Modeling and comparison of fuzzy PID controller with PSD regulation in the discrete systems

S. Koprda, Z. Balogh and M. Turčani

***Abstract*—** The development of computer technology has led to new modern management methods in the work experience. Evidence of this can be found in developments such as AC (adaptive control), robust control and, most clearly, AI (artificial intelligence) and expert systems. It is important to prefer regulator adaptation with minimal overshooting and speed and stability control for meeting criteria of technological process. This article describes one of possibilities for finding of PSD controller coefficients to reach the best quality control in comparison with standard procedures and is also devoted to creating a simple fuzzy PID controller.

***Keywords*—** Fuzzy PID, Fuzzy rules; Thermodynamic system, Regulation, MATLAB, PSD regulator.

I. INTRODUCTION

Proportional-Integral-Derivative (PID) control is a traditional linear control method used in many applications [1]. The PID controller algorithm is widely used for industrial automation tasks and thermal comfort heating and cooling applications where error, derivative of error, and integral of error are used in the calculation of control law [2].

In practice, the classic linear regulator PID is still the most used type. Its discreet version, called PSD regulator (I – component is substituted by summation and D – component by difference), was therefore one of the first applications of the discreet regulation and nowadays it is installed in the majority of control systems. Automated control systems free man from monotonous and tedious work, they are able to guarantee a stable and high quality of operation during the all period of activity, what is on the contrary of irregular capacity of man in classic systems an indisputable asset. Usually everything evolves from the dominant position of the regulator in the control circuit from classic point of view on control and automatization. Adjusting of optimal coefficients of regulator is still a current problem of the operation of industrial regulators.

Along with the development of computer technique we are currently more and more encountered with the infiltration of modern methods of controlling into the practice [3,4]. Adaptive control, robust control and last but not least also the artificial intelligence and expert systems can serve as examples. An important part of artificial intelligence in the practice represents and will, from now on, represent fuzzy logic and its applications. Tzafestas and Papanikolopoulos [5] have indicated that exploitation of fuzzy logic allows for using the human approach to propose rule-based solutions for designing fuzzy FPID controllers.

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One of the aims of the present day is to substitute the classic PID regulator for discreet PSD regulator, or fuzzy regulator. There is an everlasting conjunction in the linear control circuit between the linear progress of regulated quantity y (t) and the progress of action quantity u (t) which depends on it. This continuum and permanence of observation is not necessarily essential.

While fuzzy logic has been used as an effective tool in development of F-PID control algorithm, the performance of these controllers is limited to the extent of possible combinations of fuzzy systems characteristics such as, fuzzy rules, membership functions, and input and output scaling factors examined heuristically based on empirical knowledge and experimental trial and errors by the human designer [6].

The fuzzy controller can be viewed as a natural extension of the conventional PID control algorithm with a fuzzy implementation [7]. The structure of the fuzzy PID (FPID) controller includes two blocks of the traditional fuzzy controller: a fuzzyfier and an inference engine. [8].

It is natural that it is necessary to improve quality of any production technology in a complex way, by replacing the

Manuscript received March 28, 2011: Revised version received May 17, 2011.

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technology itself, as well as by continuous optimization of operation, where it is inevitable to exploit not only exact theoretical means, but also practical experience, or heuristic procedures from the level of dispatcher control. It is just here, where new opportunities for exploitation of fuzzy controller are opening, as a compensation for a man in control and optimizing processes. Besides the already mentioned possibilities, the exploitation of fuzzy controllers in the practice is very widespread. For example, steam turbines control, chemical reactors and cement operations control have successfully been solved [9]. An example of a non-traditional exploitation can serve the use of fuzzy controller for the acceleration of the theory of neurone networks.

II. ARRANGEMENT OF THE MEASURING CHAIN OF THERMODYNAMIC SYSTEM

Measuring chain consists of:

- Thermodynamic system of the first order,
- Temperature sensors,
- Humidity sensor,
- Heat source,
- Power supplies,
- Facility serving for temperature and humidity measurement named DN 20,
- Facilities for the measurement of consumption,
- Control programme, created in the programme MATLAB.

