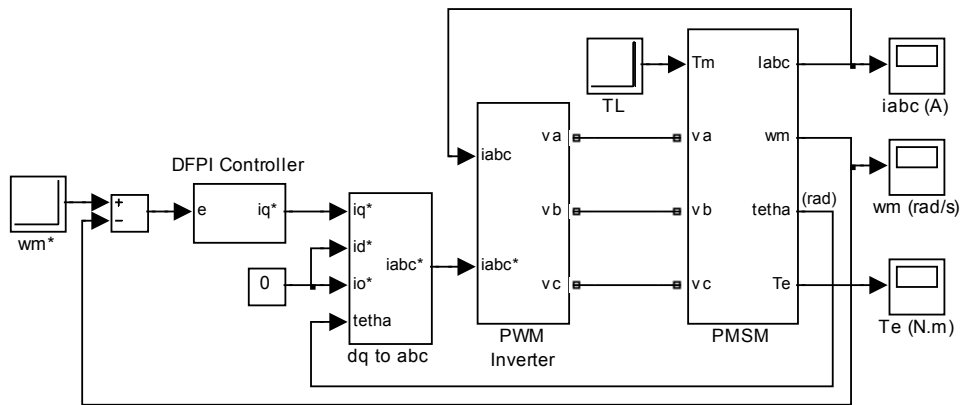


Figure 5. Simulation PMSM model using SIMULINK-MATLAB

Figure 6 shows speed response of PI controller and DFPI controller for speed reference of 700 rad/s. DFPI controller yields settling time of 0.008 s, no overshoot and small steady state error of 0.5 rad/s. Whereas, PI controller yields settling time of 0.013 s, overshoot of 4.1 % and also small steady state error of 1.1 rad/s. From their simulation results show that DFPI controller provide the improvement of performance compared to PI controller.

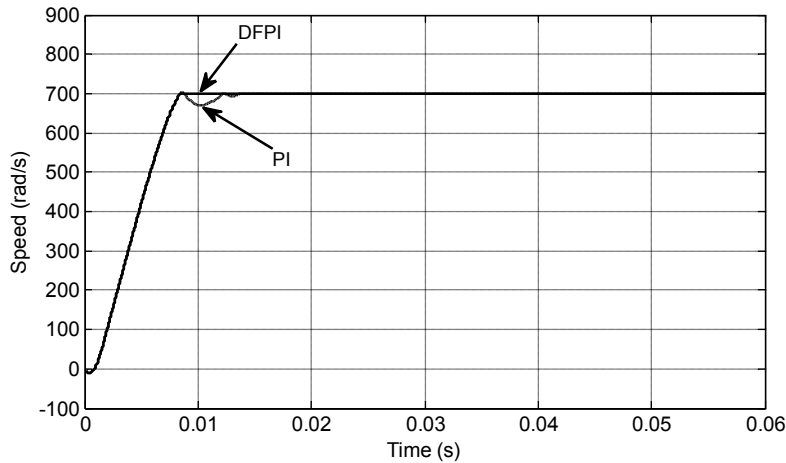


Figure 6. Speed response for speed reference of 700 rad/s.

Figure 7 shows comparison of the electromagnetic torque response between PI controller and DFPI controller. PI controller needs the greater electromagnetic torque than DFPI controller. These electromagnetic torques are used both controller to rapidly reach the speed reference, however PI controller causes speed oscillation.

Current of PMSM for PI and DFPI controllers are shown in Figure 8 and Figure 9. Both figures show that the change of electromagnetic torque causes the change of PMSM current.

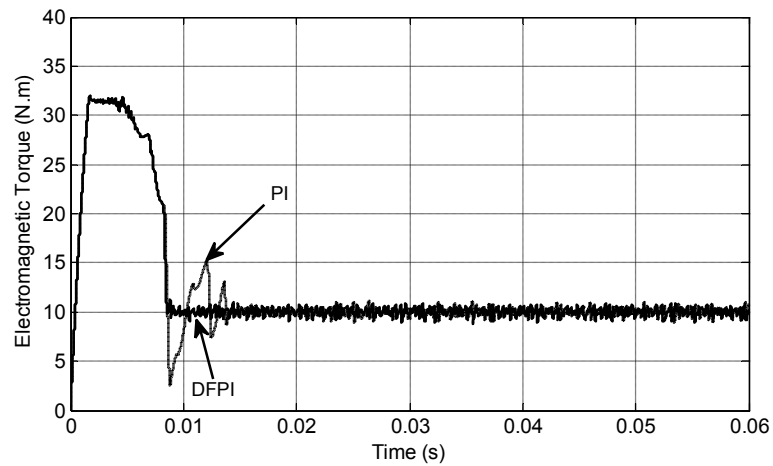


Figure 7. Electromagnetic torque responses for PI and DFPI controllers.

