

Design of a wind tunnel control system

Xueqin Rong, Yong Liu, Shupo Bu

Department of Electronic and Communication Engineering, Suzhou Institute of Industrial Technology, China

Abstract

This system takes stm32f103c8t6 as the core to control the height of table tennis and display it in real time. It is mainly composed of SCM system, driving device, ultrasonic ranging circuit, key circuit and display circuit. Select the corresponding working mode through the key circuit, use the ultrasonic distance measurement module to measure the distance, control the movement of table tennis by the single-chip microcomputer and display the height position and maintenance time by the high-resolution LCD; the driving device uses the single-chip microcomputer to control the lm358 to drive the DC motor to generate the wind force and adopt PWM speed regulation, the data measured by the ultrasonic is fed back to the single-chip microcomputer to form a closed-loop control, and use the PID control realizes the precise control of table tennis height. The system has the advantages of simple structure, high control accuracy, real-time display of measurement distance and maintenance time.

Keywords

Design, wind, system.

1. Introduction

Wind tunnel is the most effective and commonly used tool for aerodynamic experiments. Its working principle is to generate and control the air flow manually. It is a kind of pipe like equipment used to measure the effect on the aircraft and observe the physical phenomenon. It is mainly used to simulate the gas flow around the aircraft. In this paper, a wind tunnel control system based on stm32f103c8t6 single-chip microcomputer is designed. The single-chip microcomputer realizes the adjustment and control of the speed of DC fan through PWM, while the experimental table tennis of the simulation aircraft is monitored and fed back its position through ultrasonic wave in real time. The position information and position time are displayed by LCD.

2. Design function and scheme design

2.1 Design function

1. Place the small ball at the bottom of the tube, control the small ball to reach the BC section upward within 5 seconds after starting, and maintain it for more than 5 seconds.
2. When the small ball is maintained in BC section, cover the air inlet of the fan with cardboard, and keep the small ball in BC section.
3. Take the coordinates of point C as 0cm and point B as 10cm; use the keyboard to set the height position of the ball (unit: cm). After starting, make the ball stably at the specified height for more than 3 seconds, and the fluctuation shall not exceed ± 1 cm.
4. Display the height position of the ball and the timing of the ball's maintenance status in a proper way in real time.
5. Place the small ball at the bottom of the tube, and control the small ball to reach the a end of the top of the tube upward within 5 seconds after starting, without jumping away, and maintain for more than 5 seconds.
6. Place the ball at the bottom of the tube, and control the ball to complete the following movement within 30 seconds after starting: up to ab section and maintain for 3-5 seconds, down to CD section

and maintain for 3-5 seconds, up to ab section and maintain for 3-5 seconds, down to CD section and maintain for 3-5 seconds, and then rush out the tube upward.

7. When the fan stops, put the small ball into the wind tunnel from the a end by hand. After the small ball enters the wind tunnel, the system will start automatically to control the drop of the small ball to no more than D point, and then maintain it at BC section for more than 5 seconds.

2.2 Scheme design

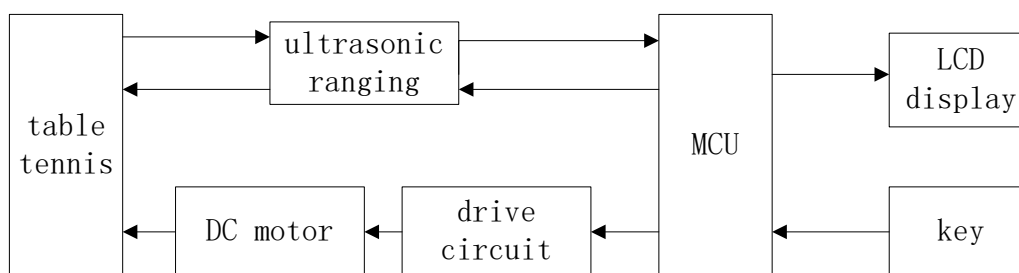


Figure 1 System block diagram

The system block diagram is shown in Figure 1. After power on, press the key, the single-chip microcomputer detects the key information and works according to the set working mode. The single-chip microcomputer sends the information to the ultrasonic sensor, which feeds back the measurement data to the single-chip microcomputer. After analyzing the data, the single-chip microcomputer generates a PWM signal and sends it to the drive circuit to control the speed of the motor so as to control the wind speed and then the height of the small ball. The same as At the same time, MCU controls LCD to display height position and maintenance time in real time.

