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Simple and Complex Control Systems Use Pneumatic Flow Control Valves

Rajesh Gupta and Rohit Srivastava***

ABSTRACT

Pneumatic control valves are frequently used in industrial facilities to regulate fluid flow rates precisely. These valves often introduce unexpected dynamics into the control loop because of the characteristics of their inputs and outputs. The control loop's performance suffers as a result, which is undesirable. In this inquiry, a fractional order parallel flow control system that is both reliable and strong is proposed (FOPCS). It is a variation of the parallel control structure (PCS), known as a fractional order parallel control structure (FOPCS), that uses fractional order calculus to increase control-loop resiliency while maintaining efficiency. To fine-tune the control structure's parameters, researchers used a backtracking search strategy. Because of this, the control loop's efficiency went through the roof. FOPCS has been proven to be a success through extensive laboratory-scale studies using modern data collection methods. Over a long period of time, these experiments were conducted. The suggested FOPCS is analysed in terms of servo, regulation, and robustness to see how well it works. FOPCS and PCS are compared quantitatively using the absolute error, controller output rate, and the combined algebraic total. FOPCS was able to manage the unexpected and nonlinear behaviour of pneumatic control valves in the flow control loop, according to all of the experimental tests.

Keywords: *Parameters Controller; Pneumatic; FOPCS; Control Valves; Proportional-Integral-Derivative Controller.*

1.0 Introduction

The dynamical management of industrial systems has become relatively essential in the process control industries for the purpose of improving the performance of such industries and increasing their profitability. This is being done with the intention of enhancing the performance of such industries and increasing their profitability. It's possible that these businesses are reliant on the many control loops that are present at a given facility. The control of a variety of factors, including flow rate, level, pressure, temperature, ratio, and others, are often included into these loops. The flow rate control loop is the most prevalent kind of this type, and it is likely to be present in as many parts of an industrial facility as is humanly practical. Because of this, flow control loops need a significant level of attention due of the substantial influence that they have on the overall productivity of the process. This is because of the fact that flow control loops are responsible for controlling the flow

**Corresponding author; PhD Scholar, Department of Mechanical Engineering, IIITDM Jabalpur,Madhya Pradesh, India (E-mail: 1613602@iiitdmj.ac.in)*
***Assistant Professor, Department of Mechanical Engineering, SR Institute of Management and Technology, Lucknow, Uttar Pradesh, India (E-mail: srivastavarohit30@gmail.com)*

of the process. Pneumatic control valves are the devices that are used the majority of the time in order to achieve the amount of flow rate control that is sought. On the other hand, the use of pneumatic control valves might result in the introduction of nonlinear and unexpected dynamics into the control loops. The majority of the time, the nonlinear behaviour of these valves may be ascribed to either the geometry of the plug or to a nonlinear link that exists between the stem position and the flow rate. However, there are certain instances in which the nonlinear behaviour cannot be explained. In addition, the nonlinear nature of the valves and the influence of ageing are two elements that contribute to the unexpected nature of flow control loops. These are both aspects that contribute to the nature of flow control loops. In spite of the fact that these control loops are nonlinear and susceptible to uncertainty, a conventional linear proportional-integral-derivative (PID) controller is used in order to regulate them on a single operational point. The use of PID controllers is widespread in the process industries because of their ability to fulfil a diverse range of objectives across a broad spectrum of processes. These objectives include, amongst others, the integration of systems and the production of inverse response characteristics in processes. This is because PID controllers are capable of managing a diverse range of processes, which is why this is the case. Conventional PID controllers may be found in the literature with a broad range of designs and applications. Each of these conventional PID controllers is tailored to a particular class of processes. . It has been said that a sufficient servo and regulatory response together with a low integral squared error was produced by employing the controller, and that the construction of a PID controller for the integrating process has been described in [1]. Another example of employing a PID controller for integrating processes can be found in [2], which describes how the gains of a PID controller were optimised with the use of a technology that uses bacteria to simulate the effects of ageing. An further illustration of the use of a PID controller for integrating processes is shown here. We were also successful in achieving a considerable boost in servo responsiveness by using the setpoint filter. This was made possible by the aforementioned success. In [3], it was mentioned that PID controllers may potentially be used for integral processes that were unstable. In order to decrease the value of the goal function, a genetic algorithm was utilised to make adjustments to the controller's gains. When the dynamics of a system incorporate integrating nature as well as temporal delay, the work of controlling the system becomes considerably more challenging. The task of regulating the system [4] provides a description of a PID controller that was constructed using the direct synthesis (DS) method for the purpose of regulating an integrating process that incorporates a time delay. This PID controller was designed for the purpose of controlling an integrating process. In addition to that, setpoint weight parameters were established so that the undesired overshoot in the process variable could be eliminated. This was done in order to achieve the goal of. In addition, the research community has taken a comprehensive approach to the problem of disturbance rejection, which is a primary concern in the process industry. This is only one of the numerous topics that has received considerable attention from researchers. It has been said that the PID controller suggested in [4], which utilises the DS method, displays convincing disturbance rejection capabilities. [4] There is still another strategy that has been discussed in [5] that works toward providing better disturbance rejection. The controller was developed specifically to allow higher disturbance rejection, and the DS approach is what makes this possible thanks to the controller's foundation in this technique.

