

**AN IMPROVED FUZZY LOGIC CONTROLLER FOR DEPTH CONTROL OF THE
VIDEORAY PRO III UNDERWATER VEHICLE**

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**A report submitted in partial fulfillment of the requirements for the degree of Bachelor
of Mechatronic Engineering**

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2015

“I hereby declare read through this report entitle “An Improved Fuzzy Logic Controller for Depth Control of the VideoRay Pro III Underwater Vehicle” and found that it has comply the partial fulfillment for awarding the degree of Bachelor of Mechatronic Engineering”

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ABSTRACT

Nowadays, human ability is limited in deep water or seabed. There some places in underwater that human unable to reach due to dangerous and high pressure. However, the underwater vehicle is created to overcome the problem. Underwater vehicle function to help scientist make an underwater research and commonly used in deep water industries. The main point is the ability of underwater vehicle able to be controlled. However, the conventional like PD also has a problem to control nonlinear operation. The PID controller also hardly to achieved zero overshoot. Thus fuzzy logic controller is introduced to overcome the problem. In this project, the objectives are to design and improved fuzzy logic controller (FLC) for depth control of underwater vehicle (based on VideoRay Pro III), to analyze performance of system response of depth control in terms of zero overshoot, faster rise time and small steady state error using FLC and to verify the system response of the depth control using hardware implementation between Matlab/Simulink and Microbox 2000/2000C. For the methodology, the pressure sensor MX5700ap, step down voltage, microbox 2000/2000C, air compressor, thruster and multimeter are used during an experiment. The experiment was setup to analyze performance of PID and FLC in terms of zero overshoot, faster rise time and small steady state error. The final experiment carried out to study the effect of membership function of real-time fuzzy logic controller using open loop simulation data. The result shows fuzzy logic controller display a best performance in term of faster rise time, zero overshoot and small steady state error than mathematical modelling PID and real time PID.

ABSTRAK

Pada masa kini, kemampuan manusia adalah terhad di dalam air yang dalam atau dasar laut. Terdapat beberapa tempat di dalam air yang manusia tidak dapat mencapai disebabkan tekanan berbahaya dan tinggi. Walau bagaimanapun, kenderaan bawah air dibuat untuk mengatasi masalah tersebut. Fungsi kenderaan dalam air untuk membantu ahli sains membuat penyelidikan di bawah air dan biasanya digunakan dalam industri dalam air. Apa yang penting ialah keupayaan kenderaan bawah air dapat dikawal. Walau bagaimanapun, konvensional seperti PD juga mempunyai masalah untuk mengawal operasi tidak linear. Pengawal PID juga hampir tidak dicapai terlajak sifar. Oleh itu pengawal logik kabur diperkenalkan untuk mengatasi masalah ini. Dalam projek ini, objektif adalah untuk mereka bentuk dan bertambah baik pengawal logik kabur dan untuk mengawal kedalaman kenderaan bawah air (berdasarkan VideoRay Pro III), untuk menganalisis prestasi tindak balas sistem kawalan kedalaman dari segi terlajak sifar, lebih cepat meningkat masa dan kecil ralat, dan untuk mengesahkan tindak balas sistem kawalan kedalaman menggunakan pelaksanaan perkakasan antara Matlab / Simulink dan Microbox 2000 / 2000C. Untuk kaedah ini, sensor tekanan MX5700ap, penurun voltan, microbox 2000 / 2000C, pemampat udara, pendorong dan multimeter digunakan semasa eksperimen. Eksperimen adalah persediaan untuk menganalisis prestasi PID dan kawalan logik kabur dari segi terlajak sifar, lebih cepat meningkat masa dan kecil ralat. Percubaan terakhir dijalankan untuk mengkaji kesan fungsi keanggotaan masa nyata pengawal logik fuzzy menggunakan simulasi gelung terbuka. Hasil kajian menunjukkan pengawal logik fuzzy memaparkan prestasi yang terbaik dalam tempoh lebih cepat meningkat masa, terlajak sifar dan kecil ralat daripada pemodelan matematik PID dan masa sebenar PID.