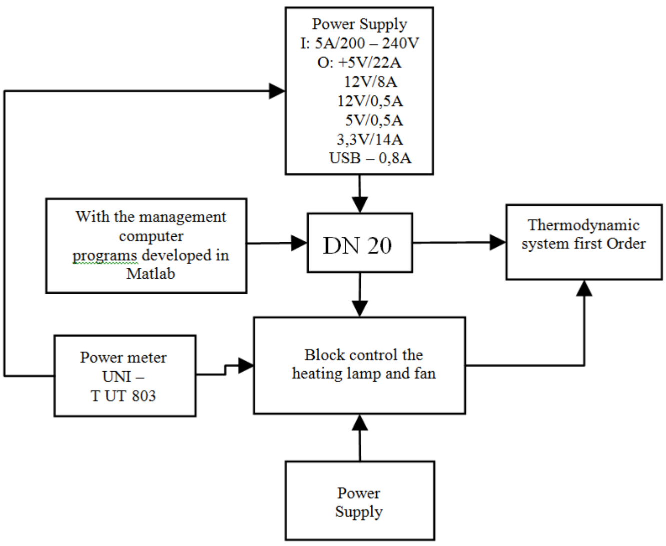

Fig. 1 Flow chart of the measuring chain

A. The design concept of the termodynamic system of the first order

The thermodynamic system was created by means of a wooden frame with the dimensions x=1.0 m, y=0.5 m and z=0.5 m. Thereafter, this frame was veneered from inside by an insulating plasterboard with the same dimensions as the size of the frame. The thickness of the insulating plasterboard is 1 cm. This frame was veneered from the outer side by polystyrene with the same dimensions as the frame. The thickness of the polystyrene is 5 cm. The volume of the system is 0.25 m^3.

B. Heat conductivity of insulating plasterboard

In this section we determined heat conductivity of the insulation plasterboard by means of the following relationship:

$$Q = \lambda \frac{S}{l}(t_1 - t_2)\tau \qquad (1)$$

The supplied heat is marked as Q, λ is heat conductivity to be determined, S is the board surface, l is the board thickness, $t_1 - t_2$ is the difference of temperatures at both sides and τ is the time during which heat Q is supplied. It is expected that the temperature difference is stabilized and that no heat is being lost.

The relationship can be adjusted as follows:

$$\lambda = \frac{Q}{\tau} \frac{l}{S(t_1 - t_2)} \qquad (2)$$

The fraction Q/ τ represents the supplied heat during the time period. If its source is electric heater elements, it is possible to substitute the output UI directly.

Thus we obtain:

$$\lambda = \frac{UIl}{S(t_1 - t_2)} \qquad (3)$$

The shape of the insulating plasterboard was cuboid with a square base with the side dimension 201 mm and thickness 13 mm. It was heated from one side by a foil with a resistance wire inside, powered up by a source with an alterable voltage and current. The board was cooled from the other side by water flowing through a metal cooler. The insulation plasterboard was separated from the foil and the cooler by a silicone heat foil. It was also equipped with incisions for thermoelements, by means of which temperature was determined on both sides. All this system was separated from the environment by polystyrene boards. Prior to the measurement itself it was necessary to calibrate thermoelements (to determine the dependence of voltage on the thermoelement on the temperature difference). This was done so that one end of the thermoelement was immersed in hot water, while the other was put aside with the surrounding temperature. Voltage of the thermoelement is directly proportional to the temperature difference on its ends.

$$U = \frac{1}{k}\Delta T \qquad (4)$$

Temperature of the environment was T_1 = 26.4 ºC, water temperature was T_2=82 ºC. Voltage on the thermoelement was U=2.34 mV. We thus obtain $k=(T_2-T_1)/U$ which equals 23.76KmV^{-1}. Having determined properties of the thermoelement, the measurement itself was executed. The results are shown in the Table I.:

TABLE I. RESULTS OF HEAT CONDUCTIVITY OF PLASTERBOARD

U, V	*I, A*	U_1*, mV*	U_2*, mV*	ΔT *, K*	λ *,* $Wm^{-1}K^{-1}$
15	0,74	0,92	0,06	22,69	0,157
18	0,88	1,28	0,10	31,3	0,163
22	1,08	1,60	0,23	43,31	0,177

Source: own research

Heat conductivity of plasterboard λ=0.166 $Wm^{-1}K^{-1}$ (arithmetic average). For comparison we found in the catalogue heat conductivity of one kind of plasterboard, which was 0.113 $Wm^{-1}K^{-1}$, which is a lower value. This could have been caused by thermal losses, or different kind of plasterboard.

C. Finding out the transient characteristics of the designed thermodynamic system

Energy constantly flows through buildings and a building envelope plays the role of an interface between the inner and the outer space. The properties of a building envelope, especially of its transparent parts, have significant influence on interaction between the two spaces [10].

Before recording the temperature data in MATLAB the design marked DN 20 was used for the sensing of temperature and humidity. It is the device, which was designed at the Department of Electrical Engineering and Automation in cooperation with the firm Power – One s.r.o. [11]. The device consists of a microprocessor DN 20, connectors for the connection of temperature and humidity sensors, and outputs for controlling the heater element and a fan. Outputs are programmed and preset by means of the program MATLAB and allow for a fluent voltage control using PWM modulation on the connector output.

The device is connected to the computer with the serial port. In the computer runs the simulation program, which records, controls temperature and humidity and ensures controlling of the thermal source and fan in the thermodynamic system.

When finding out the transient characteristics we proceeded as follows. The thermodynamic system was heated by means of a 55 wat bulb. The time of heating was approximately 23.55 hours. Temperature sensors were deployed in the bottom and top parts of the system. For temperature sensing four temperature sensors marked Dallas DS18B20 were used.