In spite of the fact that the PID control algorithm is widely used in process industries due to the fact that its construction is simple, it has a low level of complexity, and it is relatively inexpensive, there is a possibility that it may have significant shortcomings in terms of the control performance [6]. These issues include, but are not limited to, a deterioration in control performance as a consequence of derivative action in the presence of measurement noise; integral control complexity;

computational error; and so on and so forth. In addition, a PID controller is often constructed inside a conventional control framework with the goal of offering either increased servo response or enhanced disturbance rejection. This is typically done with the use of a conventional control framework. In order to achieve both of these objectives, a control strategy that has been referred to as a parallel control structure (PCS) has been published in [7]. This strategy is a control approach in terms of regulatory, servo, and robustness performance. Regulatory performance, servo performance, and robustness performance are the goals that this control approach seeks to accomplish. PCS is equipped with not one but two different PID controllers, each of which is responsible for rejecting load disturbances and monitoring the setpoint. Through the use of these separate controllers, PCS is able to effectively divorce the setpoint tracking response from the disturbance rejection response in a control loop. This is achieved in a successful manner. These different controllers have the potential to be fine-tuned in order to deliver enhanced control performance throughout the majority of conceivable operating settings. This is feasible because to the controllers' adaptability. PID controllers now have the lion's share of the market share in the industry of process control, with around 90 percent of the process control loop employing it [8]. Since a consequence of this, the PID controller is the component that should be used in PCS as it is the most suited choice.

The process of putting industrial technology into practise is complicated by a number of factors, not the least of which are nonlinearities and uncertainties. The values of the process parameters are subject to fluctuate depending on the operating point when there are nonlinearities and uncertainties present. As a result, controllers need to be developed in order to provide outputs that are more precise whenever these components are present. Researchers came to the conclusion that the standard PID controller is not a viable solution since it is unable to deliver the desired outputs in the face of a nonlinear and unpredictable environment. This was one of the main reasons why the researchers got to this result. [Further citation is required] [Further citation is required] The flow control loop that uses a pneumatic control valve as its final control element is not an exception; it, along with the other control loops, is susceptible to the degrading influence of nonlinear and uncertain dynamics. This is because the flow control loop uses a pneumatic control valve as its final control element. This is the situation regardless of the fact that the flow control loop has a pneumatic control valve functioning as its final control element. The passage of time has led to the emergence of a wide range of fresh strategies, each of which is an effort to find a solution to the problems that have been brought up. The process control industry is now investigating these novel developments; nonetheless, there are considerable concerns about the problems involved with the intricate structural application of these innovations and their successful tuning. Recent advances in control algorithms have led to the introduction of fractional order calculus [9], which is a reaction to the issues stated above. These innovations are a consequence of recent advancements in control algorithms. The reference number [10] contains both a description of a fractional order controller for integral and unstable processes as well as a discussion of the development of this controller. In order to facilitate setpoint tracking and disturbance rejection, respectively, it is necessary to optimise the gains of the fractional order proportional-integral-derivative (FOPID) and proportional-integral-derivative (PID) controllers in order to provide the minimum integrated absolute error. This is done by adjusting the fractional order proportional-integral-derivative (FOPID) controller for optimal gains (IAE). According to the findings, FOPID is superior to conventional PID in terms of disturbance rejection, and it also requires a lower amount of IAE than conventional PID does. This is due to the fact that FOPID uses a more efficient algorithm. In [11], it is stated that the FOPID controller is a generalised PID controller that provides improved resilience with simplicity in addition to all of the other benefits that standard PID controllers provide. This is in addition to all of the other advantages that are provided by standard PID controllers. This is due to the fact that the PID controller forms the basis for the FOPID controller, which is a generalisation of the PID controller. In addition, two novel tuning processes for the most effective design of a FOPID controller are provided in [12]. These procedures may be found in the aforementioned reference. The aforementioned resource has further information on these different tactics. Several simulation tests were carried out in order to provide evidence that the recommended tuning procedures are effective in achieving the desired results. A good lesson on the dynamics of fractional order control, as well as its implementation aspects and its influence, may be found in article [13], which gives this information. In addition, it has been shown and established in the scholarly literature that the FOPID controller offers more robustness despite the fact that it must function in an environment that is both nonlinear and unpredictable. There are many who believe that FOPID controllers that are assisted by fuzzy theory perform better [14,15]. In the research presented in [14], a variety of hybrid controller setups that make use of fuzzy-based concepts are investigated. In order to ensure that the closed loop system achieves the best degree of control performance that is practically attainable, the genetic algorithm was programmed into the system. In addition, various other uses of FOPID controllers may be observed in a number of industrial applications, as reported in [16–21]. These uses can be seen in a variety of different settings. Viewing these many applications of the FOPID controller is possible. However, this comes at the expense of either the setpoint tracking performance or the disturbance rejection performance. It is possible to remark that the robustness of a traditional PCS may be increased by adopting proper tuning techniques; however, this comes at the expense of either of these two performances. This is a compromise that cannot be avoided. Recently, an extension of the integer order controllers known as fractional order controllers has been completely investigated with the objective of enhancing control loop resilience. This was done in order to improve control loop resilience. This measure was taken as a result of the introduction of fractional order controllers. The importance of fractional order management has been shown in a significant number of different ways [22–25,29,30]. Many of these instances may be found in the literature.

On the basis of the results of the literature research that was carried out, one may reach the conclusion that the decoupling capabilities of PCS are responsible for properly handling the setpoint tracking and disturbance rejection tasks of PCS. On the other hand, the fractional order calculus, which helps to the improvement of the control system in more than one way, might be thought of as an example. Primarily, it is believed that it would provide the system with greater robustness [11–14]. In addition, several additional advantages, such as the ones listed below, may be realised by making use of fractional order calculus:

- Giving users a greater amount of leeway in how they configure various aspects of the control system The order of integration and differentiation in a conventional PID controller is always one, so the number of parameters that define it is typically three: proportional gain, integral gain, and derivative gain. A conventional PID controller uses integer order calculus, which means that the order of integration and differentiation is always one. These parameters may be adjusted using the control that was built so as to achieve the desired degree of performance. However, a fractional order PID controller provides a greater degree of freedom to the control designer than a conventional PID control structure does. This is because there are two extra parameters, namely the order of integration and differentiation, in a fractional order PID controller. This increase in the number of parameters that may be adjusted in the FOPID controller provides the control designer with more accessibility, allowing them to develop a structure that is more effective than before.

