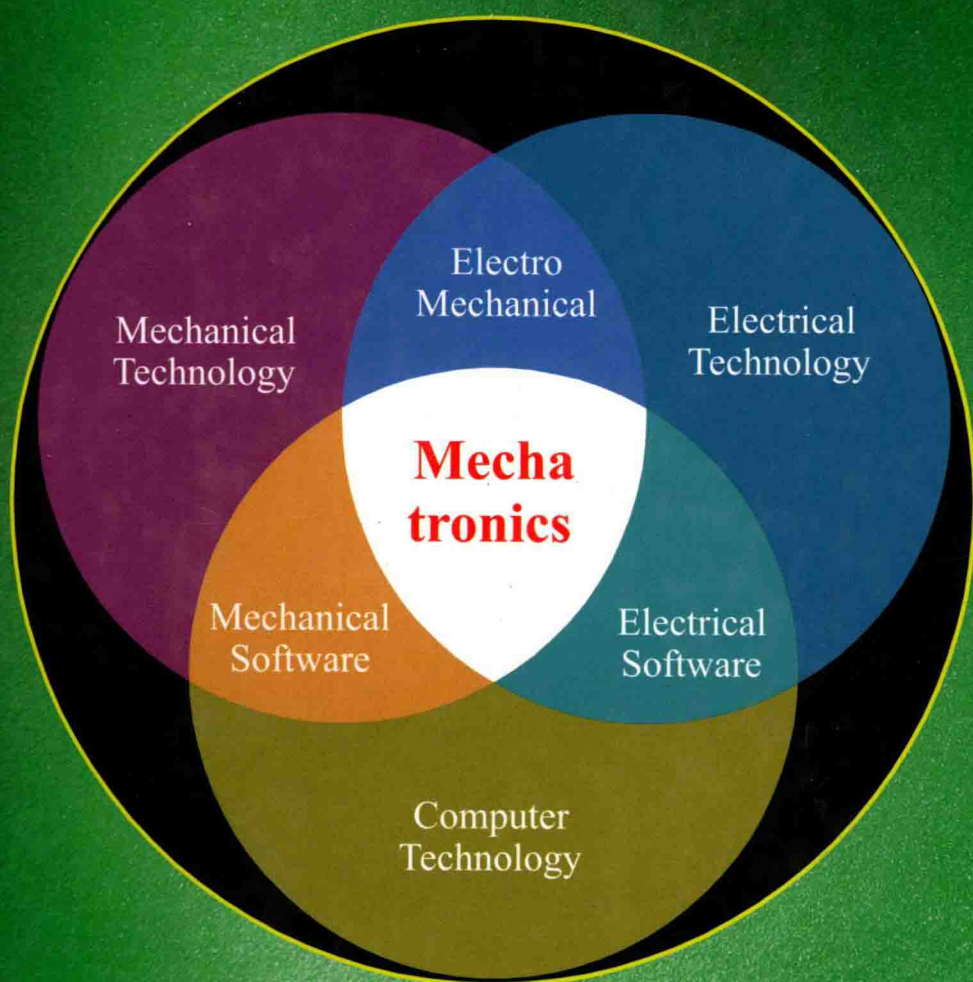


Second Edition

MECHATRONICS

with Experiments



Sabri Cetinkunt



WILEY

SECOND EDITION

MECHATRONICS

with Experiments

SABRI CETINKUNT

University of Illinois at Chicago, USA

WILEY

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MECHATRONICS

PREFACE

This second edition of the textbook has the following modifications compared to the first edition:

- Twelve experiments have been added. The experiments require building of electronic interface circuits between the microcontroller and the electromechanical system, writing of real-time control code in C language, and testing and debugging the complete system to make it work.
- All of the chapters have been edited and more examples have been added where appropriate.
- A brief tutorial on MATLAB[®]/Simulink[®]/Stateflow is included.

I would like to thank Paul Petralia, Tom Carter and Anne Hunt [Acquisitions Editor, Project Editor and Associate Commissioning Editor, respectively] at John Wiley and Sons for their patience and kind guidance throughout the process of writing this edition of the book.

Sabri Cetinkunt
Chicago, Illinois, USA
March 19, 2014

ABOUT THE COMPANION WEBSITE

This book has a companion website:

www.wiley.com/go/cetinkunt/mechatronics

The website includes:

- A solutions manual

CONTENTS

PREFACE **xi**

ABOUT THE COMPANION WEBSITE **xii**

CHAPTER 1 INTRODUCTION 1

- 1.1 Case Study: Modeling and Control of Combustion Engines **16**
 - 1.1.1 Diesel Engine Components **17**
 - 1.1.2 Engine Control System Components **23**
 - 1.1.3 Engine Modeling with Lug Curve **25**
 - 1.1.4 Engine Control Algorithms: Engine Speed Regulation using Fuel Map and a Proportional Control Algorithm **29**
- 1.2 Example: Electro-hydraulic Flight Control Systems for Commercial Airplanes **31**
- 1.3 Embedded Control Software Development for Mechatronic Systems **38**
- 1.4 Problems **43**