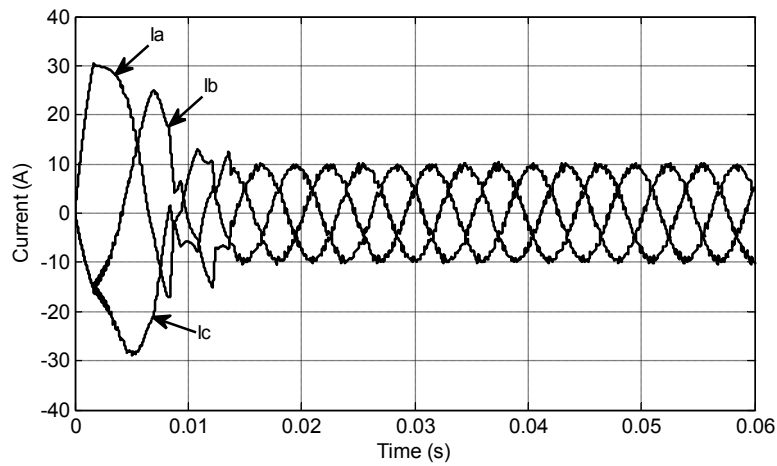


Figure 8. Current of PMSM with PI Controller

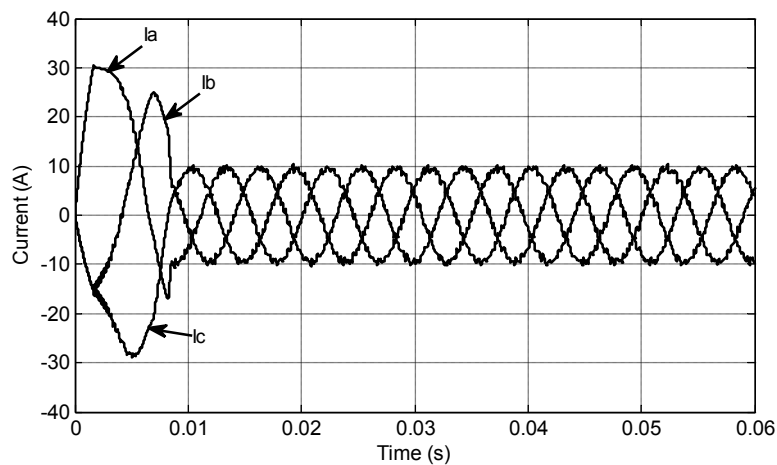


Figure 9. Current of PMSM with DFPI Controller

For disturbance conditions, the load torque of PMSM suddenly changes from 10 N.m to 15 N.m at  $t = 0.04$  s and also returns again to 10 N.m at  $t = 0.041$  s. The change of load torque affects the electromagnetic torque of PMSM shown in Figure 10. PI controller requests the greater electromagnetic torque than DFPI Controller. Disturbance also causes change of PMSM speed shown in Figure 11. Simulation result shows that speed error for PI controller is better than DFPI controller but PI Controller still produce speed fluctuation.