3. System hardware design

3.1 Motor drive circuit

The driving circuit adopts optocoupler circuit, which makes the front and rear circuits isolated and prevents the rear circuit from affecting the normal operation of the front circuit. Due to the high power of the motor, the parallel shunt mode is adopted in the amplifying circuit, so as to reduce the heat generation of the circuit and prevent the device from burning out.

The amplifier adopts lm358, which includes two independent dual operational amplifiers with high gain and internal frequency compensation. It is suitable for single power supply with a wide range of power supply voltage, and also suitable for dual power supply working mode. Under the recommended working conditions, the power supply current is independent of the power supply voltage. Its application range includes sensor amplifier, DC gain module and all other occasions where operational amplifier can be used with single power supply.

The PWM signal generated by the single-chip microcomputer system is sent out and sent to the drive circuit to generate the drive signal and control the DC motor. The circuit is shown in Figure 2, mainly composed of optocoupler, four Ti lm358 and four NPN type triodes.

3.2 Key input circuit and LCD display circuit

3.2.1 Key input circuit

As shown in Figure 3, the key circuit is mainly composed of four keys, from top to bottom are S5, S4, S3 and S2. Four keys constitute the setting of working mode, among which S5 is the delete key, S4 is the + 1 key, S3 is the - 1 key and S2 is the confirm key. The specified functions can be realized by selecting different working modes by pressing the key.