The number of used sensors and their deployment in the thermodynamic system was verified by a series of experiments. Homogenous groups, or statistically significant differences in the temperature measured by the used sensors were identified using an analysis of experimental data. Individual experiments differed by the number of sensors and their deployment. When processing the experimental data we were inspired by [12, 13, 14].

TABLE II. MULTIPLE COMPARISON (TUKEY HSD TEST)

SENSOR	**Mean**	**1**	**2**	**3**	**4**
temperature2	27,61241	****			
temperature1	27,87892		****		
temperature5	27,88321		****		
temperature3	27,97136			****	
temperature4	28,16232				****

Source: own research

From the multiple comparison one homogenous group (temperature1, temperature5) was identified. In case of the other sensors statistically significant differences in the obtained temperatures were proved. Exploitation of four sensors in our system turned up satisfactory.

Sensors, which were situated in the system, were connected to the device, which controlled microprocessor device DN 20. The device was connected with the computer, on which the program MATLAB with the created control program for the given measurement was running.

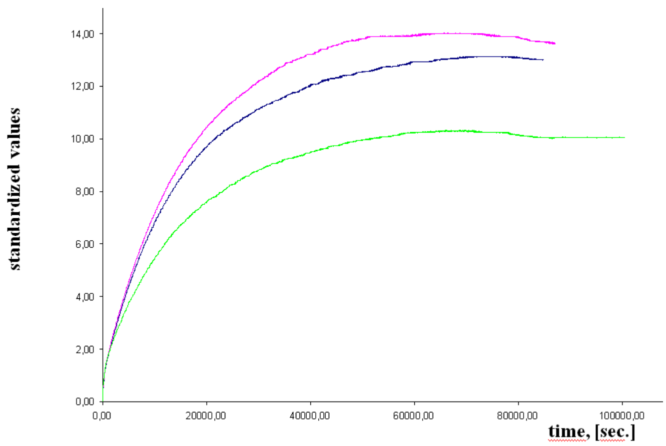

Fig. 2 The measured transitional characteristics of the thermal system model – normed (sampling period 10 s)

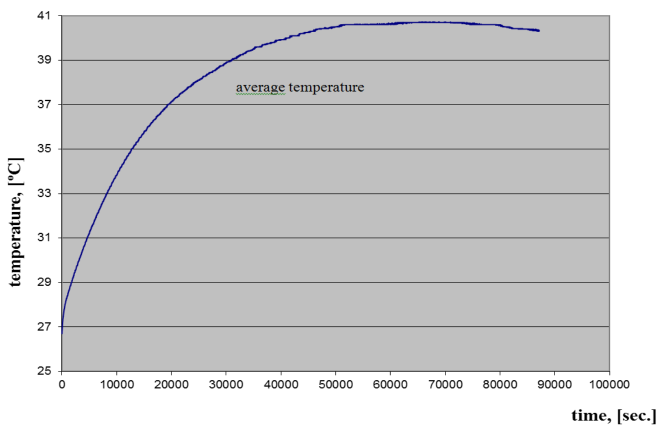

Fig. 3 Real transient characteristics measured

Equation of this thermal system will look like:

$$G(p) = \frac{K_P}{Tp + 1} \tag{5}$$

where T – will be calculated as $\left(1 - \frac{1}{e}\right)$ multiple of the final value,

K_p – is the final value,
p - Laplace operator,
e - Euler´s number

For the calculation of T the mean characteristic was used.
T = 14290 s
KP = 1
Simulation of the transient characteristics of the system

$$G(p) = \frac{1}{14290s + 1} \tag{6}$$

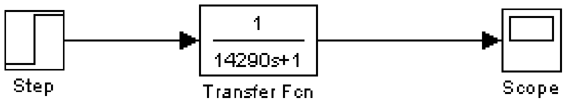

Fig. 4 Simulative scheme for detection of simulated transitional characteristic

The following orders will be used for finding the transient characteristics in the program MATLAB:

```
sys = tf(1,[14290  1])
step(sys)
```

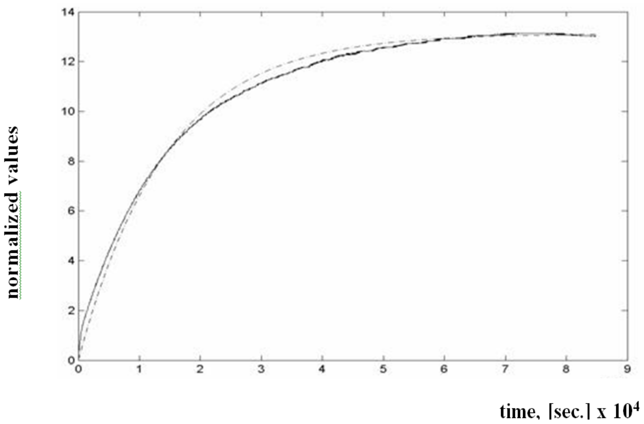

Fig. 5 Resultant characteristics of the real and simulated transient characteristics – Similarity is 99.77 %.