CHAPTER 2 CLOSED LOOP CONTROL 45

- 2.1 Components of a Digital Control System **46**
- 2.2 The Sampling Operation and Signal Reconstruction **48**
 - 2.2.1 Sampling: A/D Operation **48**
 - 2.2.2 Sampling Circuit **48**
 - 2.2.3 Mathematical Idealization of the Sampling Circuit **50**
 - 2.2.4 Signal Reconstruction: D/A Operation **55**
 - 2.2.5 Real-time Control Update Methods and Time Delay **58**
 - 2.2.6 Filtering and Bandwidth Issues **60**

- 2.3 Open Loop Control Versus Closed Loop Control **63**
- 2.4 Performance Specifications for Control Systems **67**
- 2.5 Time Domain and S -domain Correlation of Signals **69**
- 2.6 Transient Response Specifications: Selection of Pole Locations **70**
 - 2.6.1 Step Response of a Second-Order System **70**
 - 2.6.2 Standard Filters **74**
- 2.7 Steady-State Response Specifications **74**
- 2.8 Stability of Dynamic Systems **76**
 - 2.8.1 Bounded Input–Bounded Output Stability **77**
- 2.9 Experimental Determination of Frequency Response **78**
 - 2.9.1 Graphical Representation of Frequency Response **79**
 - 2.9.2 Stability Analysis in the Frequency Domain: Nyquist Stability Criteria **87**
- 2.10 The Root Locus Method **89**
- 2.11 Correlation Between Time Domain and Frequency Domain Information **93**
- 2.12 Basic Feedback Control Types **97**
 - 2.12.1 Proportional Control **100**
 - 2.12.2 Derivative Control **101**
 - 2.12.3 Integral Control **102**
 - 2.12.4 PI Control **103**
 - 2.12.5 PD Control **106**
 - 2.12.6 PID Control **107**
 - 2.12.7 Practical Implementation Issues of PID Control **111**
 - 2.12.8 Time Delay in Control Systems **117**
- 2.13 Translation of Analog Control to Digital Control **125**
 - 2.13.1 Finite Difference Approximations **126**
- 2.14 Problems **128**

**CHAPTER 3 MECHANISMS FOR
MOTION TRANSMISSION 133**

- 3.1 Introduction **133**
- 3.2 Rotary to Rotary Motion
Transmission Mechanisms **136**
 - 3.2.1 Gears **136**
 - 3.2.2 Belt and Pulley **138**
- 3.3 Rotary to Translational Motion
Transmission Mechanisms **139**
 - 3.3.1 Lead-Screw and
Ball-Screw
Mechanisms **139**
 - 3.3.2 Rack and Pinion
Mechanism **142**
 - 3.3.3 Belt and Pulley **142**
- 3.4 Cyclic Motion Transmission
Mechanisms **143**
 - 3.4.1 Linkages **143**
 - 3.4.2 Cams **145**
- 3.5 Shaft Misalignments and
Flexible Couplings **153**
- 3.6 Actuator Sizing **154**
 - 3.6.1 Inertia Match Between
Motor and Load **160**
- 3.7 Homogeneous Transformation
Matrices **162**
- 3.8 A Case Study: Automotive
Transmission as a "Gear
Reducer" **172**
 - 3.8.1 The Need for a
Gearbox
"Transmission" in
Automotive
Applications **172**
 - 3.8.2 Automotive
Transmission: Manual
Shift Type **174**
 - 3.8.3 Planetary Gears **178**
 - 3.8.4 Torque Converter **186**
 - 3.8.5 Clutches and Brakes:
Multi Disc Type **192**
 - 3.8.6 Example: An
Automatic
Transmission Control
Algorithm **194**
 - 3.8.7 Example: Powertrain
of Articulated Trucks **196**
- 3.9 Problems **201**

**CHAPTER 4
MICROCONTROLLERS 207**

- 4.1 Embedded Computers versus
Non-Embedded Computers **207**

- 4.2 Basic Computer Model **214**
- 4.3 Microcontroller Hardware and
Software: PIC 18F452 **218**
 - 4.3.1 Microcontroller
Hardware **220**
 - 4.3.2 Microprocessor
Software **224**
 - 4.3.3 I/O Peripherals of PIC
18F452 **226**
- 4.4 Interrupts **235**
 - 4.4.1 General Features of
Interrupts **235**
 - 4.4.2 Interrupts on PIC
18F452 **236**
- 4.5 Problems **243**

