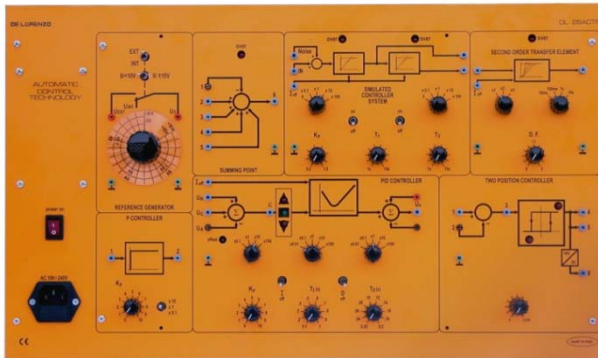




BOARD FOR THE STUDY OF THE AUTOMATIC CONTROL TECHNOLOGY



DL 26ACTR

The board covers the following topics and experiments:

- 1st order process simulator
- 2nd order process simulator
- High order process simulator
- PID controller
- P controller positive and negative
- I controller (integrators)
- D controller (derivators), negative (negative zero) and positive (positive zero)
- 5 input adder
- ON-OFF controller with hysteresis

SIMULATED CONTROLLED SYSTEM

- It allows the simulation of different processes, such as: 1st and 2nd order processes, proportional (P) action processes, integral (I) action processes, double integral (I2) action processes.
- Input summing point for controlling variable (y) and noise variable (z).
- Signal voltage range: -10V, ..., +10V
- Coefficient of the proportional action of the process
- $K_P = 0.2$ (attenuation)1.5 (amplification)
- Time constant $T_1 = 0.1 \dots 1000$ s
- Time constant $T_2 = 0.1 \dots 1000$ s
- Reset input for the restoration of the initial conditions
- Coarse setting through rotary switches
- Potentiometer fine setting
- Led indicators of over-range

PID CONTROLLER

- Standard industrial controller that can be used as P, PI,PD or PID controller in the closed loop automatic control systems.
- Input summing node for two different reference variables U_R and U_C and for one controlled variable U_A .
- Signal voltage range: -10V +10V
- Parameters of the controller continuously adjustable
- Proportional gain $K_p = 0 \dots 1000$
- Time of the integral action $T_I = 1\text{ms} \dots 100\text{s}$
- Time of the derivative action $T_D = 0.2\text{ms} \dots 20\text{s}$
- Reset input of the integral controller
- Output summing node to add or subtract noise variables
- Measurement terminal for the error signal
- Adjustment screw for the output offset
- Three led indicator of the sense of deviation
- Coarse and fine adjustment of the proportional gain K_p , of the time of the integral action T_I and of the time of the derivative action T_D
- Input I_{off} for resetting the I controller

TWO POSITION CONTROLLER

- Two position controller for discontinuous closed loop control systems.
- It is provided with an input summing point to which the reference variable (non inverting input) and the controlled variable (inverting input) are connected.
- By means of two led the binary state of the controller, whose hysteresis can be changed, is visualized.
- The controller is provided with two binary outputs at different voltages.
- Input summing point
- Signal voltage range: -10V, ..., +10V
- Output voltages: 0/+5 V ; 0/+10 V
- Adjustable hysteresis: $0 \dots \pm 2.5$ V

P CONTROLLER

- Proportional action controller suitable for the closed loop continuous control systems.
- Signal voltage range: -10V, ..., +10V
- Proportional gain $K_p = 0 \dots 100$
- Three position switch coarse setting
- Potentiometer fine setting



SECOND ORDER TRANSFER ELEMENT

- It allows to analyze the behaviour of an element with proportional transfer function able to oscillate, with a delay of the second order, both in the time domain and in the frequency domain.
- Signal voltage range: -10V, ..., +10V
- Gain factor = 1
- Time constant $T = 10 \text{ ms} \dots 30 \text{ s}$, selectable through two rotary switches
- Damping coefficient $d = 0 \dots 3$, with potentiometer setting
- Reset input for the restoration of the initial conditions
- Led indicators of over-range

LIST OF EXPERIMENTS

- P-type process
- I-type process
- I2-type process
- 1st order process
- Higher than 1st order process
- P controller
- I controller
- D controller
- PI controller
- PD controller
- PID controller
- P control, P-type process
- P control, 1st and higher order processes
- 2nd order I control, I-type processes
- Ziegler-Nichols dynamic method
- Chien-Hrones-Reswick static method
- 2 position controller, 1st order process
- 2 position controller, delayed feedback, 2nd order process
- 2 position controller, elastic feedback, 2nd order process

SUMMING POINT - 5 INPUTS

- Five input summing point; three of them, non inverting, can be used in the realization of particular configurations of the controller, using separately the elements P, I and D; the remaining inputs, one inverting and one non inverting, can be used to add the noise variables.
- Signal voltage range: -10V, ..., +10V
- Gain factor = 1
- Led indicator of over-range

OPTION

On request, the board can be provided complete with data acquisition and processing software in Labview environment.

The software will guide students to the performance of the experiments and will process the data to draw the relevant graphs. The software (DL ACTSW) needs an interface for connection to the board (DL 1893).