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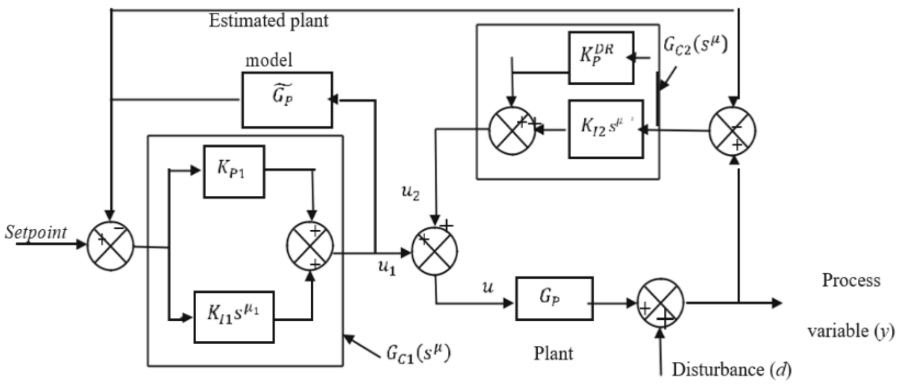
- In some situations, the implementation of an increased amount of high-frequency noise suppression inside the control loop It is essential to take into consideration the fact that a typical PID controller often struggles with high frequency noise amplification. This is because the amplitude of the derivative control component is significantly bigger at higher signal frequencies than it is at lower signal frequencies. The reason for this is because higher signal frequencies have a higher frequency. The signal of interest that is being propagated in the control loop of a process control application is often of a low frequency type. This is because low frequency signals are easier to detect and analyse. Utilizing a low pass filter is one way to cut down on the amount of high frequency noise component. Nevertheless, the rejection of noise in the control loop may also be performed or improved by using a fractional order derivative action. This is one of the many ways this can be done. This is only one of many other ways that things may be done. It is anticipated that a fractional order partial integral derivative (FOPID) will give better noise suppression than a conventional integer order control structure in circumstances involving control structures that are otherwise comparable. This is due to the fact that the magnitude of a fractional order derivative operator (with strength that is less than unity) will be lower than that of the conventional integer order control structure.
- Taking into account the need for robustness while also including fractional order calculus The sensitivity functions at a variety of operating frequencies are linked to the improvement in robustness that can be accomplished by using a fractional order controller in a control system. This increase in robustness can be obtained in a control system. Sensitivity functions are included in both a standard PID controller and a FOPID controller; however, the size of these functions is determined in very different methods. A FOPID controller that has been created appropriately is believed to be able to deliver bigger margins of stability, and as a consequence, fractional order control systems are able to achieve better degrees of resilience.

The body of work that has been referenced enables one to arrive at the conclusion that the most recent trend in research has been to improve control performance by capitalising on the one-of-a-kind qualities that fractional order calculus possesses. This conclusion can be arrived at because it is possible to reach this conclusion because it is possible to arrive at this conclusion because the research that has been referenced. Because it is feasible to draw this conclusion because it makes it possible to draw the conclusion that the body of work that has been mentioned, this conclusion may be reached because it is possible to draw this conclusion. The identification of the pattern paves the way for the drawing of this specific conclusion, which may then be inferred. It is anticipated that the fractional order controller, which will ride on the advantages provided by its features, will produce a control scheme that is more noise resistant, robust, and versatile than other control schemes. This will be accomplished by capitalising on the advantages provided by the features of the fractional order controller. This will be the outcome of making the most of the opportunities presented by the advantages that are supplied by the qualities of it. On the basis of these significant benefits that fractional order PCS (FOPCS) provides, FOPCS is currently being investigated to provide decoupled servo and regulatory performances along with improved robustness in the system. This is being done in order to take advantage of the significant advantages that FOPCS provides. This is being done in order to take full use of the many benefits that FOPCS makes available to its users. This is being done in order to make the most of the plethora of benefits that FOPCS makes available to its users so that we can maximise their potential. These advantages are obtained as a direct result of the fact that fractional order PCS is made available via FOPCS. This accessibility results in the acquisition of these advantages. It is possible that this FOPCS will assist to supply a way for controlling the variables of a process in an efficient manner, despite the presence of a nonlinear and unpredictable environment. It is possible that this FOPCS will help to offer this approach. This possibility arises as a consequence of the fact that this FOPCS was developed in order to provide such a method. This paper investigates the same concern, and an attempt has been made to investigate the hybridization of the methodologies that have been mentioned above, specifically the implementation of fractional order calculus in classical PCS for flow control while there is a nonlinear pneumatic control valve present. The purpose of this investigation is to better understand how to control flow when a nonlinear pneumatic control valve is present. The findings of this inquiry are going to be discussed in this article. This investigation is being conducted with the goal of gaining a deeper comprehension of how flow can be managed in the presence of a nonlinear pneumatic control valve. This second piece of study investigates the same issue as the one being discussed in this article. The efficiency of FOPCS may be evaluated by carrying out a series of runtime investigations on a hardware configuration while using innovative data collection technologies. These investigations can be carried out throughout the course of the system. These studies are applicable to a broad variety of hardware configurations, and they may be carried out on any one of those configurations. During the run-time studies, an in-depth examination and evaluation of the performance of FOPCS is carried out using criteria that are connected to error and aggression in controller output. This allows for a more accurate and thorough assessment of the system's capabilities. Because of this, it is possible to generate a more precise illustration of the system's total capabilities. This review has a primary emphasis on setpoint tracking, disturbance rejection, and robustness as its three primary foci areas.