**CHAPTER 5 ELECTRONIC
COMPONENTS FOR
MECHATRONIC SYSTEMS 245**

- 5.1 Introduction **245**
- 5.2 Basics of Linear Circuits **245**
- 5.3 Equivalent Electrical Circuit
Methods **249**
 - 5.3.1 Thevenin's Equivalent
Circuit **249**
 - 5.3.2 Norton's Equivalent
Circuit **250**
- 5.4 Impedance **252**
 - 5.4.1 Concept of Impedance **252**
 - 5.4.2 Amplifier: Gain, Input
Impedance, and
Output Impedance **257**
 - 5.4.3 Input and Output
Loading Errors **258**
- 5.5 Semiconductor Electronic
Devices **260**
 - 5.5.1 Semiconductor
Materials **260**
 - 5.5.2 Diodes **263**
 - 5.5.3 Transistors **271**
- 5.6 Operational Amplifiers **282**
 - 5.6.1 Basic Op-Amp **282**
 - 5.6.2 Common Op-Amp
Circuits **290**
- 5.7 Digital Electronic Devices **308**
 - 5.7.1 Logic Devices **309**
 - 5.7.2 Decoders **309**
 - 5.7.3 Multiplexer **309**
 - 5.7.4 Flip-Flops **310**
- 5.8 Digital and Analog I/O and
Their Computer Interface **314**
- 5.9 D/A and A/D Converters and
Their Computer Interface **318**
- 5.10 Problems **324**

CHAPTER 6 SENSORS 329

- 6.1 Introduction to Measurement Devices **329**
- 6.2 Measurement Device Loading Errors **333**
- 6.3 Wheatstone Bridge Circuit **335**
 - 6.3.1 Null Method **336**
 - 6.3.2 Deflection Method **337**
- 6.4 Position Sensors **339**
 - 6.4.1 Potentiometer **339**
 - 6.4.2 LVDT, Resolver, and Syncro **340**
 - 6.4.3 Encoders **346**
 - 6.4.4 Hall Effect Sensors **351**
 - 6.4.5 Capacitive Gap Sensors **353**
 - 6.4.6 Magnetostriction Position Sensors **354**
 - 6.4.7 Sonic Distance Sensors **356**
 - 6.4.8 Photoelectric Distance and Presence Sensors **357**
 - 6.4.9 Presence Sensors: ON/OFF Sensors **360**
- 6.5 Velocity Sensors **362**
 - 6.5.1 Tachometers **362**
 - 6.5.2 Digital Derivation of Velocity from Position Signal **364**
- 6.6 Acceleration Sensors **365**
 - 6.6.1 Inertial Accelerometers **366**
 - 6.6.2 Piezoelectric Accelerometers **370**
 - 6.6.3 Strain-gauge Based Accelerometers **371**
- 6.7 Strain, Force, and Torque Sensors **372**
 - 6.7.1 Strain Gauges **372**
 - 6.7.2 Force and Torque Sensors **373**
- 6.8 Pressure Sensors **376**
 - 6.8.1 Displacement Based Pressure Sensors **378**
 - 6.8.2 Strain-Gauge Based Pressure Sensor **379**
 - 6.8.3 Piezoelectric Based Pressure Sensor **380**
 - 6.8.4 Capacitance Based Pressure Sensor **380**
- 6.9 Temperature Sensors **381**
 - 6.9.1 Temperature Sensors Based on Dimensional Change **381**
 - 6.9.2 Temperature Sensors Based on Resistance **382**
 - 6.9.3 Thermocouples **383**
- 6.10 Flow Rate Sensors **385**
 - 6.10.1 Mechanical Flow Rate Sensors **385**
 - 6.10.2 Differential Pressure Flow Rate Sensors **387**
 - 6.10.3 Flow Rate Sensor Based on Faraday's Induction Principle **389**
 - 6.10.4 Thermal Flow Rate Sensors: Hot Wire Anemometer **390**
 - 6.10.5 Mass Flow Rate Sensors: Coriolis Flow Meters **391**
- 6.11 Humidity Sensors **393**
- 6.12 Vision Systems **394**
- 6.13 GPS: Global Positioning System **397**
 - 6.13.1 Operating Principles of GPS **399**
 - 6.13.2 Sources of Error in GPS **402**
 - 6.13.3 Differential GPS **402**
- 6.14 Problems **403**

CHAPTER 7 ELECTROHYDRAULIC MOTION CONTROL SYSTEMS 407

- 7.1 Introduction **407**
- 7.2 Fundamental Physical Principles **425**
 - 7.2.1 Analogy Between Hydraulic and Electrical Components **429**
 - 7.2.2 Energy Loss and Pressure Drop in Hydraulic Circuits **431**
- 7.3 Hydraulic Pumps **437**
 - 7.3.1 Types of Positive Displacement Pumps **438**
 - 7.3.2 Pump Performance **443**
 - 7.3.3 Pump Control **448**
- 7.4 Hydraulic Actuators: Hydraulic Cylinder and Rotary Motor **457**
- 7.5 Hydraulic Valves **461**
 - 7.5.1 Pressure Control Valves **463**
 - 7.5.2 Example: Multi Function Hydraulic Circuit with Poppet Valves **469**
 - 7.5.3 Flow Control Valves **471**

