

# Dynamic modeling and feedback control of a piezo-based milli-actuator

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**Abstract.** In magnetic disk drive actuators, the application of piezo electric material can be used to refine and accomplish track following in (extremely) high track density magnetic data storage. In this paper the results on the modeling and control of a piezo-based milli-actuator are presented. The modeling is done on the basis of a least squares curve fitting of an estimated frequency response and taking into account uncertainties in the modeled resonance modes of the actuator. The design and implementation of a robust controller provides a high bandwidth and accurate positioning of the tip of the suspension and illustrates the efficiency of the piezo-based milli-actuator.

**Keywords.** System identification; piezoelectric; robust control; high track density recording

## 1 Introduction

An unavoidable trend in magnetic recording is the aim to reduce the size or surface on which the magnetic media has to be stored. Especially, in magnetic disk drives there is an ungoing need to increase the storage capacity and areal density of the disk (Grochowski *et al.*, 1993; Grochowski and Hoyt, 1996). As a result, the track density needs to be increased significantly and the data has to be recorded and read with extreme precision.

The areal density is a combination of track density, measured in track per inch (TPI) in radial direction of the disk and bit density, measured in bits per inch (BPI) in tangential direction of the disk. For future high track density recording applications with areal densities of 10Gbit/in<sup>2</sup>, the track density approaches 25kTPI, yielding a track pitch of 1 $\mu$ m and an allowable servo error of 0.1 $\mu$ m (Miu and Tai, 1995; Grochowski and Hoyt, 1996). These position

requirements go beyond the possibilities of existing hard disk drive mechanisms.

In many of the existing hard disk drive mechanisms, a single Voice Coil Motor (VCM) actuator is used to perform the positioning of the read/write head over the disc surface. Novel design concepts such as advances in head and disk design, interface and channel technologies have allowed the improvement of the storage capacity. However, the development of a faster and more accurate servo mechanism that is able to position the read/write head with increased precision is still an active field of research (Cheung *et al.*, 1996; Koganezawa *et al.*, 1996; Horsley *et al.*, 1997; Guo *et al.*, 1998).

Most of the research is directed towards the design of so-called micro- and milli-actuators. These actuators are used in a dual-stage concept, where the VCM is used for the gross movements, while a second (milli-) actuator is used for the fine movements of the read/write head located at the tip of the suspension. In this way, an accurate and high bandwidth actuator can be obtained that is believed to explore the possibilities for high track density recording (Fan *et al.*, 1995).

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The aim of this paper is to present the results on the modeling and control of a prototype of a piezo electric milli-actuator. The milli-actuator used in this paper is based on the principle of two piezo-electric stacks that are inserted into the E-block, behind the base of the suspension. A schematic picture of this principle is depicted in Figure 1. As indicated in this figure, the push/pull configuration of the piezo stacks is used to achieve a radial displacement of the tip of the suspension. The advantage of this proposed design is that it does not modify the shape of the suspension itself, thereby eliminating the need for suspension redesign.

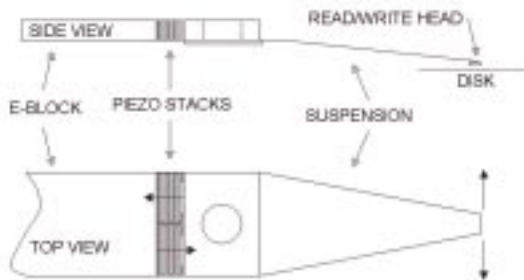


Fig. 1: Principle for piezo electric milli-actuator

The outline of the paper is as follows. First, the modeling of a prototype for the milli-actuator is presented in section 2. The modeling is done by curve fitting a measured frequency response and assuming additional uncertainties in the modeled resonance modes of the suspension and actuator. In section 3, the obtained model with uncertainty is used in an  $H_\infty$ -norm based optimization to design a robust feedback controller for the prototype design. To illustrate the effectiveness of the feedback controlled milli-actuator, in section 3 also the measured closed-loop step responses are presented where the milli-actuator and read/write head suspension is applied to a rotating disk. Finally, the paper is ended by the conclusions and future research topics mentioned in section 4.

## 2 Modeling of milli-actuator

### 2.1 Prototype design

A prototype was built to study the properties of the milli-actuator and the read/write head suspension in interaction with a rotating hard disk. The prototype is used to gather experimental data for modeling purposes and to test feedback controllers being designed. Compared to the configuration depicted in Figure 1, for the prototype a slightly different de-

sign is used. A picture of the prototype being used is depicted in Figure 2.