III. REGULATION OF TEMPERATURE IN THE THERMODYNAMIC SYSTEM BY USING THE PSD REGULATOR

PSD regulator (Proportionally –Summationally – Differential) is a discreet (numerical) variant of PID regulator. We use Kuhn´s method to calculate the parameters of PSD regulator which is suitable for setting PSD regulator with regulated system of first order.

For transmission in this form

$$G(s) = K_S \frac{(T_{1N}s + 1)(T_{2N}s + 1)....(T_{mN}s + 1)}{(T_{1N}s + 1)(T_{2N}s + 1)....(T_{mN}s + 1)} e^{-T_D s} \tag{7}$$

is thus the total time constant defined:

$$T_\Sigma = T_1 + T_2 + ... + T_n - T_{1N} - T_{2N} - ... - T_{mN} + T_D \tag{8}$$

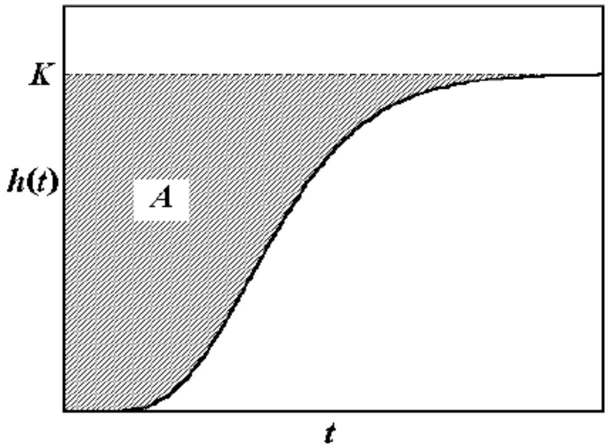

Fig. 6 The transitional characteristic of the system

$$A = \int_0^\infty (K - h(\tau))d\tau = \lim \int_0^t (K - h(\tau))d\tau = \lim s\left(\frac{K - G(s)}{s^2}\right) \tag{9}$$

h(t) is the transitional characteristic of the system and this relation can be rewritten:

$$A = \lim K \frac{(T_1s+1)(T_2s+1).(T_ns+1) - (T_{1n}s+1)(T_{2n}s+1).(T_{mn}s+1)e^{-T_Ds}}{s(T_1s+1)(T_2s+1).(Tns+1)} \tag{10}$$

We get:

$$A = K(T_1 + T_2 + ... + T_n + T_D - T_{1n} - T_{2n} - ... - T_{mn}) = KT_\Sigma \tag{11}$$

by application of the Hospitals' rule.

It is necessary to determine the stable magnitude of transitional characteristic KP to calculate the coefficients of the PSD regulator. See the picture below.

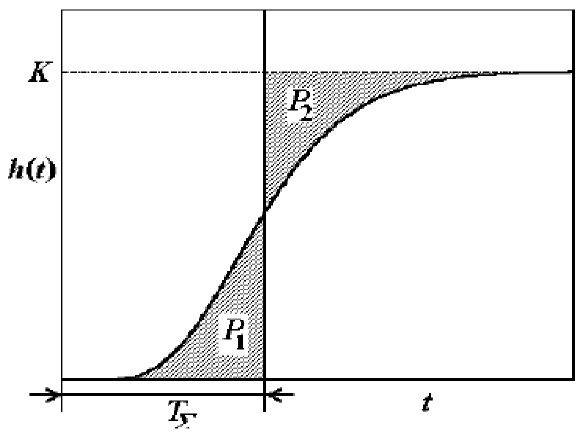

Fig. 7 Approximate assessment T_Σ, P1 = P2

We thus calculate each coefficient of the PSD regulator:
$k = 1/K_p$
$T_i = 0.66\ T_\Sigma$
$T_d = 0{,}167\ T_\Sigma$

For regulated system of first order $G(p) = \frac{K_p}{Tp+1}$ it counts:

$T_\Sigma = T$
and the stable magnitude of transitional characteristic K_p = 1.
Then the calculated parameters of PSD regulator by Kuhn´s method for the system $Gs(p) = \frac{1}{14290s+1}$ are:

k = 1
T_i = 9432 s
T_d = 2387 s

The temperature in the thermo dynamical system was set for 28°C. The bulb will affect until the attainment of the given temperature and then a ventilator will affect after exceeding this temperature. The period of duration was 5, 75 hours. The time of sampling was T_{VZ} = 30 s