7.5.4	Example: A Multi Function Hydraulic Circuit using Post-Pressure Compensated Proportional Valves	482
7.5.5	Directional, Proportional, and Servo Valves	484
7.5.6	Mounting of Valves in a Hydraulic Circuit	496
7.5.7	Performance Characteristics of Proportional and Servo Valves	497
7.6	Sizing of Hydraulic Motion System Components	507
7.7	Hydraulic Motion Axis Natural Frequency and Bandwidth Limit	518
7.8	Linear Dynamic Model of a One-Axis Hydraulic Motion System	520
7.8.1	Position Controlled Electrohydraulic Motion Axes	523
7.8.2	Load Pressure Controlled Electrohydraulic Motion Axes	526
7.9	Nonlinear Dynamic Model of One-Axis Hydraulic Motion System	527
7.10	Example: Open Center Hydraulic System – Force and Speed Modulation Curves in Steady State	571
7.11	Example: Hydrostatic Transmissions	576
7.12	Current Trends in Electrohydraulics	586
7.13	Case Studies	589
7.13.1	Case Study: Multi Function Hydraulic Circuit of a Caterpillar Wheel Loader	589
7.14	Problems	593

CHAPTER 8 ELECTRIC ACTUATORS: MOTOR AND DRIVE TECHNOLOGY 603

8.1	Introduction	603
8.1.1	Steady-State Torque-Speed Range, Regeneration, and Power Dumping	606

8.1.2	Electric Fields and Magnetic Fields	610
8.1.3	Permanent Magnetic Materials	622
8.2	Energy Losses in Electric Motors	629
8.2.1	Resistance Losses	631
8.2.2	Core Losses	632
8.2.3	Friction and Windage Losses	633
8.3	Solenoids	633
8.3.1	Operating Principles of Solenoids	633
8.3.2	DC Solenoid: Electromechanical Dynamic Model	636
8.4	DC Servo Motors and Drives	640
8.4.1	Operating Principles of DC Motors	642
8.4.2	Drives for DC Brush-type and Brushless Motors	650
8.5	AC Induction Motors and Drives	659
8.5.1	AC Induction Motor Operating Principles	660
8.5.2	Drives for AC Induction Motors	666
8.6	Step Motors	670
8.6.1	Basic Stepper Motor Operating Principles	672
8.6.2	Step Motor Drives	677
8.7	Linear Motors	681
8.8	DC Motor: Electromechanical Dynamic Model	683
8.8.1	Voltage Amplifier Driven DC Motor	687
8.8.2	Current Amplifier Driven DC Motor	687
8.8.3	Steady-State Torque-Speed Characteristics of DC Motor Under Constant Terminal Voltage	688
8.8.4	Steady-State Torque-Speed Characteristic of a DC Motor Under Constant Commanded Current Condition	689
8.9	Problems	691

CHAPTER 9 PROGRAMMABLE LOGIC CONTROLLERS 695

9.1	Introduction	695
-----	--------------	-----

9.2	Hardware Components of PLCs	697
9.2.1	PLC CPU and I/O Capabilities	697
9.2.2	Opto-isolated Discrete Input and Output Modules	701
9.2.3	Relays, Contactors, Starters	701
9.2.4	Counters and Timers	704
9.3	Programming of PLCs	705
9.3.1	Hard-wired Seal-in Circuit	708
9.4	PLC Control System Applications	709
9.4.1	Closed Loop Temperature Control System	709
9.4.2	Conveyor Speed Control System	710
9.4.3	Closed Loop Servo Position Control System	711
9.5	PLC Application Example: Conveyor and Furnace Control	712
9.6	Problems	714

CHAPTER 10 PROGRAMMABLE MOTION CONTROL SYSTEMS 717

10.1	Introduction	717
10.2	Design Methodology for PMC Systems	722
10.3	Motion Controller Hardware and Software	723
10.4	Basic Single-Axis Motions	724
10.5	Coordinated Motion Control Methods	729
10.5.1	Point-to-point Synchronized Motion	729
10.5.2	Electronic Gearing Coordinated Motion	731
10.5.3	CAM Profile and Contouring Coordinated Motion	734
10.5.4	Sensor Based Real-time Coordinated Motion	735
10.6	Coordinated Motion Applications	735
10.6.1	Web Handling with Registration Mark	735