TABLE OF CONTENTS

CHAPTER	TITLE	PAGE
	ACKNOWLEDGEMENT	i
	ABSTRACT	ii
	ABSTRAK	iii
	TABLE OF CONTENTS	iv
	LIST OF TABLES	vii
	LIST OF FIGURES	x
	LIST OF APPENDICES	xiii
1	INTRODUCTION	
	1.1 Project background	1
	1.2 Motivation	1
	1.3 Problem Statement	4
	1.3 Objectives	4
	1.4 Scope and limitation	5
2	LITERATURE REVIEW	
	2.1 Introduction	6
	2.1.1 Conventional controller	6
	2.1.2 Intelligent controller	7
	2.2 Related previous work	8
	2.3 Summary of literature review	14

CHAPTER	TITLE	PAGE
3	METHODOLOGY	
	3.1 Project Plan and process Flow	16
	3.2 Technical research	19
	3.3 Hardware	19
	3.3.1 Prototype	19
	3.3.1 Micro box 2000/2000C	21
	3.3.2 Pressure sensor	21
	3.4 Software	
	3.4.1 Matlab/Simulink	22
	3.4.2 Fuzzy Logic Controller	22
	3.4.3 Mathematical modelling	24
	3.4.4 State space	25
	3.5 Experiment Implementation	26
	3.5.1 Experiment1 : PID	26
	3.5.2 Experiment 2: FLC	27
	3.5.3 Experiment 3: Math. modelling	29
	3.5.4 Experiment 4	30
	3.5.5 Experiment 5	33
	3.5.6 Experiment 6	37
	3.5.7 Experiment 7	39
	3.5.8 Experiment 8	40

CHAPTER	TITLE	PAGE
4	RESULT AND DISCUSSION	
	4.1 Introduction	43
	4.2 Experiments implementation	43
	4.2.1 Output response using PID	43
	4.2.2 Fuzzy logic controller using Matlab	55
	4.2.3 Mathematical modelling	62
	4.2.4 Pressure sensor	64
	4.2.5 Effect real-time simulation using Microbox 2000/2000C with prototype	70
	4.2.6 System identification	72
	4.2.7 Stability	73
	4.2.8 Effect of membership function of FLC	74
	CONCLUSION AND	86
5	RECOMMENDATIONS	
	REFERENCES	88

LIST OF TABLES

TABLES	TITLE	PAGE
1.1	ROV Perceptions	2
2.1	The rule base of a Fuzzy-like PD in tabular form	12
2.2	Rule matrix of fuzzy controller	13
2.3	Summary of controller	14
	Connection with Microbox 2000/2000C, sensor and	
3.1	thruster	36
3.2	Rule table for fuzzy logic	41
4.1	Output response of PID with different parameters	53
4.2	Output response with shifting membership function	61
4.3	Comparison system response between PID and FLC	61
4.4	Output response of mathematical modelling	64
4.5	Table of pressure to depth vs. voltage	65
4.6	Percentage error of reading 1	68
4.7	Percentage error of reading 2	68
4.8	Percentage error of reading 3	69
4.9	Percentage error of reading 4	69
4.10	Summary of average error	70
4.11	System performance of real-time data Output response of real-time simulation PID	70
4.12	controller	71
4.13	Result of automatic tuning PID	71
4.14	Simulation result of automatic tuning PID	71
4.15	System identification of real-time data	72

4.16	Stability test of real-time data	73
4.17	Simulation result for change range input 1	74
4.18	Simulation result for change range input 2	74
4.19	Simulation result for change range output	75
	Average rise time and settling time for input 1	
4.20	membership function	76
	Average percent overshoot and steady state error of	
4.21	input 1	76
4.22	Summary of average output performance for input 1	77
	Simulation performance of input 1 membership	
4.23	function	77
	Average rise time and settling time of input 2	
4.24	membership function	78
	Average rise time and settling time of input 2	
4.25	membership function	78
4.26	Summary of average output performance for input 2	79
	Simulation performance of input 2 membership	
4.27	function	79
	Average rise time and settling time of output	
4.28	membership function	80
	Average overshoot and steady state error of output	
4.29	membership function	80
4.30	Summary of average output performance for output	80
	Simulation performance of output membership	
4.31	function	81
4.32	Simulation result for shifting membership function	81
	Simulation performance for shifting of membership	
4.33	function	82
	Summary result for effect of shifting membership	
4.34	function	82
4.35	Summary of output response for each membership	83