2.0 System Operation Exposition

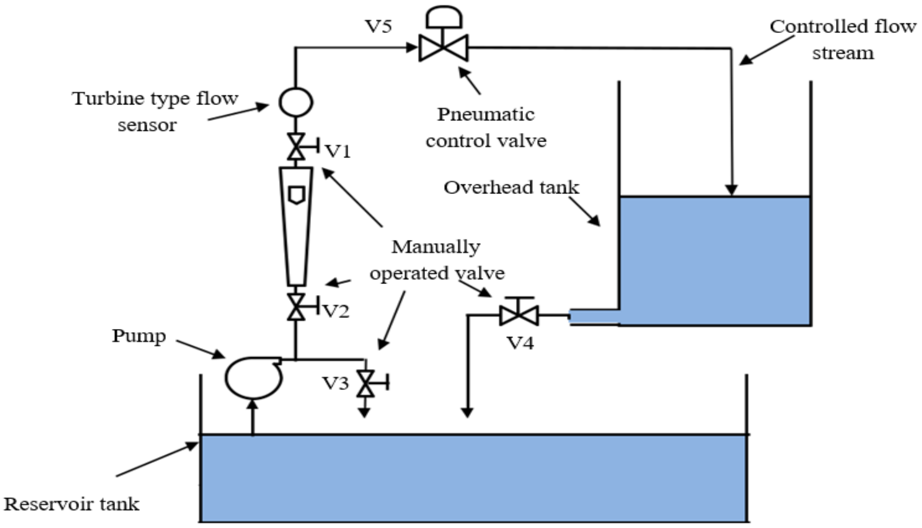
PCS is an uncommon subtype of control structure that consists of two loops for the management of just one process variable [1]. PCS is also known as a parallel control structure. These control loops have been developed with the purpose of separating the servo actions from the regulatory actions and, as a result, making them completely independent of one another. On the other hand, the need of having the ability to cope with changes in parameters, also known as resilience, is likely to be significantly increased in a conventional PCS. This requirement is mostly brought about by the presence of parameter uncertainties, which include, among other things, process nonlinearities, inaccurate evaluation of system parameters and dynamics, impacts of wear and tear, and so on. This study presents and investigates the FOPCS as a possible solution for flow control in a laboratory facility of a smaller size. the paper's focus is on the small-scale facility.

Figure 1: Fractional Order Parallel Control Structure Block Diagram



It is possible to deduce from Fig. 1 that GP is the process that has to be regulated and that y is the process variable. The 'd' disturbance is operating directly on the process, and its effect is being added to the variable that describes the process. 'u' refers to the control input that is placed into the process and is itself created. It may be noticed from Eq. 3 that the settings of both FOPI controllers may separately determine the dynamics of the servo and regulatory mechanism. However, for plant-model mismatch situation i.e. under parametric fluctuations, the dynamics of the whole control loop will be changed from the nominal. As a direct consequence of this, the independence in the control actions of G C1 and GC2 will be eradicated. In addition, the performance indices and process output variations may dramatically deviate from the nominal case in a number of different ways.

It is essential to be aware that the existing PCS has been expanded to FOPCS in order to eliminate the possibility of a difficult implementation of the controller for real-world applications. This was done in an effort to maintain the highest level of clarity feasible. The control structure was purposely kept on the simpler end of the spectrum in order to achieve a greater degree of adaptability in the manner in which it was applied. The inclusion of a fractional order controller is a crucial component that calls for painstaking attention to detail at every stage of the process. The dynamics of an operator with a fractional order may often be approximated using operators with an integer order, since this is a typical way for creating operators with fractional orders. In order to accomplish the goals of this investigation, the tried-and-true method of approximation known as Oustaloup's recursive approximation (ORA) was implemented. The creation of fractional order operators was accomplished via the application of this strategy.



3.0 Actuator Adjustment

The degree to which the settings of the controller have been fine-tuned has a considerable influence on the controller's overall performance. In order to establish realistic comparisons between the different controllers, it is necessary to alter the settings of each controller on a single platform using the most effective approach that is currently available. This must be done before any comparisons can be created. It is essential that this step be taken in order to guarantee that the comparisons are as precise as is practically feasible. By tuning the controller on a platform that is the same for all applicants, you will eliminate any risk of favouritism being shown toward a particular controller and offer each competitor with an equal opportunity to be successful. A huge number of various tuning procedures have been created and improved throughout the course of history in order to establish the appropriate parameter values for a broad range of controllers. This has required a great lot of time and effort. There has been an increased emphasis on the development of tuning processes for PID controllers as a result of the widespread use of PID controllers in recent years across the business world. This is because PID controllers have become so prevalent in today's industry as a result of their increasing availability. On the other hand, there are a number of possible obstacles that might prevent these strategies from attaining the outcomes that are wanted. These reasons may include the use of a controller with a structure other than PID; the use of a customised performance index, which these tuning approaches may not address; the use of PID controllers in a structure that is different from the classical one, etc.; the use of any combination of these and other reasons; or the use of any combination of these and other reasons. When it comes to making adjustments to the FOPCS's settings, this approach keeps running into the same problems over and over again. The performance index is a mixture of three separate criteria, and the structure itself is not a standard feedback system. The structure's goal is to maximise efficiency. For the purpose of carrying out this specific piece of research, the FOPCS does not make use of a typical PI organisation. As a direct result of this, tuning rules that have been developed in order to optimise the parameters of PI or FOPI controllers that are now in use are unable to be utilised in an effective way as a result of the inability to employ tuning rules in an efficient manner. In light of this, the research that is described here focuses on a relatively new branch of engineering that is known as the optimization of multimodal functions. The optimization of a number of unique multimodal functions is a challenging process, and standard approaches may be unable to create a solution that is genuinely optimal for this purpose. Numerous bio-inspired and meta-heuristic global optimization algorithms have been examined in attempt to find a solution to this problem. The results have shown that these algorithms are quite successful, which supports the hypothesis that finding a solution to this problem is possible.