10.6.2	Web Tension Control Using Electronic Gearing	738
10.6.3	Smart Conveyors	741
10.7	Problems	747

CHAPTER 11 LABORATORY EXPERIMENTS 749

11.1	Experiment 1: Basic Electrical Circuit Components and Kirchoff's Voltage and Current Laws	749
	Objectives	749
	Components	749
	Theory	749
	Procedure	751
11.2	Experiment 2: Transistor Operation: ON/OFF Mode and Linear Mode of Operation	754
	Objectives	754
	Components	754
	Theory	754
	Procedure	756
11.3	Experiment 3: Passive First-Order RC Filters: Low Pass Filter and High Pass Filter	758
	Objectives	758
	Components	758
	Theory	758
	Procedure	760
11.4	Experiment 4: Active First-Order Low Pass Filter with Op-Amps	762
	Objectives	762
	Components	762
	Theory	762
	Procedure	765
11.5	Experiment 5: Schmitt Trigger With Variable Hysteresis using an Op-Amp Circuit	766
	Objectives	766
	Components	766
	Theory	767
	Procedure	768
11.6	Experiment 6: Analog PID Control Using Op-Amps	770
	Objectives	770
	Components	770
	Theory	770
	Procedure	774
11.7	Experiment 7: LED Control Using the PIC Microcontroller	775
	Objectives	775
	Components	776

	Theory	776
	Application Software	
	Description	777
	Procedure	777
11.8	Experiment 8: Force and Strain Measurement Using a Strain Gauge and PIC-ADC Interface	780
	Objectives	780
	Components	781
	Theory	781
	Application Software	
	Description	784
	Procedure	785
11.9	Experiment 9: Solenoid Control Using a Transistor and PIC Microcontroller	787
	Objectives	787
	Components	787
	Theory	787
	Hardware	787
	Application Software	
	Description	788
	Procedure	788
11.10	Experiment 10: Stepper Motor Motion Control Using a PIC Microcontroller	790
	Objective	790
	Components	790
	Theory	790
	Application Software	
	Description	791
	Procedure	793
11.11	Experiment 11: DC Motor Speed Control Using PWM	794
	Objectives	794
	Components	794
	Theory	794
	Application Software	
	Description	795
	Procedure	796
11.12	Experiment 12: Closed Loop DC Motor Position Control	799

Objectives	799
Components	799
Theory	799
Application Software	
Description	802
Procedure	804

APPENDIX MATLAB®, SIMULINK®, STATEFLOW, AND AUTO-CODE GENERATION 805

A.1	MATLAB® Overview	805
A.1.1	Data in MATLAB® Environment	808
A.1.2	Program Flow Control Statements in MATLAB®	813
A.1.3	Functions in MATLAB®: M-script files and M-function files	815
A.1.4	Input and Output in MATLAB®	822
A.1.5	MATLAB® Toolboxes	831
A.1.6	Controller Design Functions: Transform Domain and State-Space Methods	832
A.2	Simulink®	836
A.2.1	Simulink® Block Examples	843
A.2.2	Simulink® S-Functions in C Language	852
A.3	Stateflow	856
A.3.1	Accessing Data and Functions from a Stateflow Chart	865
A.4	Auto Code Generation	876

REFERENCES 879

INDEX 883

INTRODUCTION

THE MECHATRONICS field consists of the synergistic integration of three distinct traditional engineering fields for system level design processes. These three fields are

1. mechanical engineering where the word “mecha” is taken from,
2. electrical or electronics engineering, where “tronics” is taken from,
3. computer science.

The field of mechatronics is not simply the sum of these three major areas, but can be defined as the intersection of these areas when taken in the context of systems design (Figure 1.1). It is the current state of evolutionary change of the engineering fields that deal with the design of controlled electromechanical systems. A mechatronic system is a computer controlled mechanical system. Quite often, it is an *embedded computer*, not a general purpose computer, that is used for control decisions. The word mechatronics was first coined by engineers at Yaskawa Electric Company [1,2]. Virtually every modern electromechanical system has an embedded computer controller. Therefore, computer hardware and software issues (in terms of their application to the control of electromechanical systems) are part of the field of mechatronics. Had it not been for the widespread availability of low cost microcontrollers for the mass market, the field of mechatronics as we know it today would not exist. The availability of embedded microprocessors for the mass market at ever reducing cost and increasing performance makes the use of computer control in thousands of consumer products possible.

The old model for an electromechanical product design team included

1. engineer(s) who design the mechanical components of a product,
2. engineer(s) who design the electrical components, such as actuators, sensors, amplifiers and so on, as well as the control logic and algorithms,
3. engineer(s) who design the computer hardware and software implementation to control the product in real-time.

