

Abstract

Steckel hot rolling forms part of the larger steelrolling process. Steckel hot rolling is one the most common type of hot rolling, used in the industry. Presently there is much research and development work being done on the control of rolling mills. This research project concerns the dynamic control of a practical hot rolling mill. The main objective of this research is to develop a

Modelling for Control of a Steckel Hot Rolling Mill

by

Ernst Scholtz

Submitted in partial fulfillment of the requirements for the degree

Master of Engineering (Electronic Engineering)

in the

Faculty of Engineering

UNIVERSITY OF PRETORIA

October 1999

Abstract

Steckel hot rolling forms part of the larger steelmaking process. Steckel hot rolling is not the most common type of hot rolling mill, found in the industry. Steckel mills are normally associated with developing countries and are also very similar to cold rolling mills. The modelling aspect of this dissertation focuses on a practical investigated Steckel rolling mill, which is used in the production of stainless steel strip. Various types of rolling mills that can roll various shapes and dimensions of products are found in the industry, but only hot strip rolling is investigated in this dissertation.

In this dissertation models were identified in order to create a mill simulator that can adequately simulate Steckel rolling mill behaviour. The constructed simulator is able to simulate the thickness crown behaviour of the hot strip as well as the tension in the sheet while rolling. The simulator is not able to simulate the temperature, shape and flatness behaviour of the Steckel rolling process.

The mill simulator consists of a roll gap model, stand model, tension model as well as models accounting for the dynamics associated with the hydraulic actuators. The integration of these models in order to form the mill simulator, and the application of this simulator in an investigation of the interactions in the Steckel rolling mill process is considered a substantial contribution to the literature.

This dissertation forms the basis of a continuing research project, which aim is to apply a model based predictive control method, to regulate the centerline gauge and strip tension in the hot rolling mill. Tension control of the strip is normally associated with multistand hot rolling mills and little literature exists concerned with the tension and gauge interactions associated with the Steckel hot rolling mill process. This dissertation addresses this issue and the dynamic interaction is identified.

The nonlinear mill simulator was used to identify a linear model for control system design. The linear model was identified around a certain operating point associated with a certain pass of a multiple pass rolling schedule. Step tests were applied to the manipulated variables of the nonlinear mill simulator, and by doing system identification a linear time invariant multivariable transfer function model was derived.

Open loop simulation results were compared with time responses found in the literature and practical logged data as far as possible, in order to asses the performance of the mill simulator.

This dissertation ends with an initial control problem formulation and a discussion of how to implement the linear model in a Model Predictive Control (MPC) structure.

Keywords

steelmaking, hot rolling, Steckel rolling mill, dynamic modelling, system identification, control problem formulation, nonlinear, mill simulator, centerline gauge, tension, strip crown

Opsomming

Die Steckel warm walsingproses vorm 'n integrale deel in staal-vervaardiging. Dié wals is egter nie die mees algemene warmwals nie en word hoofsaaklik gebruik in ontwikkelende lande. Die wals is baie soortgelyk aan kouewalse. Die modellering in hierdie verhandeling is gebaseer op 'n praktiese Steckel warmbandwals wat gebruik word om vlekvrye staal band te produseer. Verskeie tipes walse wat verskillende vorme en groottes produkte kan rol bestaan; maar slegs warm band walsing word in hierdie verhandeling ondersoek.

Verskeie modelle is ondersoek om 'n wals-simulator op te stel wat die Steckel wals gedrag akkuraat naboots. Die simulator kan die dikte kroon gedrag en die spanning in die band voorspel. Temperatuur variasies, vorm en platheid word nie deur die simulator in ag geneem nie.

Die wals simulator bestaan uit walsgaping-, walsraamwerk-, en spanning modelle, sowel as modelle vir die hidrouliese aktueerders. Die koppeling en verband ondersoek, tussen die voorafgenoemde modelle word beskou as 'n groot bydrae tot die literatuur.

Die verhandeling is deel van 'n navorsings projek wat ten einde sal poog om model gebaseerde voor-spellings beheer te gebruik om middel dikte en band spanning in die warm wals te reguleer. Spannings beheer word gewoonlik geassosieer met veelvoudige stand warm walse en min literatuur bestaan oor die interaksie tussen spanning en dikte in die Steckel. Hierdie verhandeling beskou die dinamiese interaksie.