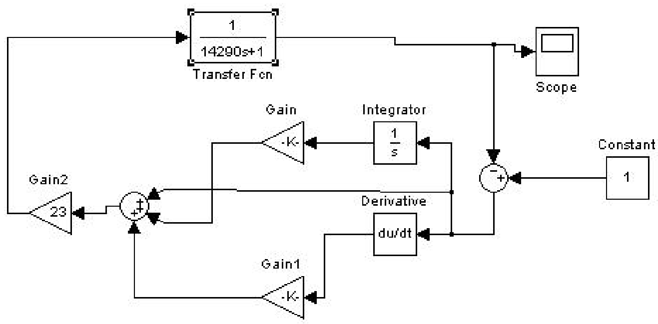

Fig. 8 Simulative scheme of PDS regulator with the system

The first step of the optimization of PSD regulator is setting the same onset time of output signal of simulated PSD regulator and the system with the real measured process of onset of the temperature during the regulation.
We have reached the right setting by means of optimalization and for regulation of the temperature we will speculate PSD regulator with parameters:

k = 12
T_i = 10600 s
T_d = 1 s

Then the graphic temperature progress of the arranged PSD regulator is:

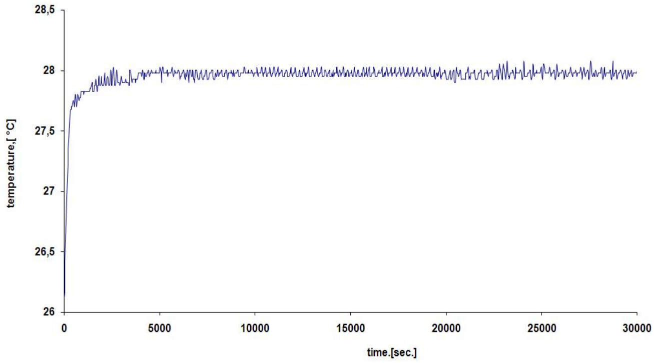

Fig. 9 PSD regulation diagram

The temperature varied between 27,85ºC and 28,075 ºC during the measurement.
To compare with the desiderative magnitude we can observe that this range of temperature was 0,15 ºC.
We fixed a condition before the measurement that temperature range (whether it is PSD regulation or fuzzy PID regulation) can be max. 1 °C.

IV. Proposal of Fuzzy Control of Temperature and Ventilation in the Thermodynamic System of the First Order

Proper functioning of the control algorithm is essential for adequate adjustment and velocity of the roller blind alternations. Control algorithms with fuzzy controllers offer better response and efficiency in case of complex nonlinear and time varying working conditions when compared to conventional PID controllers. The advantage of the fuzzy controller's design derives from its similarity to human reasoning [15].
Thermodynamic system was described by a two-dimensional fuzzy system with a single output MISO (multi input, single output). Input variables are temperature and relative humidity, which belong among basic descriptive traits of air exchange, while the output variable is the signal for continuous control of the heater element and fan revolutions. In the process of passive ventilation air with variable basic features from external or internal environment is used.

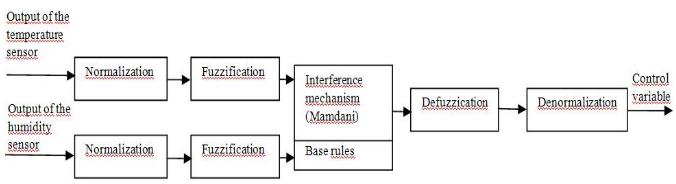

Fig. 10 Block structure of the designed general fuzzy control system

Fuzzy controllers, in the application of fuzzy sets theory [16,17], have some special characteristics that other controllers lack or do not have. First of all, they provide systematic and efficient means of capturing the linguistic fuzzy information from the human experts or the real world. Next, they can convert the linguistic control strategy into an automatic control strategy that is nonlinear and model-free. Practically, the fuzzy control is easy to understand and simple to implement, because it emulates the human control strategy. Thus it has been reported recently that a lot of fuzzy controllers are able to control such systems that are very complex or poorly modeled and that experienced human operators are available for providing expert rules [18, 19].

The control system consists of three main sections: fuzzification, interferential mechanism and defuzzification. One part of fuzzification converts the real exact values into a fuzzy expression, while fuzzy interferential mechanism evaluates the input data and calculates the output value based on the base of knowledge and the database. These fuzzy values of outputs are converted into real values in the process of defuzzification.

Generally, a control system, which is capable of implementation in a various system of ventilation and a different construction design concept, was proposed. We expected exploitation of linear sensors. The function of adherence of the input variable (temperature) was mapped into the normalized universum [-1, 1], the function of adherence of the input variable (humidity) was mapped into the normalized universum [-3, 3], the function of adherence of the output variable (signal for the control of heater element and fan) was mapped into the normalized universum [-100, 100] and subsequently fuzzified. The functions of adherence of the input variables and the output variable are in figures 11, 12 and 13.

