Optimal PID-Control for First Order Plus Time Delay Systems & Verification of the SIMC Rules

Chriss Grimholt    Sigurd Skogestad∗

Department of Chemical Engineering, Norwegian University of Science and Technology (NTNU), Trondheim, Norway
∗e-mail: skoge@ntnu.no

Abstract: Optimal cascade PID-settings are found for first-order with delay processes for specified levels of robustness ($M_s$-value) and compared with a modified SIMC-rule for PID-control (Figure 1). Optimality (performance) is defined in terms of the integrated absolute error for combined step changes in load output and load input disturbances. The SIMC method for PID-controller tuning (Skogestad, 2003) has already found wide industrial usage. For a first-order system with time delay,

$$G(s) = \frac{k}{(\tau_1 s + 1)} e^{-\theta s}$$

the SIMC-rules are given as

$$K_C = \frac{1}{k} \frac{\tau_1}{\tau_c + \theta}$$

$$\tau_I = \min\{\tau_1, 4(\tau_c + \theta)\}$$

and results in a PI-controller. If a PID-controller is desired for a first-order system, we propose to introduce derivative action with $\tau_D = \theta/3$ to counteract the time delay $\theta$. With the SIMC-rule, the robustness level is adjusted by changing the tuning parameter $\tau_c$. The added derivative action was found to give surprisingly good settings with near Pareto-optimal performance. However, to take advantage of this increase in performance the tuning parameter $\tau_c$ should be reduced to about half of the recommended value $\tau_c = \theta$.

Keywords: Optimality, PID controllers, Pareto-optimal, robustness, performance evaluation.

REFERENCES

Fig. 1. Pareto-optimal trade-off between robustness ($M_s$) and performance ($J$) with PI and PID control for four lower order processes.