3.1 Product explanation

Figure 3: Laboratory Scale Plant Snapshot

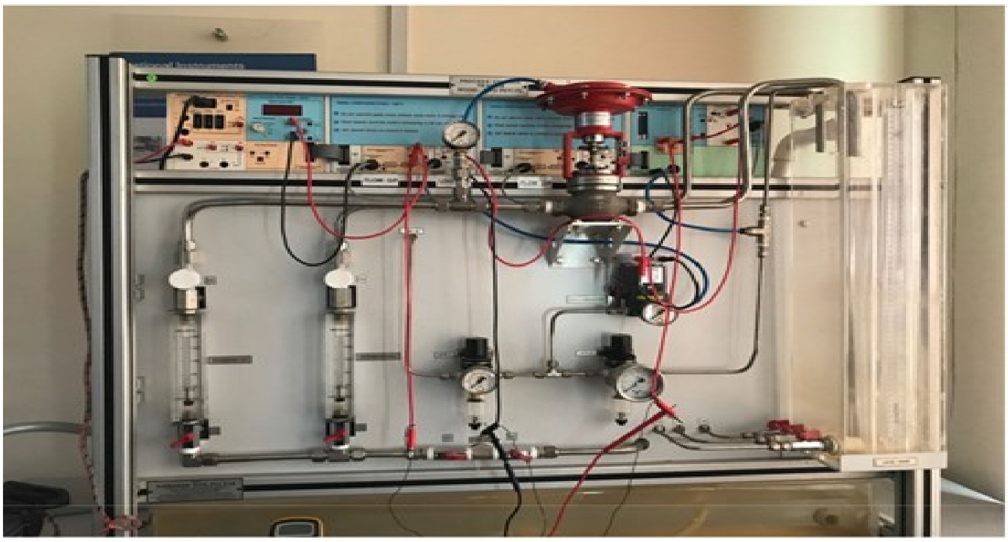


Figure 2 is a figure that depicts the process control system that was used for this study at the laboratory size. The diagram is in the form of a schematic. The schematic design that is now being

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presented is not a precise portrayal of the actual plant; rather, it is an example of the significant components that were used over the course of this investigation. The facility that has been described above uses a pneumatic control valve that has an equal percent characteristic in order to regulate the flow of the fluid. In order to do this, the valve must have an equal percent characteristic. The link between stem position and flow rate is demonstrated to be nonlinear by the equal percentage characteristic, which describes how the percentages add up.

The air-to-close kind of pneumatic control valve that is used in this system has a diaphragm that measures one half of an inch. In order to transform the rate of fluid flow into voltage, a flow transducer in the form of a turbine is used. This transducer converts the flow rate that is measured on a scale that runs from 0 to 200 LPH to a scale that measures voltage and may go anywhere from 0 to 2.5 V. The facility has two acrylic body rotameters that each measure a half an inch in diameter and have a range that extends from zero to two hundred LPH. The water that is being tested is stored in a tank made of acrylic, and it is pushed using a distribution motor pump that has a rating of 0.062 kW, 1/12 HP, 2800 RPM, a 1/2 inch output, 500 LPH, and a brass impeller. The pump is moving the water at a rate of 500 LPH. In order for the pump to function, a power supply that provides 230 volts at 50 hertz is essential. The factory in issue employs a wide range of converters in its operations. Figure 3 depicts the laboratory size flow process setup in its entirety. This configuration was employed in the research described in this article.

3.2 The assessment of the kinetics of the method

It was said earlier in this piece of writing that the flow rate control loop may have a nonlinear and unexpected behaviour. This was mentioned because of the existence of a pneumatic control valve. This is due to the fact that the pneumatic control valve is an integral part of the loop. The procedure was put through its paces at a number of various operating points by being stimulated with a range of input signals. This was done in order to confirm the confusing behaviour that was seen throughout the testing. After the open-loop system had been built, the change in flow rate that it produced was evaluated and analysed. Because the control valve that was used is of the air-to-close kind, the plant had to be stopped in the beginning so that open loop data could be gathered. This was done by providing the control valve with an input of one hundred percent (2.5 V from the computer), which resulted in the flow rate being decreased to zero. The creation of open loop data is shown graphically in Figure 4, along with its recording, as seen in the figure. The diagram has been drawn in a schematic format. It is essential to keep in mind that the computer will be the origin of the input signal that will be applied to the process by means of the NI myRIO-1900, and that the matching signals from the flow sensors will be supplied back to the computer via the same route, i.e. via the myRIO. Both of these facts are important to keep in mind. Figure 5 also includes a block diagram, which presents the many structural components that are involved in the estimation and verification of process dynamics. This figure may be seen displaying the information. It is possible to deduce from this figure that the voltage input that is produced by the personal computer is sent to the pneumatic control valve by way of myRIO and a combination of a voltage to current converter and a current to potential converter. This is done in order to achieve the correct potential at the pneumatic control valve. In the following sections, a detailed description and inventory of the components that were used will be provided.

The scenario shown in figure 6 is representative of what often occurs when there is a shift in the input voltage of 1.75 V. This particular scenario has also been selected to serve as the nominal example for the study being conducted. Table 1 displays the estimated transfer function that describes the relationship between a change in the applied input and a change in the flow rate. Several case examples are presented that illustrate the use of this function. This table makes it very easy to come to the conclusion that the open loop dynamics of the process are extremely dependent on the input and the operating point of the system. As a result, they exhibit a pattern of behaviour that is riddled with high levels of uncertainty, which can be deduced from the fact that they display such a pattern. It is presumed that the process exhibits first order dynamics, which are differentiated by a static gain (K) and a temporal constant. This is the working hypothesis (T). In spite of this, the values that various aspects of the world take on from one instant in time to the next are shown to be subject to major changes. The fluctuation in static gain is far more evident, even for very little variations in the input signal.