A mechatronics engineer is trained to do all of these three functions. In addition, the design process is not sequential with mechanical design followed by electrical and computer control system design, but rather all aspects (mechanical, electrical, and computer control) of design are carried out simultaneously for optimal product design. Clearly, mechatronics is not a new engineering discipline, but the current state of the evolutionary process of the engineering disciplines needed for design of electromechanical systems. The end product of a mechatronics engineer's work is a working prototype of an embedded computer controlled electromechanical device or system. This book covers the fundamental

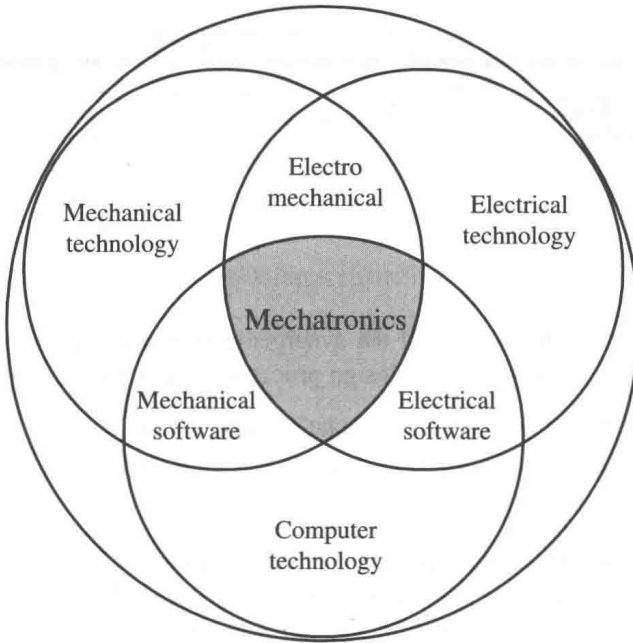


FIGURE 1.1: The field of mechatronics: intersection of mechanical engineering, electrical engineering, and computer science.

technical topics required to enable an engineer to accomplish such designs. We define the word *device* as a stand-alone product that serves a function, such as a microwave oven, whereas a *system* may be a collection of multiple devices, such as an automated robotic assembly line.

As a result, this book has sections on mechanical design of various mechanisms used in automated machines and robotic applications. Such mechanisms are designs over a century old and these basic designs are still used in modern applications. Mechanical design forms the “skeleton” of the electromechanical product, upon which the rest of the functionalities are built (such as “eyes,” “muscles,” “brains”). These mechanisms are discussed in terms of their functionality and common design parameters. Detailed stress or force analysis of them is omitted as these are covered in traditional stress analysis and machine design courses.

The analogy between a human controlled system and computer control system is shown in Figure 1.2. If a process is controlled and powered by a human operator, the operator observes the behavior of the system (i.e., using visual observation), then makes a decision regarding what action to take, then using his muscular power takes a particular control action. One could view the outcome of the decision making process as a low power control or decision signal, and the action of the muscles as the actuator signal which is the amplified version of the control (or decision) signal. The same functionalities of a control system can be automated by use of a digital computer as shown in the same figure.

The sensors replace the eyes, the actuators replace the muscles, and the computer replaces the human brain. Every computer controlled system has these four basic functional blocks:

1. process to be controlled,
2. actuators,
3. sensors,
4. controller (i.e., digital computer).