	function	
4.36	Comparison output response with different type of controller	65

LIST OF FIGURES

FIGURE	TITLE	PAGE
1.1	Broken 21” oil pipe 5000’ down in the Gulf of	3
1.2	ROV helps missing MH370	3
2.1	Block diagram of PID controller	6
2.2	Block diagram of fuzzy logic controller	7
2.3	CIS Control scheme	8
2.4	DFS Control Scheme	8
2.5	Control effort of the CIS and DFS control scheme for the linear model	9
2.6	Experiment Results Testing Open Loop System for ROV	10
2.7	Comparison between Mathematical Model With System Identification Model	10
2.8	The system response of ROV system based on linear equation	11
2.9	Slope of 0.5 linear equation	11
3.1	K-chart vehicle	16
3.2	Flowchart diagram of project report PSM 1	17
3.3	Flowchart diagram of project PSM 2	18
3.4	VideoRay Pro III underwater vehicle	19
3.5	Prototype based on VideoRay Pro III	20
3.6	Thruster configuration based on VideoRay Pro III	20
3.7	Micro-box 2000/2000c	21
3.8	Pressure sensor MPX250	21
3.9	Simulink library	22

3.10	PID close loop system	22
3.11	FIS Editor	23
3.12	Input 1 membership function	23
3.13	Rules of fuzzy logic controller	23
3.14	Rules viewer of fuzzy logic controller	24
3.15	Rules surface of fuzzy logic controller	24
3.16	Block diagram of PID close loop system	26
3.17	Output graph for control system	27
3.18	Matlab/Simulink block diagram	28
3.19	Membership function editor	28
3.20	Rule editor	29
3.21	Simulation of ROV modelling	30
3.22	Subsystem of ROV	30
3.23	Flowchart of pressure sensor experiment	31
3.24	Pressure sensor MPX5700ap	31
3.25	Step down voltage regulator	32
3.26	Multimeter	32
3.27	Experiment setup to obtained data	32
3.28	Real-time simulation using Microbox 2000/2000C	34
3.29	Prototype (based on VideoRay Pro III)	35
3.30	Pressure sensor circuit	35
3.31	Mini compressor	35
3.32	Wire connection at Microbox 2000/2000C	36
3.33	Analog to digital converter system	36
3.34	Real time open loop system	37
3.35	Real time data simulation	37
3.36	Data in system identification	38
3.37	Best fits of data	38
3.38	System identification	39
3.39	State space matrix equation	39
3.40	Test stability of data	40

3.41	Simulation real-time of fuzzy logic controller	41
3.42	Rule viewer surface of fuzzy logic controller	42
4.1	Graph depth vs. time for $i= 1.5$	43
4.2	Graph depth vs. time for $i= 1.07$	44
4.3	Graph depth vs. time for $p= 0.4$	45
4.4	Graph depth vs. time for $p= 0.5$	46
4.5	Graph depth vs. time for $p= 0.6$	47
4.6	Graph depth vs. time for $p= 0.7$	48
4.7	Graph depth vs. time for $p= 0.8$	49
4.8	Graph depth vs. time for $p= 0.9$	50
4.9	Graph depth vs. time for $p= 1$	51
4.10	Graph depth vs. time for $p= 2$	52
4.11	Graph depth vs. time for output “center”	55
4.12	Graph depth vs. time for output “right”	56
4.13	Graph depth vs. time for output “left”	57
4.14	Graph depth vs. time for input 1 “center”	58
4.15	Graph depth vs. time for input 1 “right”	59
4.16	Graph depth vs. time for input 1 “left”	60
4.17	Graph depth vs. time for mathematical modelling	64
4.18	Graph of ideal voltage	66
4.19	Graph of real voltage	66
4.20	Graph of ideal voltage compare with real voltage	67
4.21	Graph of depth vs. time for mathematical modelling	83
4.22	Graph of depth vs. time for real time PID	84
4.23	Graph of depth vs. time for real time FLC	84