Die nie-lineêre simulator is gebruik om 'n lineêre model af te lei wat gesik sou wees om 'n beheerder vir die proses te ontwerp. Die lineêre model was afgelei om 'n werkspunt wat verkty is vanaf 'n tipiese verloop van die veelvoudige verloop wals skedule. Stap toetse is op die gemanipuleerde veranderlikes van die nie-lineêre wals simulator gedoen, en die resultate gebruik om deur middel van stelsel identifikasie 'n linieêre tyd invariante model te verkry. Ope lus tyd simulasiereultate is met die literatuur en praktiese data vergelyk om die doeltreffendheid van die simulator te ondersoek.

Die verhandeling eindig met 'n aanvanklike beheer probleem uiteensetting en bespreek die kwessies omtrent die gebruik van die lineêre model vir die toepassing van model gebaseerde voorspellings beheer.

Sleutelwoorde

staalproses, warmband walsing, Steckel wals, dinamiese modellering, beheerstelsel probleem formulering, nie-lineêre, wals simuleerde, middel plaat uitset dikte, aangelegde plaat spanning, plaat kroon

Acknowledgements

The author wishes to thank the following persons and institutions for their contribution to this dissertation.

Prof. Ian K. Craig, the promoter, for the dedication, leadership and advice undertaken during this dissertation. Furthermore for the motivation and inspiration provided to the author to pursue a Ph.D.

Prof. P. Chris Pistorius for advice regarding the process aspects of this dissertation.

Prof. F. W. Leuschner for making the undertaking of this dissertation a possibility, as well as the opportunity provided to the author to pursue a Ph.D.

Liaan Lewis of Columbus Stainless Steel for organizing of plant visits and personal conversations regarding the Steckel Mill at Columbus Stainless Steel at Middelburg, South Africa. Petrus Bothma, previously of Highveld Steel and Vanadium, for an initial explanation of the Steckel hot rolling mill process. Cobus Potgieter of Columbus Stainless Steel for the excellent effort regarding the completion of the comprehensive questionnaire compiled by the author, and Arno Ferreira of Columbus Stainless Steel with help provided with the logged data of the Steckel mill under consideration.

Gerald Hearns of the University of Strathclyde for providing some crucial literature for this dissertation.

Rudolph Bester of the University of Pretoria for his time and the numerous discussions concerned with the mechanical modelling aspects featured in this dissertation.

Academic staff at the University of Pretoria for advice regarding various aspects of the dissertation, especially Prof. X. Xia and Prof. Y. Yavin; and colleagues: Fernando Camisani, Hans Bekker, Niel Kemp, Martin Smit, Kobus Oosthuizen, Leon Staphorst, Stefan Swanepoel, Bennie Waldeck and Jacques van Wyk.

The Foundation for Research Development for financial assistance during the course of the dissertation. The University of Pretoria that provided funding in order for the author to attend an international training course concerned with hot rolling mill control and technology at the University of Strathclyde, Glasgow.

My parents for creating opportunities for me and their guidance. My brother, sister-in-law, and grandparents for their loving support. I would like to praise the Lord for making everything possible.

This thesis is dedicated to my late mother and grandfather.

Contents

1	Introduction	1
1.1	Background	1
1.2	Dissertation Motivation	3
1.3	Aims and Contributions	4
1.4	Organization	5
2	Process Description	8
2.1	Introduction	8
2.2	General Production Route	8
2.3	Hot Rolling Process Flow	10
2.4	Steckel Finishing Mill	15
2.5	Conclusion	18
3	Simulator model derivation	19
3.1	Introduction	19
3.2	Nonlinear models	19
3.3	Roll gap model	22
3.3.1	Introduction	22
3.3.2	Orowan's differential equation derivation	24
3.3.3	Roll gap variables	27
3.3.3.1	Deformed roll radius	27
3.3.3.2	Friction Coefficient	28
3.3.3.3	Yield stress model	28
3.4	Tension Model	29
3.4.1	Introduction	29
3.4.2	Tension Model	31
3.5	Stand Model	33
3.5.1	Introduction	33

