

Making robots balance

Part 3



What are we doing today?

- today we recap the P controller, and what it means
- we then add two more ingredients to our 'artificial brain' that we are putting into our robot: the I controller and D controller
- by mixing these three ingredients we will get our 'final' brain, a PID controller, a brain that is used practically everywhere, in the whole world

Our purposes

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- have fun

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- understand the world a bit better

Our purposes

- have fun
- understand the world a bit better
- see that math is useful

What is going to happen in today's part

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- recall what is the “P controller”

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- recall what is the “P controller”
- introduce the “I and D controllers”

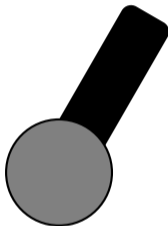
What is going to happen in today's part

- recall what is the “P controller”
- introduce the “I and D controllers”
- connect I and D with useful math concepts

Connecting things

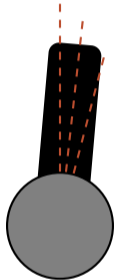
- let's recall what the P controller was, and how we arrived to it

Towards the P controller: our first heuristic



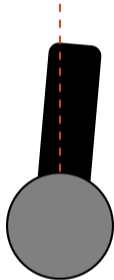
⇒ spin the wheels as fast as possible clockwise

Towards the P controller: our second heuristic



⇒ depending on the zone, spin the wheels more or less fast

The P (i.e., proportional) controller



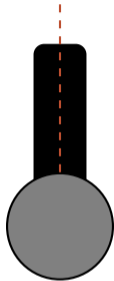
\Rightarrow speed of the wheels = $P \cdot$ angular error

Remember: P is a design choice!

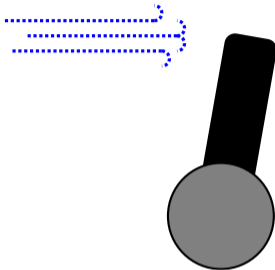
- P small implies a 'gentle' control action
- P big implies an 'aggressive' control action

- but our brain is not complete if we make it only using the P ingredient
- let me show you what I mean:
- the “P controller” brain we put inside the robot makes the wheels move so that the robot stays upright
- what is the P controller doing, actually? well, the more tilted the robot is, the more the wheels push
- now remember: I may be more or less aggressive, that means choosing P bigger or smaller
- but pretend to be in the open space now, and that there is some wind that is keeping blowing and pushing just a tiny bit the robot
- you can simulate it by using a hairdryer – try!
- anyway, what happens with the wind? the wind pushes, and the P controller reacts
- the wind makes a force, and the P controller makes a force too
- whenever the two forces are equal, then we get an equilibrium
- but at the equilibrium the robot is not perfectly vertical, and thus it is not how I would like it to be
- somehow the “P controller” brain by itself is not “smart enough” to realize that there is this wind that is disturbing, and thus it cannot eliminate its effects
- let's see this through an animation