LIST OF APPENDICES

APPENDIX	TITLE	PAGE
A	Gantt Chart	90

CHAPTER 1

INTRODUCTION

1.1 Project background

The ROV is a tethered underwater vehicle which is in unmanned categories. ROV commonly used in deep water industries which is involved in oil and gas activities. ROVs widely uses in offshore construction, military and scientific community. ROV used to as replace manned rescue system in military and helps scientist to make a research about underwater knowledge, deep sea animal and plants. The final year project is focused in designing the fuzzy logic controller to improve system response in terms of minimum overshoot, faster rise time, small, steady state error for depth control of the ROV (based on VideoRay Pro ROV III)

1.2 Motivation

The main encouragement to choose this title ‘An improved Fuzzy Logic Controller for depth control of the VideoRay Pro III underwater vehicle’ rather than other project because ROV is an interesting knowledge. ROV are widely use in several of application. ROV also can be used to explore science or natural environment at seabed. In paper [8] mentioned about impacts using ROV which is the two hundred ninety individuals completed the questionnaire in summer 2005. The respondent in the study ranged from 12 to 84 years old. The question was designed to examine the impacts using an ROV had on individual’s interactions with and connection to the natural environment. Table 1.1 shows that positive perceptions regarding ability of the ROV to be fun, safe and interesting to use as well as safe,

low impact and conservation oriented. Furthermore, respondents suggests it was good science and research tool. However, negative perceptions were noted only among adults and included the possibility of becoming disconnected from nature. From the case study shows that the ROV offers an alternative to who's loved to explore natural environment but may fear the water, have physical limitations or want to explore depths not physically possible.

Table 1.1: ROV Perceptions [8]

Perceptions of ROV	Mean	Stand. Dev.
The ROV could be useful.	4.76	.67
The ROV was creative.	4.50	.98
The ROV was exciting.	4.39	.97
The ROV helped me understand the natural resource.	4.19	1.12
The ROV was easy to use.	3.80	.25
The ROV was difficult to use.	2.02	1.27
The ROV was stressful to use.	1.77	1.24
The ROV was boring to use.	1.38	.90

Note: Responses were measured on a 5-point scale with 1=strongly disagree and 5=strongly agree.

Other than that, ROV had function to solve underwater tragedy like deep water horizon oil spill in the Gulf of Mexico. The broken oil pipe in the Gulf of Mexico dumped 300 million gallons of water a day into Charles River (figure 1.1) and affected the water supply to for two million people The problem was determine by enlisted ROV to investigate the immediate wellhead area. The ROV discover two leaks which one from a kink in the riser and a primary link from the end of the riser, where it broken off from the rig. It a risk for human to dive in 5000' down in the Gulf of Mexico and ROV is a solution for critical situation [7].

Mysterious tragedy MH370 also used ROV in search black box in a seabed of Hindi Ocean. ROV can firm, scan and crucially pick up things from the seabed (figure 1.2).Other example is Remora which can function 6000metres which is used in salvage AF447 and other crashed planes [6]. Another important thing in ROV is the system response for depth control. In order to develop a better response in depth control for future, an analysis from fuzzy logic controller is introduced.



Figure 1.1: Broken 21” oil pipe 5000’ down in the Gulf of Mexico taken by ROV [7]

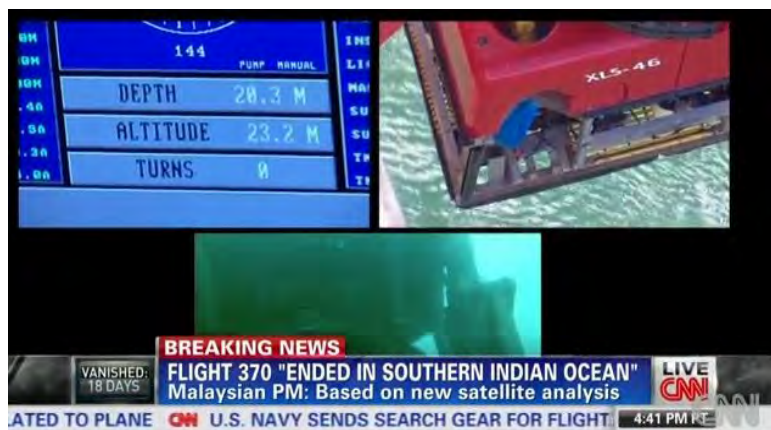


Figure 1.2: ROV helps missing MH370 [6]