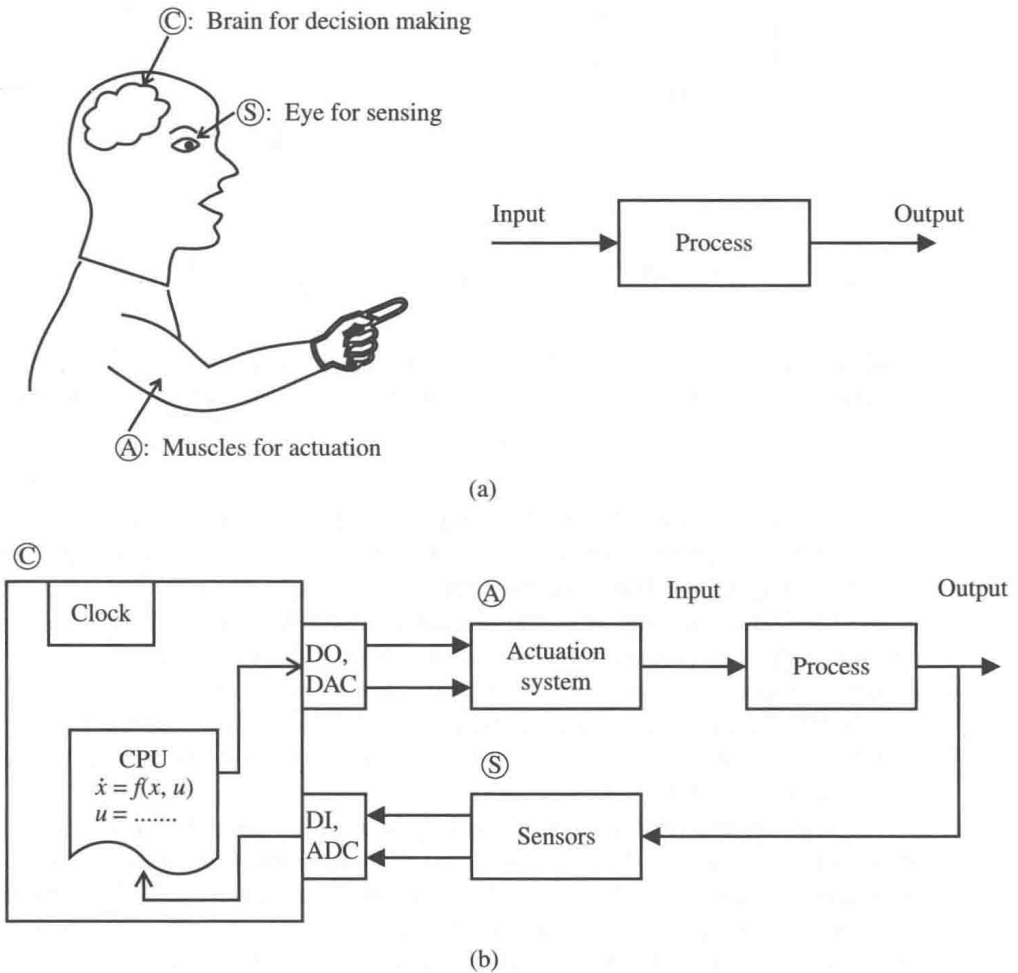


FIGURE 1.2: Manual and automatic control system analogy: (a) human controlled, (b) computer controlled.

The microprocessor (μP) and digital signal processing (DSP) technology had two impacts on control world,

1. it replaced the *existing* analog controllers,
2. prompted *new* products and designs such as fuel injection systems, active suspension, home temperature control, microwave ovens, and auto-focus cameras, just to name a few.

Every mechatronic system has some sensors to measure the status of the process variables. The sensors are the “eyes” of a computer controlled system. We study most common types of sensors used in electromechanical systems for the measurement of temperature, pressure, force, stress, position, speed, acceleration, flow, and so on (Figure 1.3). This list does not attempt to cover every conceivable sensor available in the current state of the art, but rather makes an attempt to cover all major sensor categories, their working principles and typical applications in design.

Actuators are the “muscles” of a computer controlled system. We focus in depth on the actuation devices that provide high performance control as opposed to simple ON/OFF actuation devices. In particular, we discuss hydraulic and electric power actuators in detail. Pneumatic power (compressed air power) actuation systems are not discussed.

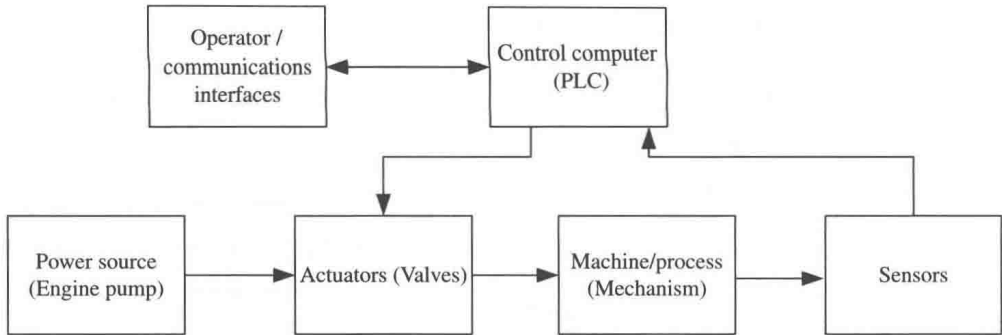


FIGURE 1.3: Main components of any mechatronic system: mechanical structure, sensors, actuators, decision making component (microcontroller), power source, human/supervisory interfaces.

They are typically used in low performance, ON/OFF type control applications (although, with advanced computer control algorithms, even they are starting to be used in high performance systems). The component functionalities of pneumatic systems are similar to those of hydraulic systems. However, the construction detail of each is quite different. For instance, both hydraulic and pneumatic systems need a component to pressurize the fluid (pump or compressor), a valve to control the direction, amount, and pressure of the fluid flow in the pipes, and translation cylinders to convert the pressurized fluid flow to motion. The pumps, valves, and cylinders used in hydraulic systems are quite different to those used in pneumatic systems.

Hardware and software fundamentals for embedded computers, microprocessors, and digital signal processors (DSP), are covered with applications to the control of electromechanical devices in mind. Hardware I/O interfaces, microprocessor hardware architectures, and software concepts are discussed. The basic electronic circuit components are discussed since they form the foundation of the interface between the digital world of computers and the analog real world. It is important to note that the hardware interfaces and embedded controller hardware aspects are largely standard and do not vary greatly from one application to another. On the other hand, the software aspects of mechatronics designs are different for every product. The development tools used may be same, but the final software created for the product (also called the application software) is different for each product. It is not uncommon that over 80% of engineering effort in the development of a mechatronic product is spent on the software aspects alone. Therefore, the importance of software, especially as it applies to embedded systems, cannot be over emphasized.