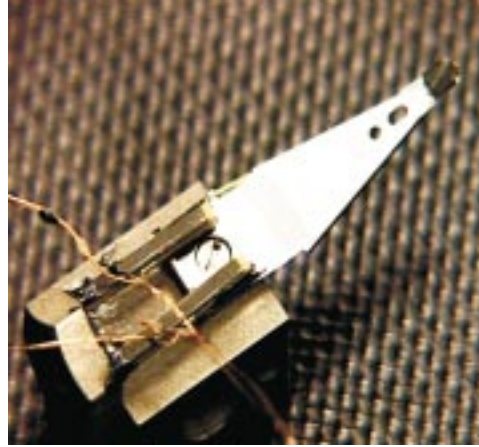


Fig. 2: Bottom view of prototype with special e-block, piezo stacks, wiring and suspension of read/write head

In the prototype design of Figure 2, the connection of the suspension to the e-block is used as a pivoting device. The piezo stacks are attached with cyanoacrylate to the bottom of the suspension and a special e-block. The special e-block is used in order to accommodate the test platform to support the read/write head suspension over a rotating disk, whereas the bottom connection of the stacks provide easy access to the piezo stacks for experimentation purposes.

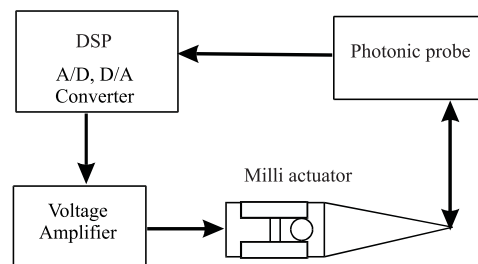


Fig. 3: Experimental set up with DSP, milli-actuator, photonic probe and voltage amplifier

The modeling of the prototype design is done via system identification techniques, where measured time domain data is used to formulate a dynamical model of the the milli-actuator and the read/write head suspension in interaction with a rotating hard

disk. As indicated in Figure 3, the experimental data is obtained by using a photonic probe to measure the relative displacement  $y(t)$  of the read/write head located at the suspension tip. For excitation purposes, the piezo stacks are supplied with a random input voltage  $u(t)$ . The generation of the input voltage  $u$  and the measurement of the relative position  $y$  is done with a Digital Signal Processor (DSP).

To illustrate the attainable static displacement at the suspension tip with the prototype design, an open-loop measured step response is plotted in Figure 4. From Figure 4 it can be observed that for an 8 Volt input voltage step, an average displacement of approximately  $3\mu\text{m}$  is measured at the suspension tip. However, the open-loop behavior of the milli-actuator exhibits many lightly damped resonance modes that need to be modeled and possibly controlled in order to achieve the required position accuracy of  $0.1\mu\text{m}$ .

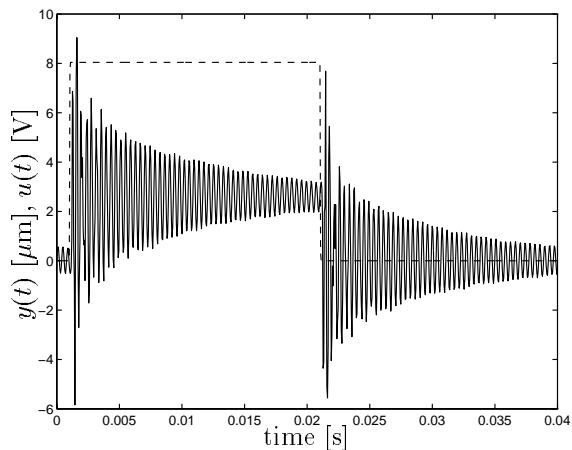


Fig. 4: Measured tip position  $y(t)$  in  $\mu\text{m}$  (—) to a step input  $u(t)$  in voltage (- -)

Since the milli-actuator is a fast responding mechanical system and experiments can be gathered relatively easily, it is advantageous to model the milli-actuator via a frequency domain based system identification technique (Pintelon *et al.*, 1994). In such a system identification technique, a frequency response is measured and used to find a dynamical model by curve fitting the obtained frequency response. For the piezo based milli-actuator depicted in Figure 2, the frequency domain of interest lies between the 100 Hz and the 10 kHz. For this range, a frequency response will be estimated and used to construct a dynamical model for the milli-actuator.

## 2.2 Frequency response estimation

The experimental setup depicted in Figure 3 is used to measure the frequency response of the milli-

actuator. To obtain a frequency response of the milli-actuator, the input signal  $u(t)$ , being the input to the piezo stacks is designed as a sum of 300 sinusoids. Formally, the input  $u(t)$  is given as

$$u(t) = \sum_{k=1}^N a_k \sin(\omega_k t + \phi_k), \text{ with } N = 300 \quad (1)$$

where the frequency grid  $\Omega := (\omega_1, \omega_2, \dots, \omega_N)$  is chosen such that the frequencies  $f_k = \omega_k/(2\pi)$  are distributed approximately logarithmically between 100 Hz and 9 kHz.