1.3 Problem Statement

There are many problems happen in a remotely underwater vehicle that related with control system. The conventional controller like PD also has a problem with depth control of the ROV. The PD controller is not suitable in a nonlinear operation of depth control. The conventional PID controller also hardly to achieve zero overshoot in system response of depth control. This problem is crucial because it might cause damage to the remotely underwater vehicle if it contact directly with the seabed. Thus, intelligent control system such as fuzzy logic controller is needed in order to solve PD and PID problems.

The fuzzy logic controller is considered as new controller method to improve depth control of the ROV. Therefore, a shifting membership function will be used to analyze the effect of system response of depth control. The results is one simple contribution to this field of study.

1.4 Objectives

The objectives of final year project are:-

1. To design and improve the fuzzy logic controller for depth control of underwater remotely operated vehicle (based on VideoRay PRO ROV III)
2. To analyze performance of system response of depth control in terms of zero overshoot, faster rise time and small steady state error using FLC
3. To verify the system response of the depth control using hardware implementation between MATLAB/Simulink and Micro-box 2000/2000C.

1.5 Scope and Limitation

This project is mainly about the control system. The prototype based on VideoRay Pro III was used in this project. The prototype of the ROV is built by following parameters of thruster construction VideoRay Pro III (2 horizontal thruster and 1 vertical thruster). The dimension of prototype built up by refer to VideoRay Pro 3s (30.5 x 22.5 x 21cm). Since this project related with depth control, the movement of ROV covered a vertical up and down. The depth of ROV while doing an experiment is set less than 5m only. This project were carried out in a condition disturbance will be assumed to zero. This project were implement the intelligent control system which is Microbox 2000/2000C. The experiment related with Microbox 2000/2000C was setup in CIA Lab, FKE since a Microbox 2000/2000C is prohibited to use out of CIA lab, FKE.

CHAPTER 2

LITERATURE REVIEW

2.1 Introduction

This chapter will focus on ROV depth control. The topic cover about controllers that use in ROV. The main point in this chapter are to know an advantages and disadvantages each of controllers that effect the performance of depth control. Related journal of implementation controller for underwater robot also will be review and study to gain a knowledge and able to improve an existing method.

2.1.1 Conventional controller

The conventional controller includes PID, PD and PI controller. Conventional controller widely used in industrial control system. In term of stability and overshoot, intelligent system is more effective than conventional system. However, both system have their own advantages and disadvantaged by depending on applications.

- PID controller is a combination proportional, integral and derivative controller. The sum of three elements to calculate the output of PID controller.

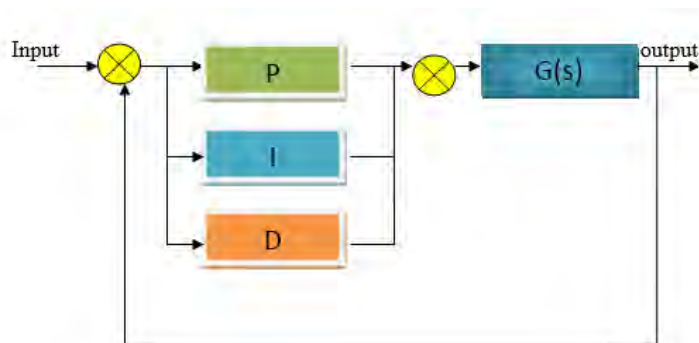


Figure 2.1: Block diagram of PID controller

Where,

K_p : Proportional gain, a tuning parameter

K_i : Integral gain, a tuning parameter

K_d : Derivative gain, a tuning parameter

e : Error = SP-SV

t : Time or instantaneous time (the present)

T : Variable of integration; takes on values from time 0 to the present t .