Mechatronic devices and systems are the natural evolution of automated systems. We can view this evolution as having three major phases:

1. completely mechanical automatic systems (before and early 1900s),
2. automatic devices with electronic components such as relays, transistors, op-amps (early 1900s to 1970s),
3. computer controlled automatic systems (1970s–present)

Early automatic control systems performed their automated function solely through mechanical means. For instance, a water level regulator for a water tank uses a float connected to a valve via a linkage (Figure 1.4). The desired water level in the tank is set by the adjustment of the float height or the linkage arm length connecting it to the valve. The float opens and closes the valve in order to maintain the desired water level. All the functionalities of a closed loop control system (“sensing-comparison-corrective actuation”

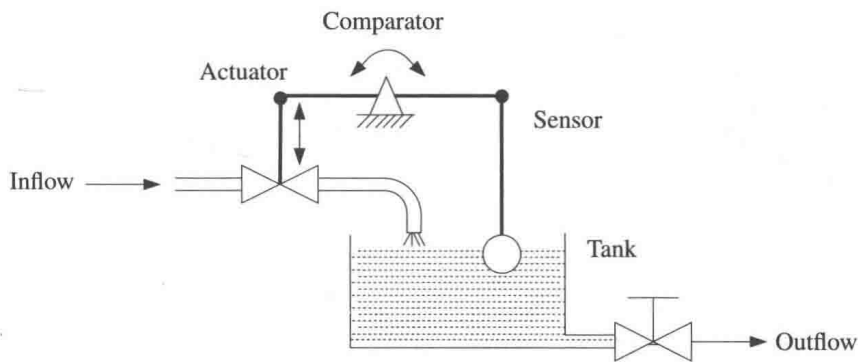


FIGURE 1.4: A completely mechanical closed loop control system for liquid level regulation.

or “sensor-logic-actuation”) may be embedded in one component by design, as is the case in this example.

Another classic automatic control system that is made of completely mechanical components (no electronics) is Watt’s flyball governor, which is used to regulate the speed of an engine (Figure 1.5). The same concept is still used in some engines today. The engine speed is regulated by controlling the fuel control valve on the fuel supply line. The valve is controlled by a mechanism that has a desired speed setting using the bias in the spring in the flywheel mechanism. The actual speed is measured by the flyball mechanism. The higher the speed of the engine is, the more the flyballs move out due to centrifugal force. The difference between the desired speed and actual speed is turned into control action by the movement of the valve, which controls a small cylinder which is then used to control the fuel control valve. In today’s engines, the fuel rate is controlled directly by an electrically actuated injector. The actual speed of the engine is sensed by an electrical sensor (i.e., tachometer, pulse counter, encoder) and an embedded computer controller decides on how

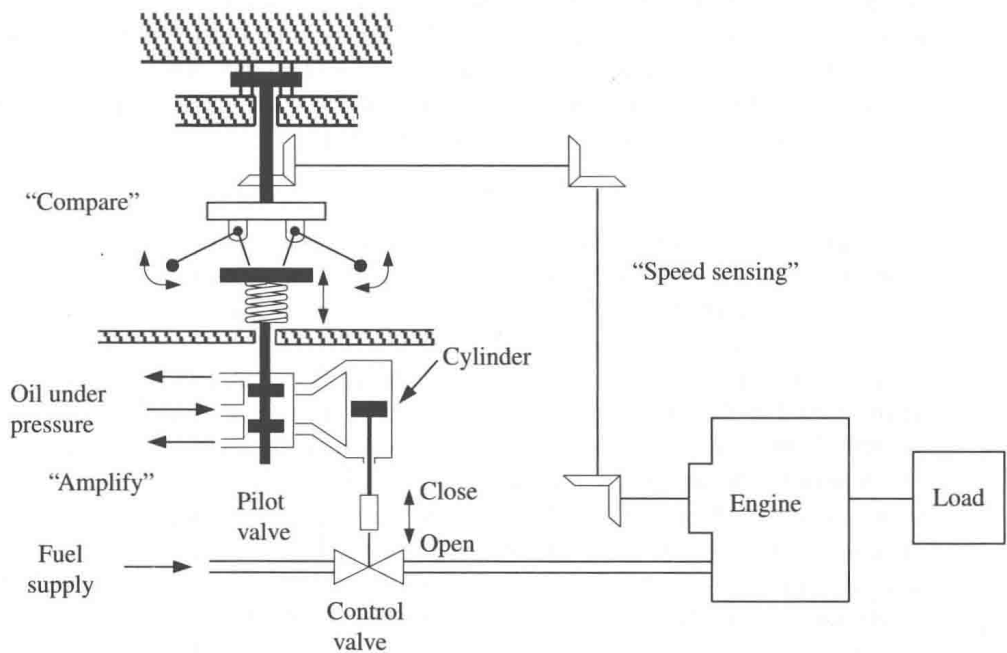


FIGURE 1.5: Mechanical “governor” concept for automatic engine speed control using all mechanical components.