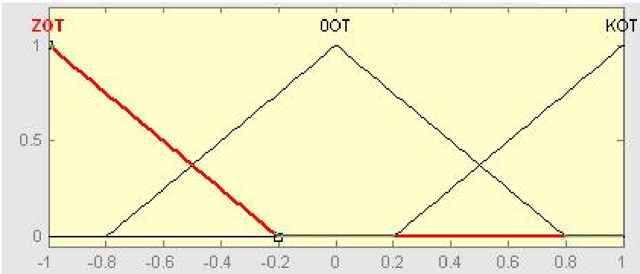

Fig. 11 Function of adherence of the input variable (temperature)

$OT = T_{REQ}\text{-}T$ (12)

OT – temperature deviation

T_{REQ} – required temperature

T – input temperature

ZOT – negative temperature deviation

0OT – zero temperature deviation

KOT – positive temperature deviation

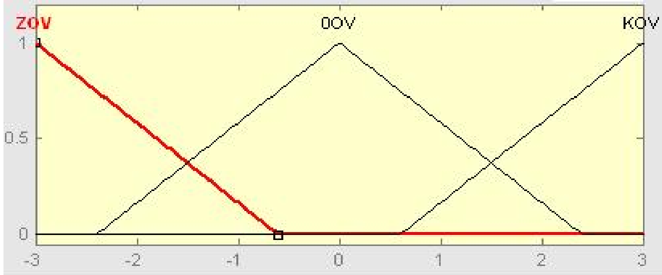

Fig. 12 Function of adherence of the input variable (humidity)

$OV = V_{REQ}\text{-}V$ (13)

OV – humidity deviation

V_{REQ} – required humidity

V – input humidity

ZOV – negative humidity deviation

0OV – zero humidity deviation

KOV – positive humidity deviation

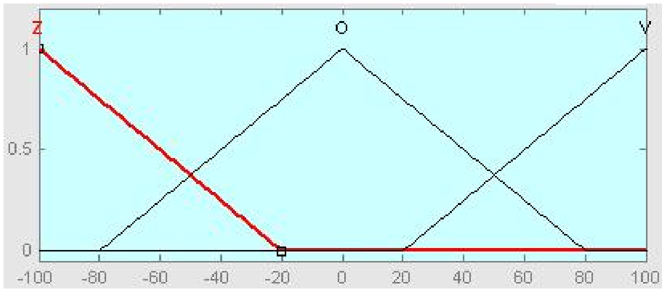

Fig. 13 Function of adherence of the output variable (heater element and fan control)

Z – bulb

O – zero

V – ventilator

Distribution of functions of adherence of the output control variable is again in the normalized interval, while their shape is formed by sharp lines on the given position of the verbal value in consequence of the decision rules, so-called singletons. In fact, this means that the value (0, -100) represents the value, during which it is an active heater element and the value (0, 100) represents the value, during which it is an active fan.

If/then rules offer a convenient format for expressing pieces of knowledge. But it is just a format which can cover different intended semantics and uses. The consequent of a rule may be qualified with various modalities expressing, for instance, strong ones such as certainty, obligation, or weaker

ones such as possibility or feasibility. Rules may have implicit exceptions, or may universally hold. Depending on their interpretation, rules have to be represented and processed in a specific way at the inference level [20].

The Mamdani type of fuzzy system is more suitable for applications where understandability of the model is important. Also, "the number of the input fuzzy sets and fuzzy rules needed by the Sugeno fuzzy systems depend on the number and locations of the extrema of the function to be approximated" [21, 22]. On the other hand, the Mamdani type of fuzzy system uses less fuzzy sets and rules why it is simpler and thus more understandable. Triangular fuzzy sets support this simplicity of fuzzy model.

Fuzzy logic control of the system operates on the basis of implication of two fuzzy statements. If ascendent then consequent (by means of an implication of the Mandami alternative If <fuzzy statement> then <sharp ascending value>). A fuzzy linguistic model with the following hierarchy was used:

1. If (OT is ZOT) and (OV is ZOV) then (u is V)
2. If (OT is ZOT) and (OV is 0OV) then (u is 0)
3. If (OT is ZOT) and (OV is KOV) then (u is 0)
4. If (OT is OOT) and (OV is ZOV) then (u is V)
5. If (OT is OOT) and (OV is 0OV) then (u is 0)
6. If (OT is OOT) and (OV is KOV) then (u is 0)
7. If (OT is KOT) and (OV is ZOV) then (u is V)
8. If (OT is KOT) and (OV is 0OV) then (u is Z)
9. If (OT is KOT) and (OV is KOV) then (u is Z)

When choosing the rules, quantitative expert knowledge supported by theoretical knowledge based on vague input information, were used. It is necessary to provide conditions of completeness, consistency, continuity and interaction of the set of rules. Local changes can be obtained by alternation of the consequent of the appropriate rule and the size of the area, where the change will be realized, can be influenced by the width of fuzzy sets.

The whole base of knowledge of the fuzzy control system was filled up by means of the graphic user interface and using the means - Matlab program - Fuzzy Logic Toolbox into the corresponding universes. The fuzzy control system results in a non-linear control area depicted in the figure 14.