CONTENTS

CONTENTS

3.5.2	Literature review	34
3.5.3	Modelling Assumptions	37
3.5.4	Partial Differential Equation (PDE) Model	37
3.5.5	Four-High Stand	39
3.5.5.1	Top Back Up Roll (TBU)	39
3.5.5.2	Top Work Roll (TWR)	41
3.5.5.3	Bottom Work Roll (BWR)	41
3.5.5.4	Bottom Back-Up Roll (BBU)	42
3.5.6	Two-High stand	42
3.5.6.1	Top Roll Pack	44
3.5.6.2	Bottom Roll Pack	44
3.5.7	Gaugemeter Compensation	45
3.6	The Hydraulic Actuator	48
3.6.1	Introduction	48
3.6.2	Modelling of the dynamic components	49
3.6.2.1	Operation	49
3.6.2.2	Servovalve	49
3.6.2.3	Hydraulic cylinder	51
3.6.2.4	Operation and interaction with stand model	52
3.7	Temperature modelling	54
3.7.1	Introduction	54
3.7.2	Roll gap temperature modelling	55
3.7.3	Coiler furnace models	55
3.7.4	Thermal crown modelling	56
3.8	Conclusion	56
4	Nonlinear plant simulator	57
4.1	Introduction	57
4.2	Simulator inputs	57
4.2.1	Introduction	57
4.2.2	Motivation for the choice of simulation operating point	59
4.2.3	Rolling variables	59
4.3	Roll gap model	60
4.3.1	Solution methodology	60
4.3.2	Physical constants	63

CONTENTS

CONTENTS

4.3.3	Flow chart	64
4.4	Tension Model	64
4.4.1	Solution methodology	64
4.4.2	Flow chart	66
4.5	Stand Model	67
4.5.1	Solution Methodology	67
4.5.2	Two Roller model	72
4.5.2.1	Model equations	72
4.5.2.2	Mass, stiffness and damping elements	74
4.5.2.3	Discretization	77
4.5.2.4	Solution	77
4.5.2.5	Flowchart	78
4.5.3	Physical constants	78
4.5.4	Mill Stretch Model	83
4.6	Hydraulic actuator model	84
4.6.1	Physical constants	84
4.7	Dynamic Simulator	85
4.8	Conclusion	89
5	Simulation results	90
5.1	Introduction	90
5.2	Roll gap model simulations	91
5.3	Nonlinear state-space model	97
5.3.1	Calculation of steady state values	97
5.3.2	Non steady state startup	97
5.4	System Identification	98
5.4.1	Design and results from the step tests	102
5.4.1.1	Combined hydraulic strokes, $\delta x_{L\&R}$	102
5.4.1.2	Speed steps, $\delta v_{bc}, \delta v_{fc}$	107
5.4.1.3	Input thickness disturbance, δh_1	109
5.4.2	Identification	109
5.4.2.1	The model for $g_{11}(s)$	109
5.4.2.2	The model for $g_{21}(s)$ and $g_{31}(s)$	110
5.4.2.3	The model for $g_{22}(s)$ and $g_{33}(s)$	113
5.4.2.4	The model for $g_{12}(s)$	113

CONTENTS

CONTENTS

5.4.2.5	The model for $g_{32}(s)$	115
5.4.2.6	The model for $g_{d11}(s)$	115
5.4.2.7	The model for $g_{d12}(s)$	117
5.4.2.8	The model for $g_{d13}(s)$	117
5.4.3	Suitability of the identified model	118
5.5	Conclusion	119
6	Control Problem Formulation	120
6.1	Introduction	120
6.2	The Control Problem	120
6.2.1	Background	120
6.2.2	Initial control problem formulation	122
6.3	Model predictive control (MPC)	123
6.3.1	Background	123
6.3.2	Why MBPC?	125
6.3.3	MPC theory	126
6.3.4	Control law computation: On-line optimization	127
6.3.5	Stability and constraint handling	128
6.3.6	Tuning of Predictive Control algorithms	128
6.4	Controller specifications	129
6.5	Conclusions	131
7	Conclusion and recommendations	132
7.1	Conclusion	132
7.2	Contribution of this work	133
7.3	Recommendations	134
7.3.1	Modelling and identification projects	134
7.3.2	Control projects	135
A	Appendix A	145
A.1	Rolling Mill Definitions	145
A.2	Four Roller Model	147