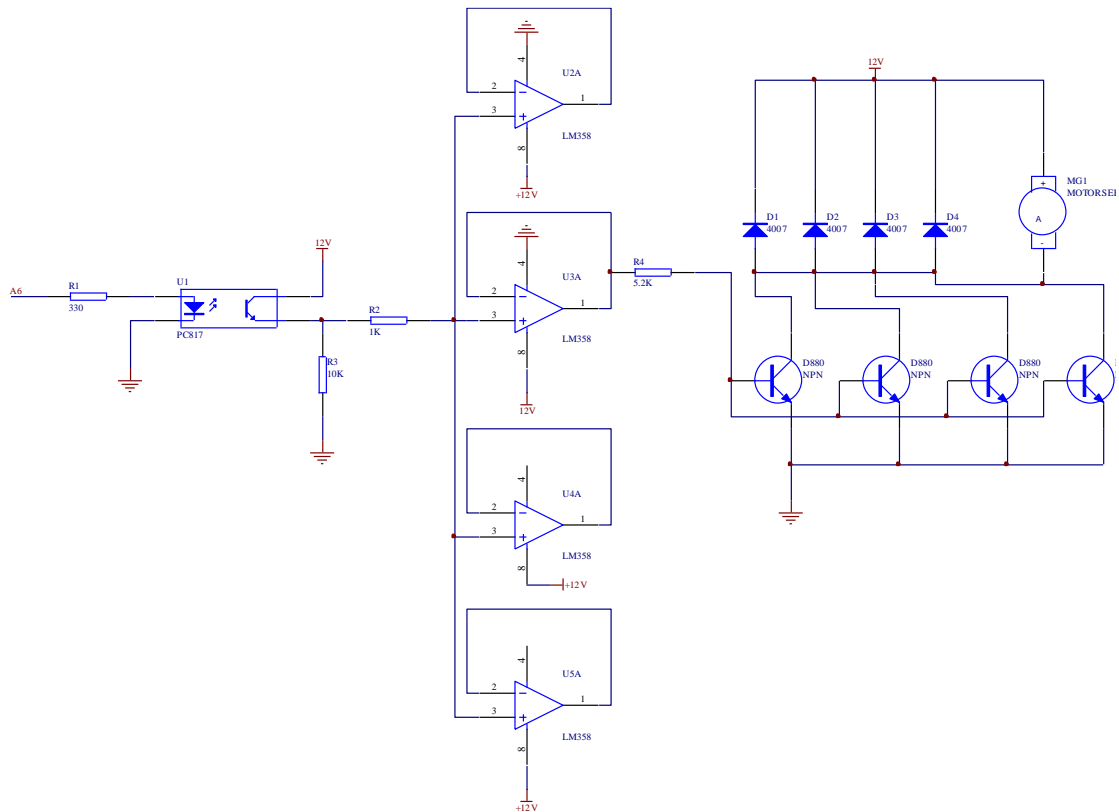


Figure 2 driver circuit

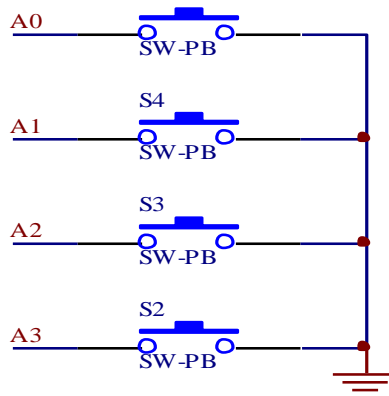


Figure 3 key input circuit

3.2.2 LCD display circuit

LCD display circuit is as shown in Figure 4. LCD12864 LCD display module is selected. MCU sends the current position height and corresponding maintenance time of table tennis to LCD for real-time display.

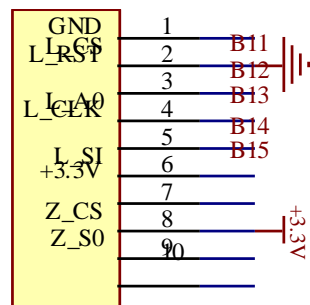


Figure 4 LCD display circuit

3.3 Ultrasonic sensor circuit

The circuit of ultrasonic sensor is as shown in Figure 5. The trig pin and echo pin of ultrasonic sensor are respectively connected with the A7 and A8 of single chip microcomputer. The single chip microcomputer sends signals to the ultrasonic transmitter for transmission. When the sent signals meet the ping-pong ball, they are reflected back and received by the ultrasonic receiver, and then sent to the single chip microcomputer. The single chip microcomputer for the time of transmitting and receiving signals and in the air The current table tennis position is calculated by the propagation speed of.

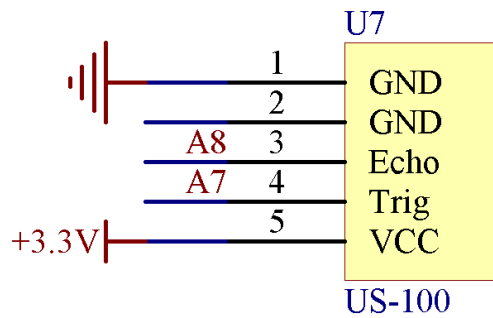


Figure 5 Ultrasonic sensor circuit

4. Software design

The single-chip microcomputer collects the information of the key input circuit to make it work in the corresponding function mode. After the single-chip microcomputer controls the ultrasonic transmitter to transmit the signal, the ultrasonic receiver sends the received signal to the single-chip microcomputer. The single-chip microcomputer calculates the distance, analyzes the current situation, realizes the PID control, and generates the corresponding PWM signal to the drive circuit. At the same time, the single-chip microcomputer also outputs the current position. Information on altitude and maintenance time.