2.1.2 Intelligent controller

Nowadays, an intelligent control shown some success in a control method. For example neural network, fuzzy logic controller and genetic algorithm. Intelligent controller like fuzzy logic show a highly time consuming but it is suitable for nonlinear motion and need some tuning process in order to increase a performance. Fuzzy logic widely used in washing machine, rice cooker, and others. Block diagram of fuzzy logic controller as shown in Figure 2.2.

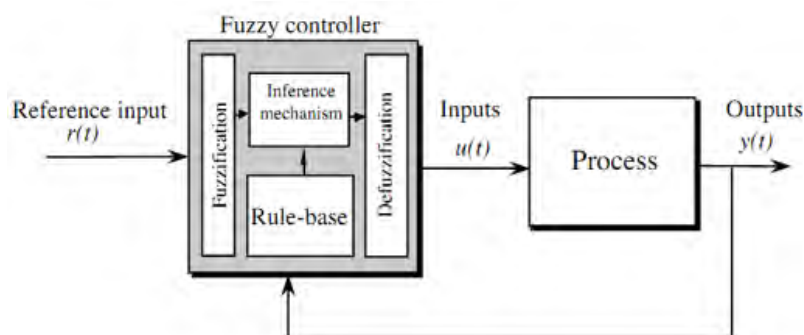


Figure 2.2: Block diagram of fuzzy logic controller [9]

Component:

- Rule-base – set of rules regarding on how to control
- Fuzzification – transforming process of numeric input into any form that can be used and detected by inference

- Inference mechanism – this mechanism use information that is formed from fuzzification and decide which rules will be applied in that of situation
- Defuzzification – convert the conclusion into numeric input for the plant that is reached by inference mechanism.

2.2 Related Previous Work

According to S. M. Zanoli [1] the PID controller with an input smoothing pre filter is introduced as a tuning of the pre filter parameters shown to reduce an overshoot. The Newtonian or a Lagrangian formalism is used as a system equation to derive a general non-linear model that described the dynamic of an underwater vehicle. The depth control divide in two different method which is continuous input smoother (CIS) as shown in Figure 2.3 and discrete fuzzy smoother DFS as shown in figure 2.4 [1].

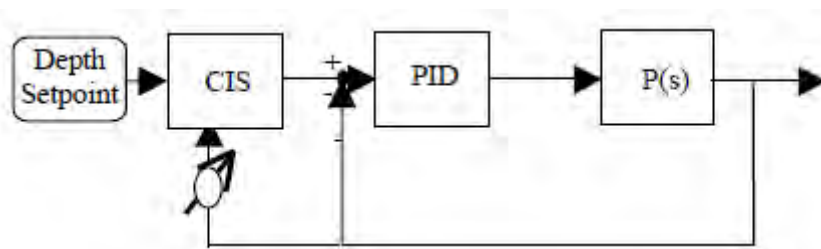


Figure 2.3: CIS Control scheme [1]

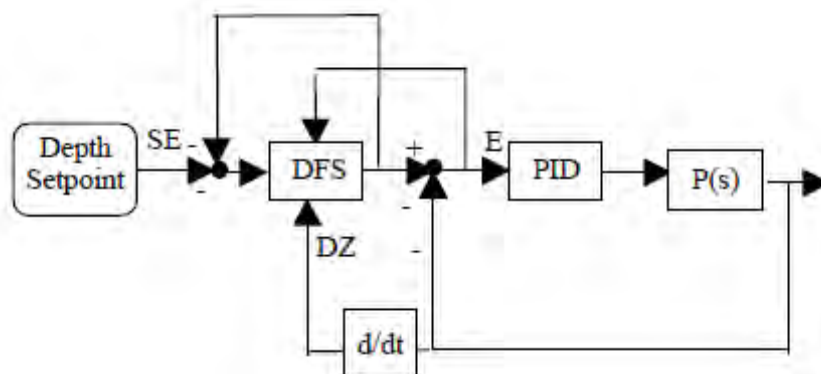


Figure 2.4: DFS Control Scheme [1]