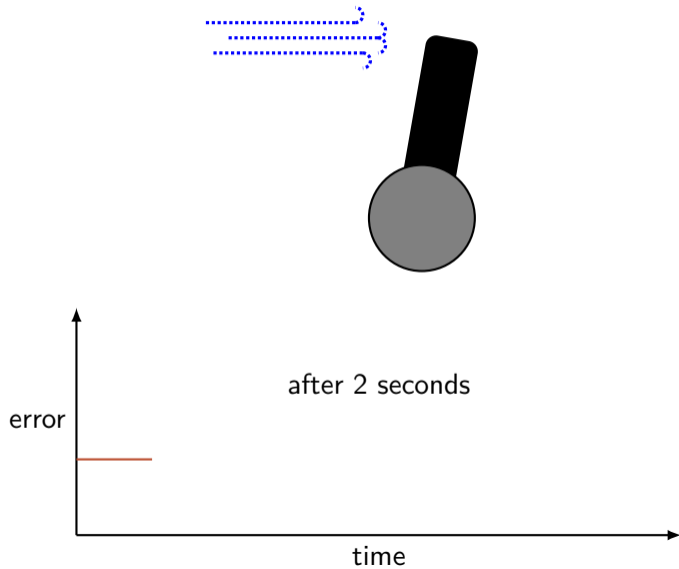
No wind = no problems



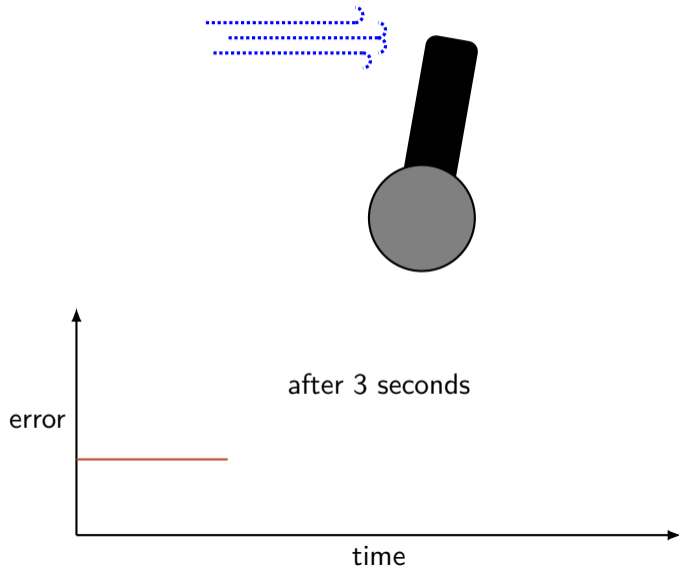
Some wind = some problems



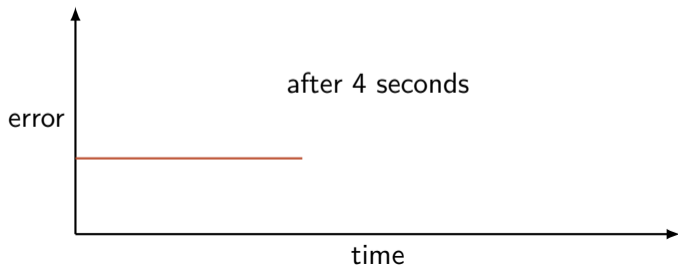
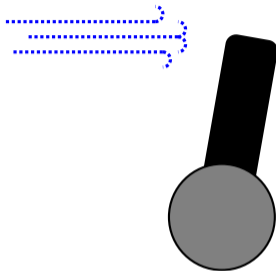
Some wind = some problems



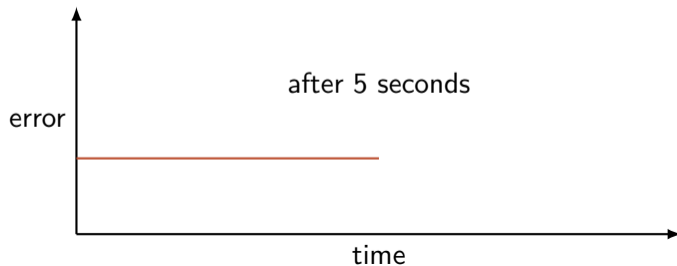
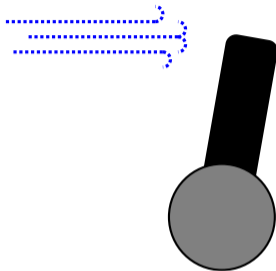
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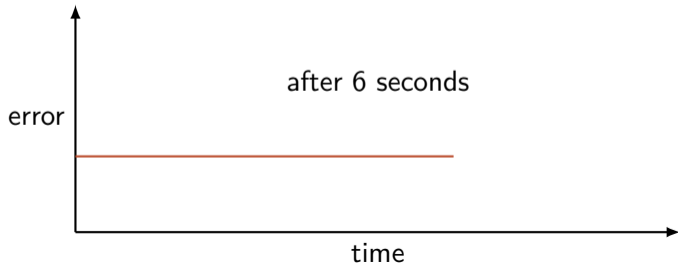
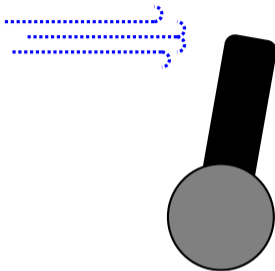
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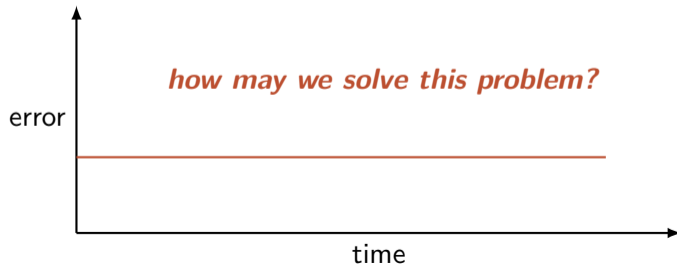
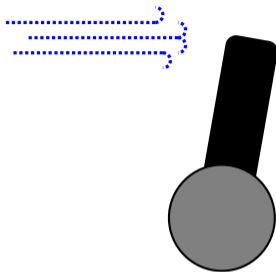
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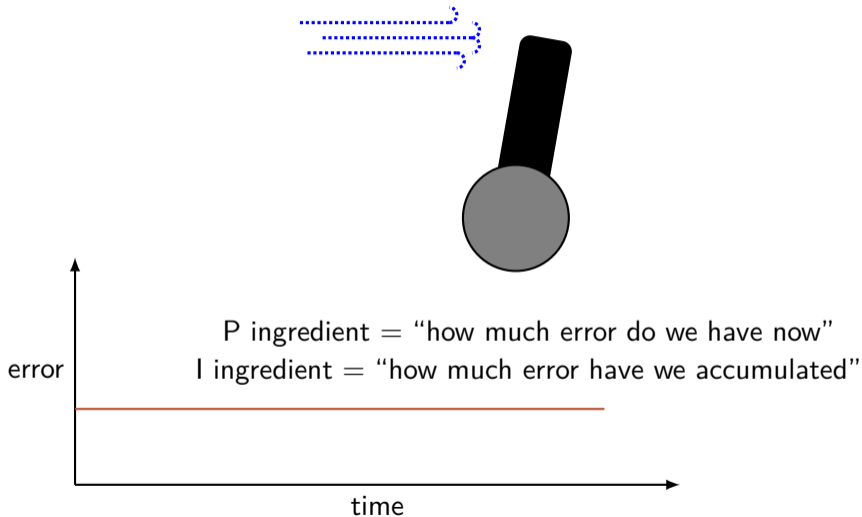