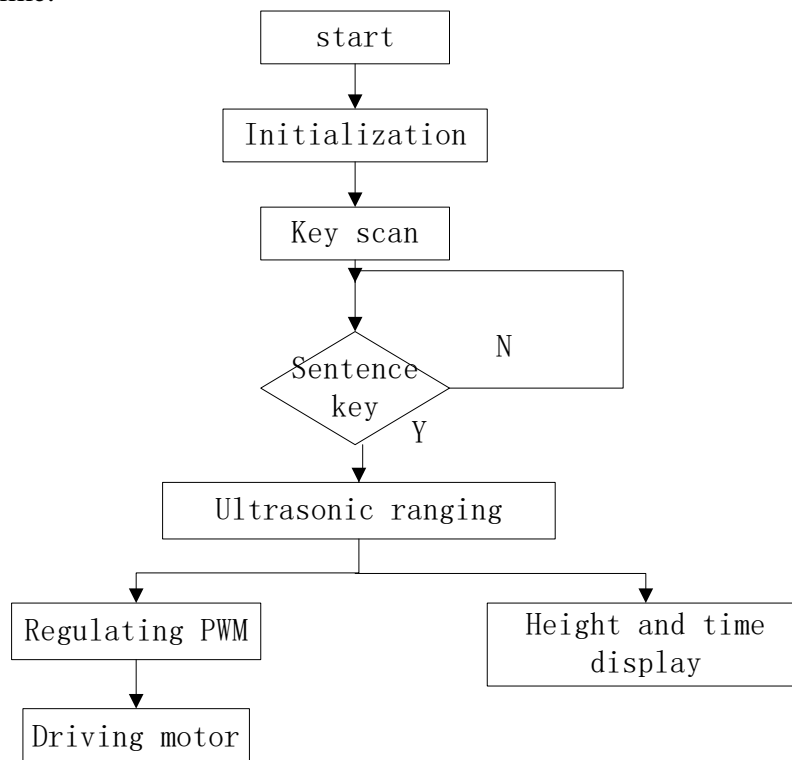


Figure 6 Procedure flow chart

5. Test

5.1 Table tennis height test

After the joint debugging of the system, two table tennis balls are used to set the height positions of 10cm, 25cm and 40cm respectively for testing. The test results are shown in Table 1.

Table I table tennis height position measurement (height in cm)

height	Table Tennis	The first time	The second time	The third time	The fourth time	The fifth time	mean value
10	Nail ball	12	9	10	13	8	10.4
	B ball	11	10	12	8	13	10.8
25	Nail ball	27	25	24	26	25	25.4
	B ball	25	26	26	25	25	25.4
40	Nail ball	40	39	40	40	40	39.8
	B ball	40	40	39	40	40	39.8

5.2 Function test

The system control is divided into mode 1 to mode 5. After the motor is started, press key 2 as mode 1 to realize the small ball starting for 5 seconds to reach BC section and maintain for 5 seconds; then cover one third with long cardboard and keep the small ball in BC section; press key 2 to continue to press key 2 as mode 2, and set the height with key, and maintain at the set height for more than 3 seconds; press key 2 to press the third as mode 3, and it will be small within 5 seconds after starting. When the ball reaches the top of the tube, it does not jump away and lasts for more than 5 seconds; press the fourth button to set mode 4, and the ball moves many times in 30 seconds; press the fifth button to set mode 5, so as to put the ball from above, and the fan controls the ball to fall no more than D points. At the same time, LCD12864 liquid crystal display module is selected to monitor the height position of the small ball to the small ball and the maintenance time of the small ball in real time.

5.3 Test analysis and conclusion

By testing the different height of table tennis, it is found that table tennis is relatively difficult to control in the low position, with slightly lower accuracy. When it is set in the middle position and high position, the control effect is relatively good, and it can basically maintain at the set height, and the stability time is longer.

Using PID algorithm to control the height of table tennis, the adjustment of KP, Ki, KD three parameters is more important, it needs more experiments to achieve better results.

Conclusion

Using stm32f103c8t6 single chip microcomputer to control the DC fan, the position control of the ball in the wind tunnel is realized. In order to better understand the position of the ball, the LCD display is used to display the current position information in real time, and finally the design of the wind tunnel control system is completed. The performance of the system is stable, the function is perfect, and all the design indexes are achieved.

Acknowledgements

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