Ain Shams University
Faculty of Engineering
Electrical power and Machines Dept.

Performance Evaluation of Transverse Flux Electrical Linear Motor

M.Sc. Thesis By

Eng. Ahmed Yousry Naga EL-Ibiary

Submitted in partial fulfillment of the Requirements for the M.Sc. Degree in Electrical Engineering

Supervised By

Prof. Dr. Mohamed Abd Latif Badr

Professor –Electrical Power and Machines Department Faculty of Engineering, Ain Shams University

Dr. Hany Mohamed Hasanien

Assistant Professor –Electrical Power and Machines
Department
Faculty of Engineering, Ain Shams University

Cairo 2011

APPROVAL SHEET

For The thesis:

PERFORMANCE EVALUATION OF TRANSVERSE FLUX ELECTRICAL LINEAR MOTOR

Presented by

Eng. Ahmed Yousry Naga EL-Ibiary

Submitted in partial fulfillment of the requirements for the M.Sc. degree in electrical engineering

Approved by

<u>Name</u> <u>Signature</u>

Prof. Dr. Mohamed Abd Latif Badr

Dr. Hany Mohamed Hasanien

Date: / / 2011

Examiners Committee

The thesis:

PERFORMANCE EVALUATION OF TRANSVERSE FLUX ELECTRICAL LINEAR MOTOR

Presented by

Eng. Ahmed Yousry Naga EL-Ibiary

Submitted in partial fulfillment of the requirements for the M.Sc. degree in electrical engineering

Name, title and affiliation	<u>Signature</u>
1.	
2.	
3.	
4.	

Statement

This thesis is submitted to Ain Shams University in partial fulfillment of the requirements for M.Sc. degree in Electrical Engineering.

The included work in this thesis has carried out by the author at the Electrical Power and Machines Department, Ain Shams University. No part of this thesis has been submitted for a degree or a qualification at any other university or institution.

Name : Ahmed Yousry Naga EL-Ibiary

Signature:

Date : / /2011

To

My father who is always supporting me and guide me to the success, my brother, my family and my friends who gave me strength till finishing this thesis.

Acknowledgements

The author would like to express his sincerest gratitude to **Prof. Dr. Mohamed Abd Latif Badr, and Dr. Hany Mohamed Hasanien** for the great support, excellent supervision and encouragement shown during the period of this study.

Special thanks to the Electrical Power and Machines Department, Faculty of Engineering; Ain shams University, for the great support and encouragement.

ABSTRACT

The transverse flux linear motor (TFLM) drive is nowadays one of the most interesting electric drives due to its good features that made it comparable with the other electric drives, for certain application.

In this thesis, The dynamic response of an TFLM has been obtained using information derived from the finite element analysis (FEA), which can determine the exciting coil flux-linkages as a function of both the coil current and the linear position of the mover. This work has been achieved through a digital simulation study of the mathematical model of the motor.

This model comprises a set of phase circuit equations in addition to the mechanical differential equations of motion. These equations are then solved using numerical integration of the nonlinear differential equations of the motor using the magnetization data expressed in the form of a look-up table $\Psi(x, i)$. The cubic spline interpolation is used to determine the intermediate values of the variables given by the look-up table, which, in turn, gives more accurate representation than other methods. This method is applied to compute the instantaneous values of the current and force for each phase and the total thrust force.

Early "traditional" controllers for TFLM have a simple control technique. This control technique causes ripples in the thrust force and speed profiles to take place. Since the thrust force developed by a TFLM is a nonlinear function of phase currents and mover position such ripples often occur. These ripples represent one of the main disadvantages of this type of motors.

The main contribution of this thesis is the development of an artificial neural network controller (ANN) for transverse flux linear motors for the purpose of speed control. The dynamic response of the TFLM with the proposed controller is studied during starting, and under different load disturbances. The effectiveness of the proposed artificial neural network controller is then compared to both of the conventional proportional plus integral plus derivative controller (PID), and the fine tuning of the PID controllers by using Ziegler-Nichols Rules. The dynamic response of the TFLM with this proposed controller is found to be fast and of high speed response.