Discussion time!



- got some intuition? shared it with your friends?
- let's see if we have the same idea!
- let's see if you discovered the I controller by yourself!

The I (integral) ingredient: consider the past history of the error!



- but, as before, how do we design I ?
- to understand we should ask ourselves: what is the effect of having different I s?
- if I put $I =$ a tiny tiny number, what is going to happen?
- if I put $I =$ a huge number, what is going to happen?
- let's have a chat all together, and see what we think about this

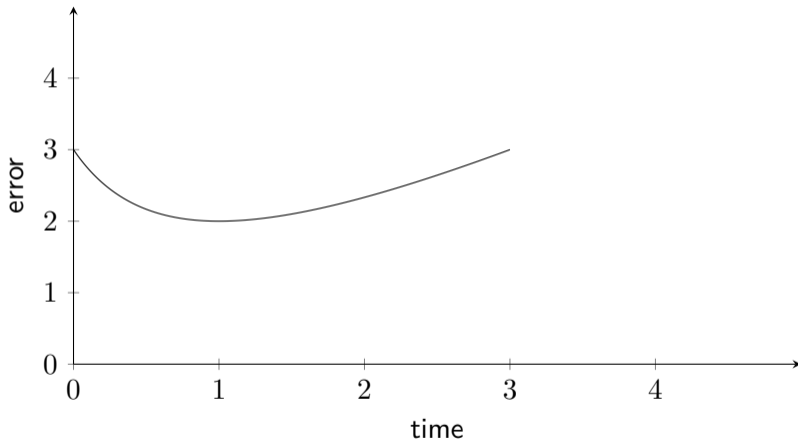
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- if I put $I =$ a tiny tiny number, what is going to happen?
- if I put $I =$ a huge number, what is going to happen?

- good! So, the effects of choosing I are kind of similar as before for P , but not quite the same: the bigger I , the more we use the past to decide what to do now
- uhm, using the past errors to decide what to do now. . . and may we also use the future errors to decide what to do now? Can we forecast which errors we are going to make in the future?

The D (derivative) ingredient: consider the future errors!

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- cool, now we have the P-part to consider the error (that is how much the robot is tilted) now, in the past and the future! Let's combine these ingredients into one controller now!
- what we will achieve then is called the PID-controller, because it contains a proportional, an integral and a derivative part!

Combing all the ingredients: the PID-controller!

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my action =

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my action = $P \cdot$ current error

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my action = $P \cdot \text{current error} + I \cdot \text{area of past error}$

Combing all the ingredients: the PID-controller!

my action = $P \cdot \text{current error} + I \cdot \text{area of past error} + D \cdot \text{slope of current error}$

- let's make a summary:
- P is how much I react to the current error
- I is a memory term: if I have been making errors for some time, then compensate for them
- D is trying to compensate for what I think the error will be in the next future. But watch out, predicting the future is a challenging thing, and the D term may make your brain quite nervous; try later on to put D big and you will see

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- D = slope = “derivative”. Symbol: $\frac{d}{dt}e(t)$

- and now I leave you with playing with the robot; choose different P s, different I s, and different D s, and see what happens
- my proposal: try now to disturb the robot by gently poking it, placing it on a different surface, or attaching some weight to it! let's see who finds the PID combination that resists the most!

- so, now I let you do, and close this series video - I hope you liked it and that in the why you learned something about the most common automatic control strategy, the PID controller!
- please feel free to keep in touch, and good luck with all your wonderful projects!
- bye!

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