Figure 4: Schematic Diagram for Input Application and Data Collection

Figure 5: Block Diagram for Process Dynamics Estimation

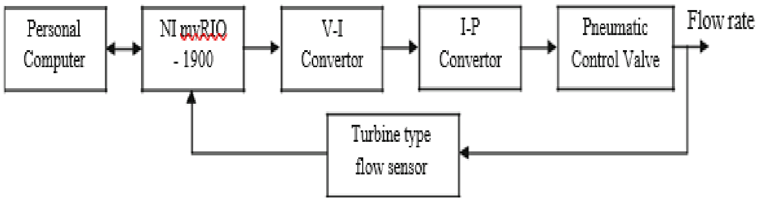


Figure 6: Actual and Estimated Flow Rate for the Estimation of System Transfer Function

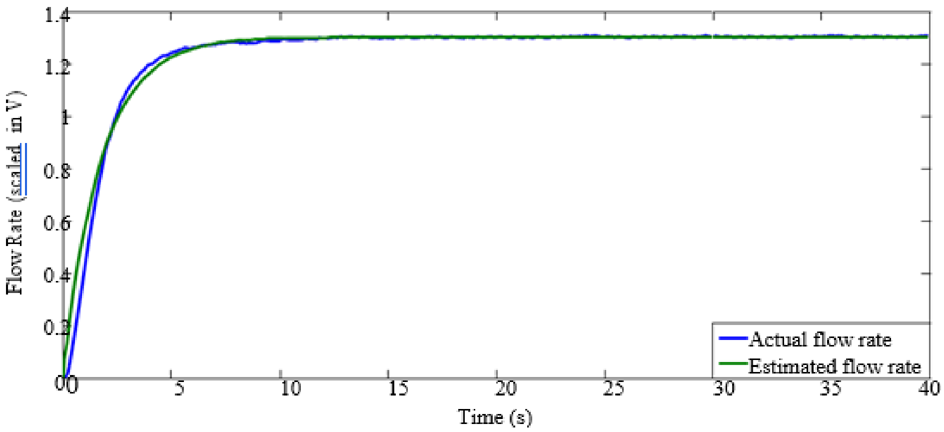


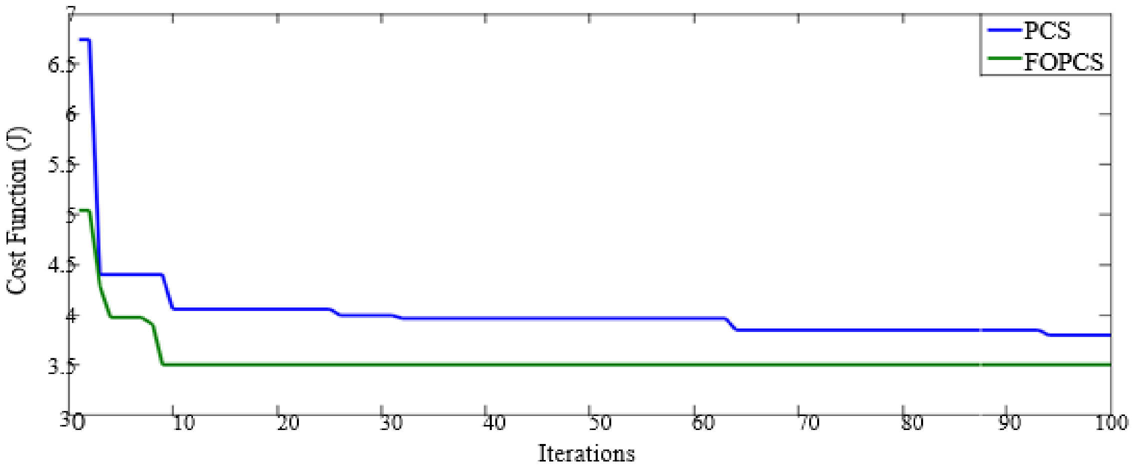
Table 1: Plant Parameters Values for Different Operating Points

S.no.	Input change (V)	Static gain (K)	Time constant (T)
1	− 1.71	− 0.671	1.745
2	− 1.80	− 0.744	1.770
3	− 1.85	− 0.795	1.741

3.3. Tuning of PCS and FOPCS

In this section, we will discuss the optimization of the parameters for both PCS and FOPCS. Both of these systems will be discussed. You are welcome to have a look at Figure 1, which provides an overview of the FOPCS block diagram. It is possible to determine, just by glancing at this graphic, that the FOPCS controller makes use of not one but two FOPI controllers. These FOPI controllers may be differentiated from one another by making use of a total of three distinguishing characteristics. The components of the cost function, which is the optimization function that is being evaluated, are the integral of absolute error (IAE) and the integral of absolute rate of controller output. Both of these variables are integrals (IARCO). The cost function, which is represented by the symbol J, is defined as the algebraic summing of the IAE and IARCO variables in such a way that each variable gets the same amount of weight. The following is an analysis of how valuable IAE and IARCO are:

Figure 7: Cost Fucntion Versus Iteration Curve for PCS and FOPCS Obtained Through BSA



4.0 Analysis of Results

To evaluate and assess the performance of PCS and devel-oped FOPCS, extensive runtime studies were carried out on a laboratory scale process control trainer. These runtime stud-ies include flow regulation in a controllable flow stream for nominal case and for different setpoint values. Since chang-ing the setpoint may change the dynamics as well as the parameters of the plant, this study was essential to gauge the performance of PCS and FOPCS controllers. In view of this, first the nominal case, where the control schemes were orig-inally tuned and then other operating conditions were taken into account. Setpoint tracking and the disturbance rejection studies were carried out in a single run since the control structures under investigation are capable of handling both of these problems

Figure 9a–c, respectively, illustrates the controller outputs of GC1 and GC2 as well as the aggregate controller output that is applied to the system. Because of these figures, it is very easy to see that initially (for setpoint tracking), u1 is the primary contributor of u, but after the disturbance is applied, u2 is the primary contributor. This is a very important distinction to make. This is because these data make it extremely straightforward to recognise that u1 is the key contributor to u. The reason for this is because these data. This is made very evident when we take a look at these figures. The fact that u1 is in charge of servo action and u2 is in charge of regulatory action made the appropriate course of action quite evident.