LIST OF CONTENTS

	Abstract List of contents List of figures List of tables List of symbols Chapter 1: INTRODUCTION	VIII X XIII XVIII XIX
1.1	General	1
1.2	Historical Background of the Linear Motors	1
1.3	Over-view of Transverse Flux Linear Motor TFLM	3
1.4	Thesis Objectives and layout	8
	Chapter 2: PERMENAT MAGNET EXCITATION TRANSVERSE FLUX LINEAR MOTOR CONSTRUCTION AND OPERATION	
2.1	General	10
2.2	Motor construction	15
2.3	Force Production	17
2.3.1	 Principle of operation 	17
2.3.2	• Static thrust force curves	18
2.4 2.5	Analytical model of PM-type TFLM Inverter Circuits For PM-type TFLM	20 22
2.5.1	* *	23
2.3.1	 Power inverter with asymmetric full bridge 	23

Chapter 3: STATIC CHARACTERISTICS OF TRANSVERSE FLUX LINEAR MOTOR

General	26
Static Characteristics	26
Representation Of The Magnetic Curves OF	27
PM-TFLM	
Computation Of The Static Characteristics	30
 The Flux Linkage-Current Curves 	30
 Computation Of The Static Torque 	31
Curves	
Dynamic Model of TFLM	34
simulating the dynamic model of the TFLM	37
TFLM performance under constant speed	38
operation	
	Static Characteristics Representation Of The Magnetic Curves OF PM-TFLM Computation Of The Static Characteristics • The Flux Linkage-Current Curves • Computation Of The Static Torque Curves Dynamic Model of TFLM simulating the dynamic model of the TFLM TFLM performance under constant speed

Chapter 4: SPEED CONTROL OF TRANSVERSE FLUX LINEAR MOTOR

4.1	Control Theory historical review	46
4.2	Introduction to Control Systems	48
4.2.1	 Classification of Control Systems 	49
4.2.1.A	The type of operating techniques used in driving the output to a	49
	desired value	
4.2.1.B	➤ The use of feedback	50
4.2.1.C	➤ The Nature of the System	50
	Behavior	
4.2.1.D	> The Application Area	51
4.2.1.E	The Method of generating the control pulses	52
4.2.1.F	The Synchronization between the signals within the control system and input voltages	52

4.2.2	 Characteristics of Control Systems 	52
4.2.2.A	➤ Stability	52
4.2.2.B	> Accuracy	53
4.2.2.C	Speed of Response	53
4.2.2.D	Sensitivity	53
4.2.2.E	Representation	53
4.3	PID Controller	54
4.4	Tuning rules for PID controller	56
4.5	Ziegler-Nichols Rules for tuning PID	58
	controllers	
4.6	Artificial Intelligence based controllers	62
4.6.1	 Artificial Neural Network controller 	65
4.6.2	 Neuron Types 	67
4.6.3	 Artificial Neural Networks 	72
	Architectures	
4.6.4	 Training Algorithms 	77
4.6.5	 Control Applications of ANNs 	78
4.6.5	 ANN Simulink Block Diagram 	79
4.7	Speed control of TFLM	79
4.8	Applying PID Controller to the TFLM	84
4.9	Applying the fine tuning of the PID controller	89
	to the TFLM	
4.10	Applying Artificial Neural Network (ANN)	92
	Controller to TFLM	
4.11	The comparison between the PIDs controllers	96
4.12	The comparison between the PIDs controllers	100
	and the ANN controller.	
	Conclusion	104
	References	107
	Publications	109
	Appendix	110