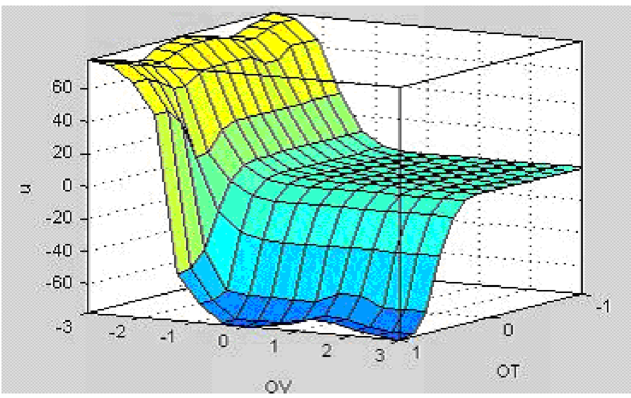

Fig. 14 Generated control area of the designed system

Having finished the design of the fuzzy control, it was inevitable to connect the fuzzy controller with the system in order to practically verify the function of the controller. For the provision of sensing the input quantities (temperature and humidity) and the consecutive control up to the selected value the microprocessor device DN 20, which was described in the previous chapters, was used again. For the interconnection of the designed fuzzy controller with the microprocessor device DN 20 and the thermodynamic system a control scheme in the program MATLAB was created. The control scheme consists of the block Write read format, Write format and the block Processing. The control scheme is in figure 15.

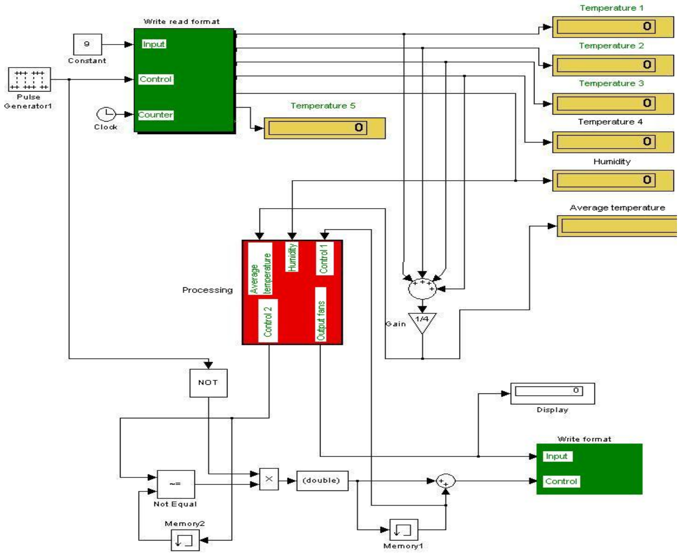

Fig. 15 Control scheme

The most important part of the control scheme is the Processing block. The Processing block contains the defined fuzzy controller and a selector, which, as need may be, provides control of the heater element or fan. The Processing block scheme is shown in figure 16.

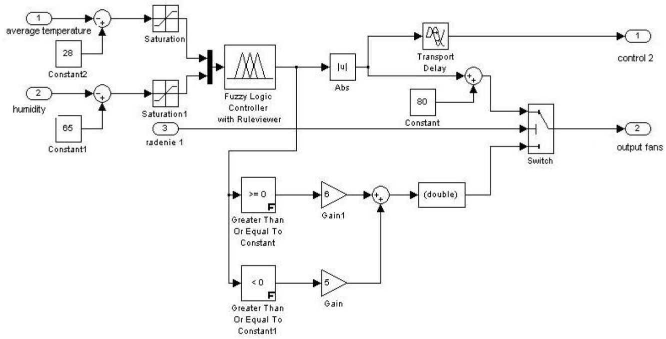

Fig. 16 Block scheme of the Processing block

In the Processing block we can also set up the required value of temperature and humidity in the thermodynamic system.

In our case we set up temperature to the value 28 ºC and relative humidity to 65 %. The obtained results are presented in figures 17 and 18.