Figure 9: Controller Output Variation (a) G_{C1}, (b) G_{C2}, (c) Aggregate Controller Output For Nominal Case

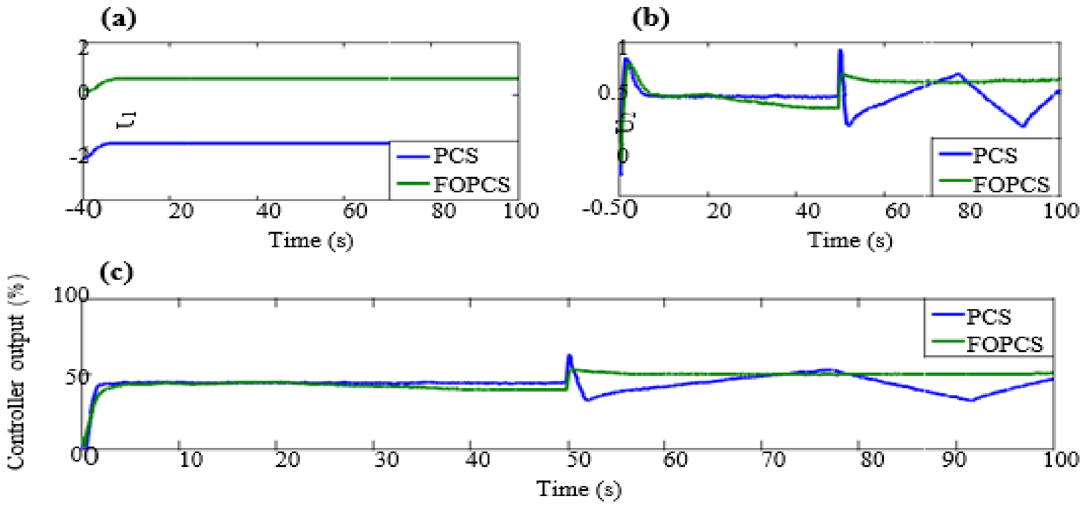


Figure 10: A Comparison of the Performance of PCS and FOPCS for the Nominal Example is Shown Graphically in Figure 10, Which is a Depiction of the Comparison in Graphical Form

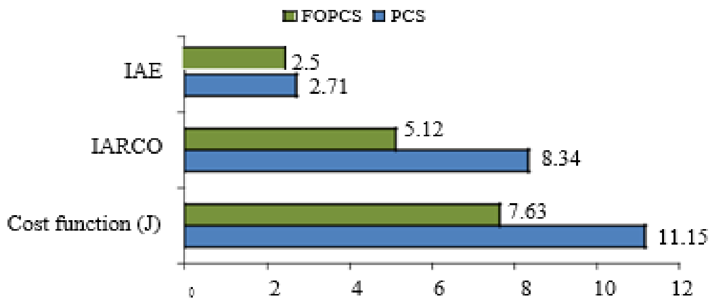


Figure 14: (a) Process Variable Variation Obtained by PCS and FOPCS for Robustness Test (case-II), (b) Estimated Output Variation for Robustness Test (case-II)