LIST OF FIGURES

1.1	The configuration of the PM- TFLM.	3
1.2	The traction application of TFLM.	6
1.3	The linear compressor application of TFLM.	6
1.4	The robotics application of TFLM.	7
1.5	The elevator application of TFLM.	8
2.1	Basic configuration of TFLM.	11
2.2	The phase inductance related to the mover position.	12
2.3	Relation of MMF and generated force.	12
2.4	Configuration of TFLM with PM excitation.	13
2.5	Relation of MMF and generated force.	14
2.6	Configuration of single-phase PM- type TFLM.	16
2.7	Principle of force generation.	17
2.8	Principle of force generation.	18
2.9	The static thrust force curves of PM-type TFLM.	19
2.10	One-dimensional model and magnetic equivalent circuit of PM-type TFLM.	22
2.11	An asymmetric full bridge inverter for a 1-ph of PM-type TFLM.	24
2.12	Characteristic diagrams of single phase TFLM:	
	(a) The current in accordance with mover position.	25
	(b) The total force generated in accordance with mover position.	25
3.1	The flux linkage-current curves using the finite element analysis and the cubic-spline interpolation.	31
3.2	Co-energy curves against: (a) current for different rotor positions. (b) Rotor displacement for different values of	33 33

	phase current.	
3.3	The static torque curves of TFLM	34
3.4	The TFLM traction forces	35
3.5	the simulink modulation of the TFLM	37
3.6	the static characteristics under the TFLM subsystem	38
3.7	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 11$ mm at speed $V = 2$ m/sec.	40
3.8	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 13$ mm at speed $V = 2$ m/sec.	41
3.9	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 15$ mm at speed $V = 2$ m/sec.	42
3.10	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 11$ mm at speed $V = 4$ m/sec.	43
3.11	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 13$ mm at speed $V = 4$ m/sec.	44
3.12	the flux, current and the trust force at $X_{on} = 5$ mm and the $X_{off} = 15$ mm at speed $V = 4$ m/sec.	45
4.1	PID control system.	57
4.2	Unit step response of a plant.	59
4.3	S-Shaped response curve.	59
4.4	Closed loop system with a proportional controller.	61
4.5	Conventional and neural network-based function approximators.	66
4.6	Sketch for ANN layers.	68
4.7	Sigmoidal activation function of bipolar analogue neurons ($\lambda = 1$).	68
4.8	Sigmoidal activation function for unipolar analogue neurones ($\lambda = 1$).	69
4.9	Non-sigmoidal activation function.	70
4.10	Radial basis activation function: two-dimensional case	72

4.11	Feed-forward neural network architecture.	74
4.12	Cellular neural network.	75
4.13	One-layer real-time recurrent neural network	76
	(discrete time model).	
4.14	ANN Matlab Subsystem	80
4.15	Load force of the TFLM	81
4.16	TFLM response in the first zone without control	82
4.17	TFLM response in the second zone without	83
	control	
4.18	TFLM response in the third zone without control	84
4.19	System with PID controller	85
4.20	System Response with PID.	86
4.21	The PID response in the 1 st zone	87
4.22	The speed response for PID in switching from	88
	half to full load of the TFLM.	
4.23	The PID response in the switching back the full	89
	load of the TFLM.	
4.24	The first zone response for the TFLM driven by	90
	PID controller.	
4.25	The second zone response for the TFLM driven	91
	by PID controller.	
4.26	The third zone response for the TFLM driven by	92
	PID controller.	
4.27	System under study	93
4.28	The 1 st zone response of the TFLM driven by	94
	ANN controller.	
4.29	The second zone response of the TFLM driven by	95
	ANN controller.	
4.30	the 3 rd zone response of the TFLM driven by	96
	ANN controller.	
4.31	The comparison between the PID tuned and	98
	untuned method.	
4.32	The comparison between the PID tuned and	99

	untuned method.	
4.33	The comparison between the PID tuned and	100
	untuned method.	
4.34	PID and ANN controller response for first zone.	101
4.35	PID and ANN controller response for second	102
	zone.	
4.36	PID and ANN controller response for third zone.	103