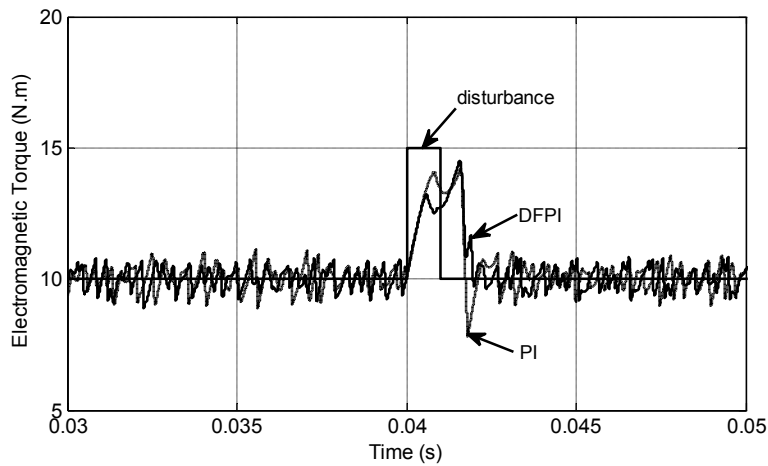


Figure 10. Electromagnetic torque of PMSM for disturbance condition

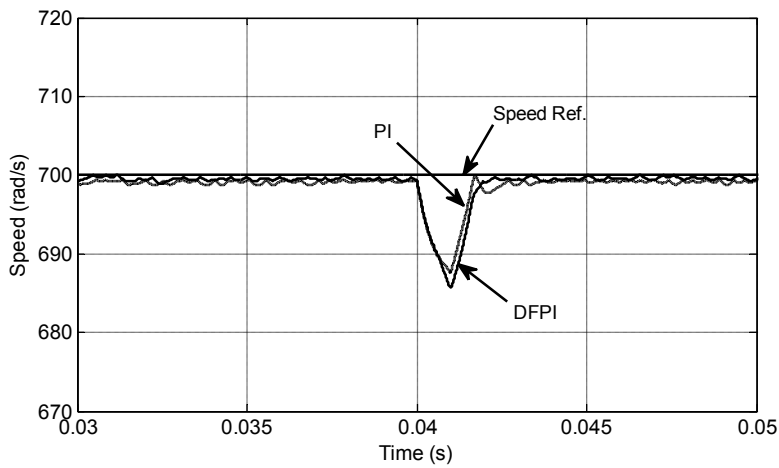


Figure 11. Speed responses for disturbance condition

Figure 8 and Figure show PMSM current of PI and DFPI controllers during disturbance condition. Both figures show that the disturbance causes the change of PMSM current. Simulation results show that PMSM current for DFPI controller is better than PI controller.

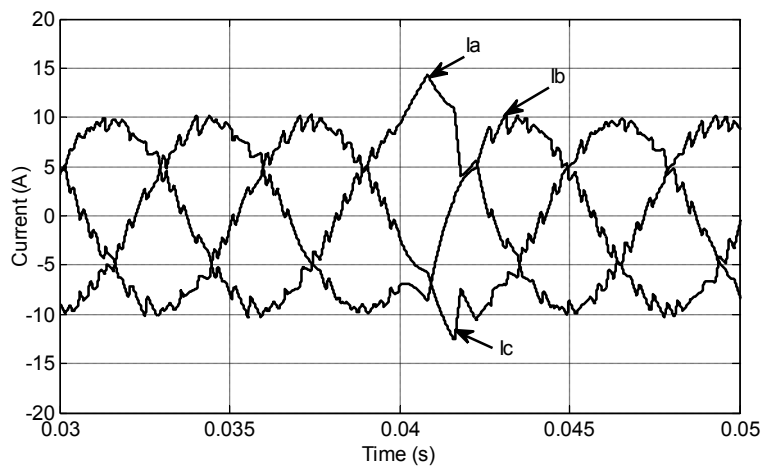


Figure 12. Current of PMSM for PI Controller

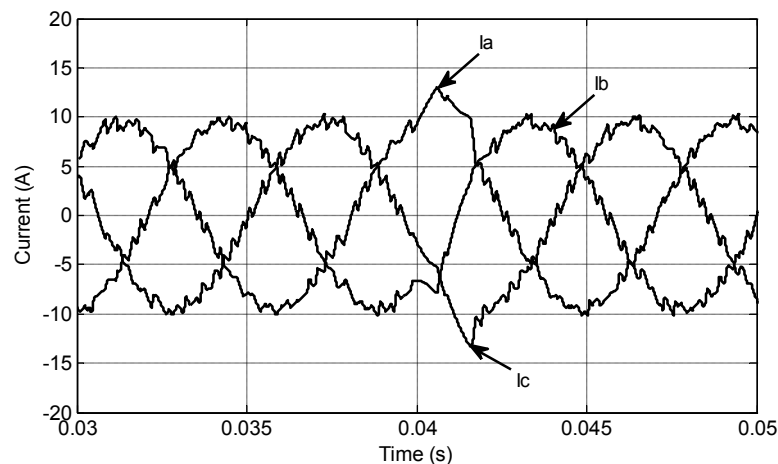


Figure 13. Current of PMSM for DFPI Controller

## 6. CONCLUSION

Double fuzzy proportional integral (DFPI) controller applied in speed control of PMSM has been presented and discussed. Double fuzzy logic technique is used to adjust the parameters of PI controller ( $K_p$  and  $K_i$ ). Double fuzzy logic can improve the performance of PI controller when there are changes of PMSM parameters. DFPI controller proposed is verified by simulation process. Simulation results show that DFPI controller produces better performance compared to PI controller. DFPI controller rapidly achieves the speed reference, has small steady state error, no overshoot and decreases speed oscillation during load disturbance condition. The settling times of PI and DFPI controllers are 0.008 s and 0.013 s respectively. Whereas, steady state errors of PI and DFPI controllers are 0.5 rad/s and 1.1 rad/s respectively.

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