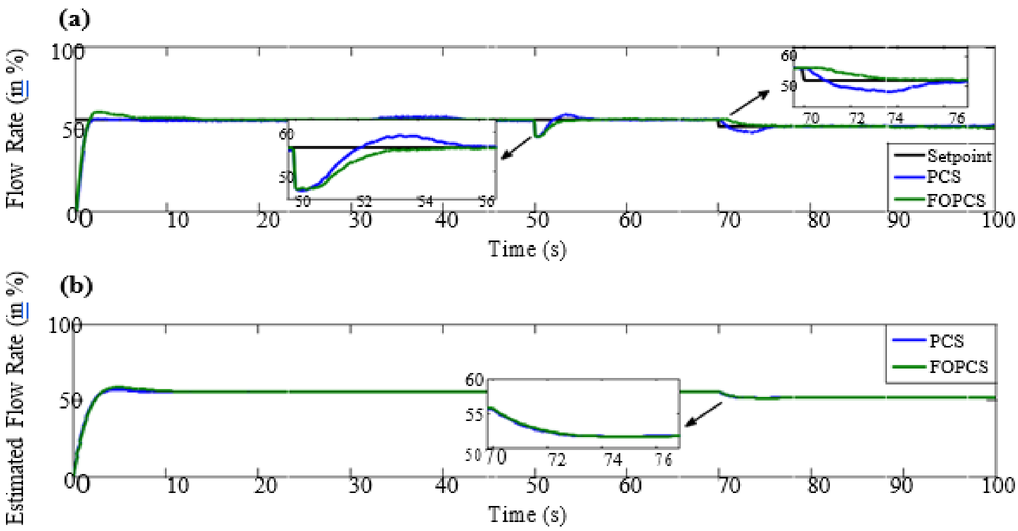


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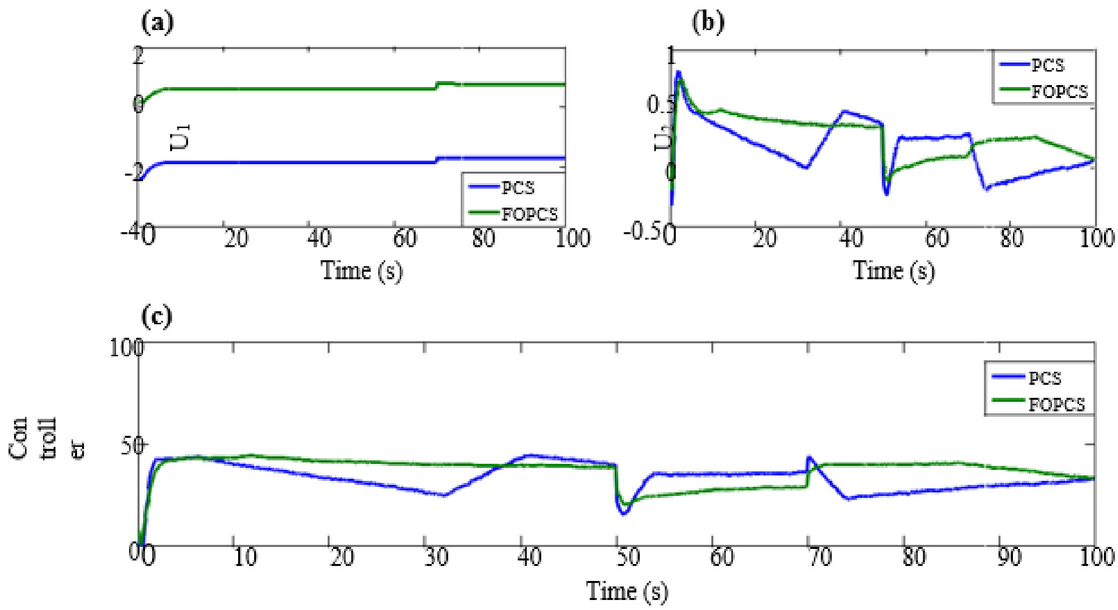
Figure 14a depicts the variation that happens in the regulated process variable that is related to the flow rate in the fluid line. This variation can be seen in the figure. This figure makes it possible to draw the conclusion that the reaction of the FOPCS controller is still superior to the response of the PCS controller in all of the parameters that were taken into consideration. This conclusion can be reached by considering the fact that it is possible to draw this conclusion. When it comes to managing the disturbance rejection at t = 50 s and the monitoring of the new setpoint value, which is 1.3 V at t = 70 s, the normal PCS controller is unable to compete with the FOPCS controller because of its inability to monitor the new setpoint value. The FOPCS controller is able to manage each of these responsibilities with an exceptional level of success.

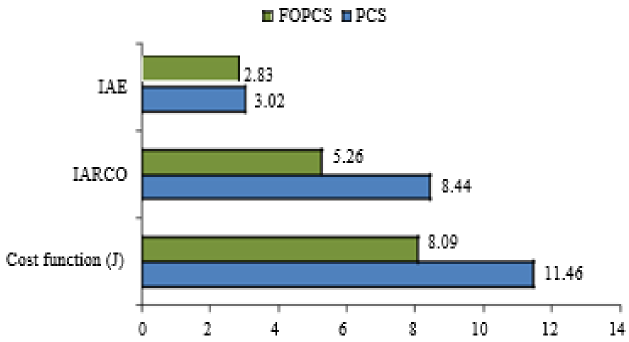
Figure 15: Controller Output Variation (a) G_{C1}, (b) G_{C2}, (c) Aggregate Controller Output for Case-II



This also illustrates that PCS is decoupling in terms of the servo and regulatory actions that it is doing. In addition to this, the outputs of the corresponding controllers are indicated in This also shows that PCS is decoupling in terms of the servo and regulatory measures that it is doing, as seen by the fact that it is doing these things. In addition, the outputs of the required controllers are shown in figure 15, which may be found by clicking this link. A quick look at this chart makes it abundantly clear that there was not the slightest bit of fluctuation in the output that the controller was producing for GC1 at the time t = 50 seconds. This is because GC1 is not charged with giving the controller output until after an adjustment has been made to the setpoint. The reason for this is due to the fact that.

Higher tracking, regulatory, and resilience performance was shown by the FOPCS in the flow rate control loop, which had nonlinear and unpredictable dynamics. The aggregate cost function J validates the efficacy of FOPCS as well; the value it returns for FOPCS is 8.08, whereas the value it returns for PCS is 11.47. This leads to an increase of 29.45 percentage points in overall performance. Figure 16 is a graphical representation of the comparison of the controllers' performance that was created with the intention of making the data more readily comprehended.

Figure 16: Bar Graph for the Quantitative Comparison between PCS and FOPCS for Different Setpoint Case-II



5.0 Conclusion

Building and analysing a fractional derivative simultaneous control structure (FOPCS) has been done with the intention of enhancing the robustness of flow control by employing a pneumatic control valve without diminishing the level of control performance. This was accomplished through the use of fractional order parallel control structures. This article contains a copy of the aforementioned work. Because the presence of a pneumatic control valve renders the process nonlinear and unpredictable, FOPCS is being examined as a possible solution to this issue. The traditional parallel control structure, also known as a PCS, is getting an update in the form of the proposed field-oriented parallel control structure (FOPCS). The original purpose of the PCS was to divorce the servo response from the systematic strategy in the control loop. This more traditional PCS was designed to contribute to the FOPCS that was originally presented. Two controllers, one of which is normally a controller, are responsible for the implementation of the system in a typical PCS. These controllers manage the system's operation. This structure successfully decouples the servo and regulatory responses, but it may not be able to give a greater level of robustness inside the control loop. . In addition, the inclusion of fractional order calculus in conventional PCS has been made possible. In addition to this, the standard PCS has been updated to include the fractional order calculus. The assessment was carried out with the assistance of three separate performance indicators, namely the integral of absolute error, the integral of the absolute rate of controller output, and the algebraic summation of the aforementioned two, which is also referred to as the cost function (J). The fact that the values of the considered performance indices are lower for FOPCS than they are for PCS suggests that FOPCS is more capable of handling parametric uncertainties without compromising the control performance. This conclusion is drawn from the results of the experimental studies that were carried out. This is due to the fact that FOPCS values for certain performance metrics are much lower. In general, one can reach the conclusion that FOPCS improves the robustness, along with increased regulatory performance and smoother controller output production. This is one of the reasons why this conclusion is possible. [Further citation is required] [Further citation is required] Additionally, the research that was done for this study may be extended in order to test recommended FOPCS on an industrial level facility in order to evaluate the capabilities of the system. This would be done in order to examine the capabilities of the system. In addition, other possible advancements to the control system that may be investigated include the use of intelligent methods such as neural networks and fuzzy logic. These are only two examples. In addition to this, the FOPCS that has been shown is possible to be extended to multivariable systems that have strong interactions between one or more loops. This is a possibility since the FOPCS has been described.

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