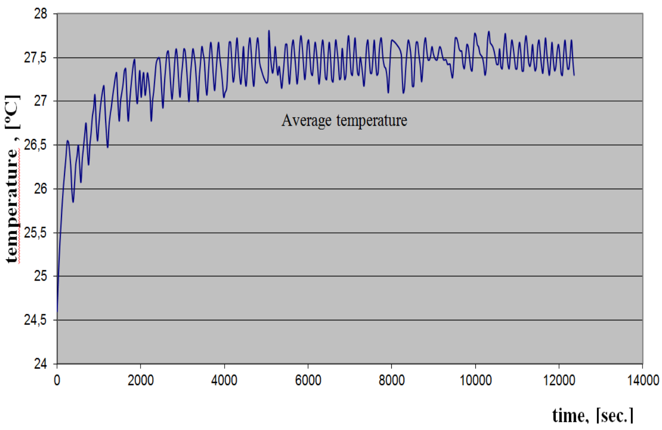

Fig. 17 Course of temperature using fuzzy control

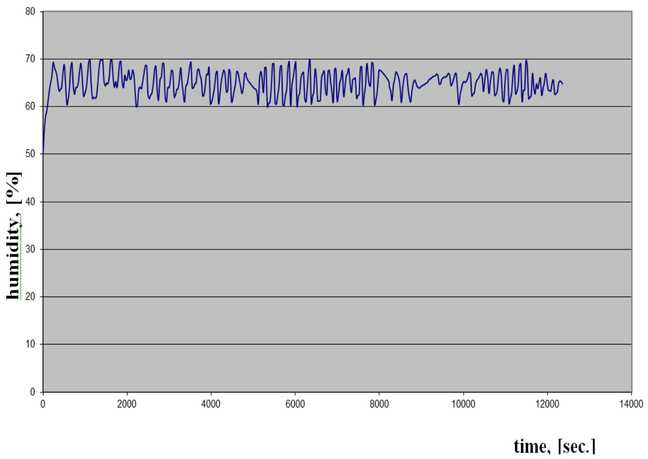

Fig. 18 Course of humidity using fuzzy control

The period of measurement was 3.4 hours and the period of sampling lasted for 30 s. The initial value of temperature was 24.73 ºC and humidity 48 %. In the course of measurement temperature oscillated within the range of 27.4 ºC to 27.78 ºC. When comparing with the required value of temperature we can state that the range of temperature was 0.6 ºC. The value of humidity oscillated within the range of 60 up to 69.8 % when compared with the required value, which means that the controller was capable of controlling humidity with the ± 5 % accuracy.

Then, we can say that besides the natural external interference, the design of the fuzzy logic control system is influenced also by the factors of shape and distribution of the input and output functions of adherence, the used interference rules and the selected values of measures. Practically, the setting of controller is most frequently done by alternating the sizes of measures, by which it is possible to shift the value of the control intervention into the required position on the control area, thus reaching the adequate value of its size.

In the future, the above mentioned control system could be extended by an implementation of genetic algorithms.

V. Discussion

While proposing PSD regulation we used Kuhn´s method [23] for setting the parameters of PSD regulation. The equation of PSD regulator was arranged by the approximation of integral by means of rectangles from right direction. In PSD regulation the change of the magnitude of power of the bulb and the ventilator depended on the desiderative temperature in the thermo dynamical system. Using the PSD regulation we assigned both conditions. It means that the regulator was able to assign the desiderative temperature in a given interval and was able to react to arising troubles much more precisely. I the case of the condition of temperature range 1°C, which was defined for both types of regulators, we can observe that in PSD regulation the range was 0, 15°C what presents 15% of the maximum.

The next problem we faced was the creation and simulative verification of fuzzy PID regulator. While proposing fuzzy regulator we used graphic surroundings Graphical User Interface (GUI) which was granted by MATLAB. In these surroundings we have done all setting of the regulator, from the assessment of the function of appurtenance, the setting of the base of rules, the behaviour of the regulator till the consent of a suitable type of fuzzyfication and defuzzyfication.

The proposed system fuzzy temperature and wetness control was practically tested in laboratory conditions in thermo dynamical system of the first order. The advantage of fuzzy regulation is that we can control two and more input variables [11]. Fuzzy control was oriented on temperature and wetness regulation.

I the case of the yet mentioned condition of temperature range 1°C, which was defined for both types of regulators, we can observe that in fuzzy PID regulation the range was 0, 6°C what presents 60% of the maximum.

VI. Conclusion

The article is about the problem of temperature regulation by means of PSD regulator and the regulation of temperature, wetness by means of fuzzy PID regulator. The advantage of PSD regulator is:

- PSD regulator is able to assign optimal conditions in thermo dynamical systems,
- It is possible to optimize the parameters of PSD regulator with a suitable modification of algorithm control,
- Lower consumption of electric energy.

The disadvantage of PSD regulation is that it is able to control just one of the desiderative quantities and also complicated constructional solutions into a proportional control of action items.

The proposed fuzzy PID regulator can be used to optimize technology which contains preferenced level of control and there is a possible access to the knowledge of the operator.

It is possible to sum up globally the advantages of fuzzy regulator:

- Advantage in regulation of dynamic and non-linear systems ,
- Effectiveness in a faster attainment of the desiderative magnitude (good repercussion), while analogue

regulator is advantageous for holding the magnitudes of the variable on a desiderative magnitude,
- It is always possible to create the algorithm of fuzzy regulator, although at the expense of a great number of principles.

ACKNOWLEDGMENT

This publication is published thanks to the financial support of the project KEGA 368-043UKF-4/2010 named: Implementation of elements of interactivity in the contentual transformation of professional informatics subjects.

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