The amplitude  $a_k$  in (1) for each sinusoid is kept constant and set to 1, while the phase  $\phi_k$  is chosen randomly using a uniform distribution between  $-\pi$  and  $\pi$ . In this way, a noisy signal input signal  $u(t)$  is obtained with a well defined auto spectrum  $S_{uu}(\omega)$  (Ljung, 1987).

The periodic input signal  $u(t)$  is applied to the piezo stacks of the milli-actuator and the relative displacement  $y(t)$  of the tip of the suspension is measured and stored by the DSP. The signals  $u(t)$  and  $y(t)$  are sampled at 20 kHz and used to estimate the cross spectrum  $S_{yu}(j\omega)$  using spectral analysis (Priestley, 1981).

With the estimated cross spectrum  $S_{yu}(j\omega)$  and the auto spectrum  $S_{uu}(\omega)$ , the frequency response  $G(j\omega_k)$  of the milli-actuator can be estimated along the frequency grid  $\Omega$  via

$$G(j\omega_k) = \frac{S_{yu}(j\omega_k)}{S_{uu}(\omega_k)}$$

An amplitude Bode plot of the estimated frequency response  $G(j\omega_k)$  has been depicted in Figure 5.

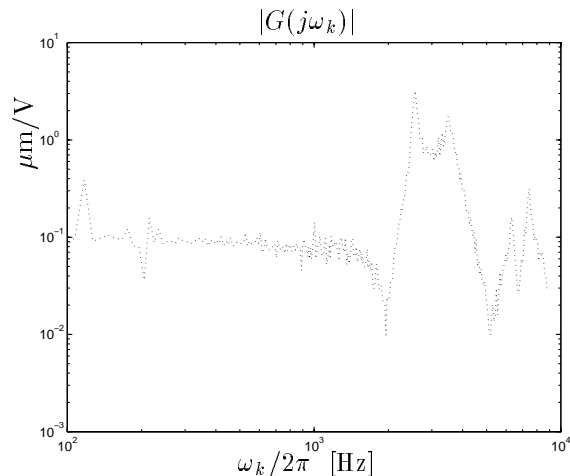


Fig. 5: Amplitude bode plot of measured open-loop frequency response between piezo stack voltage and suspension tip displacement

It can be seen from Figure 5 that the milli-actuator exhibits several lightly damped resonance

modes. It should be noted that the frequency response depicted in Figure 5 is measured while the read/write head at the tip of the suspension was supported by a rotating disk.

### 2.3 Least squares curve fitting

Given the estimated frequency response  $G(j\omega_k)$  along the frequency grid  $\Omega = (\omega_1, \omega_2, \dots, \omega_N)$ , the aim of the frequency domain identification is to find a (discrete time) linear time invariant model  $P$  of limited complexity that approximates the data  $G(j\omega_k)$ . This model can be used to characterize the natural frequency and damping of the resonance modes of the milli-actuator. Additionally, such a discrete time model can be used to design a digital feedback controller.

To address the limited complexity, the SISO model  $P$  to be determined is parametrized in a transfer function representation

$$P(z, \theta) = \frac{b_0 + b_1 z^{-1} + \dots + b_n z^{-n}}{1 + a_1 z^{-1} + \dots + a_n z^{-n}} \quad (2)$$

where  $z = e^{j\omega}$  denote the  $z$ -transform variable and

$$\theta := [b_0 \ b_1 \ \dots \ b_n \ a_1 \ \dots \ a_n]$$

denotes a real valued parameter of unknown coefficients in the transfer function representation given in (2). Furthermore, it can be seen from (2) that the order or complexity of the linear model can be specified with the integer value  $n$ .

The approximation of the data  $G(j\omega_k)$  by the model  $P(z, \theta)$  is addressed by considering the following curve fit error

$$E(j\omega_k, \theta) := [G(j\omega_k) - P(e^{j\omega_k}, \theta)]W(j\omega_k) \quad (3)$$

that needs to be minimized. In (3),  $W(j\omega_k)$  denotes a scalar weighting function used to influence the curve fitting of the frequency response data.

With the definition of the curve fit error in (3), a parameter  $\hat{\theta}$  is estimated by solving the following (non-linear) minimization

$$\hat{\theta} = \arg \min_{\theta} \sum_{k=1}^N E(j\omega_k, \theta) E^*(j\omega_k, \theta)$$

where  $*$  is used to denote the complex conjugate transposed. A computational procedure to address this minimization is presented in de Callafon *et al.* (1996) and used in this paper to find a model  $P(z, \hat{\theta})$  via a LS curve fitting.

### 2.4 Modeling results

Using the estimated frequency response depicted in Figure 5, the LS curve fitting described in the previous section is used to find a dynamical model of

the milli-actuator. The order  $n$  of the discrete time model  $P(z, \theta)$  is set to 10 in order to capture the various resonance modes present in the estimated frequency response. The weighting  $W(j\omega_k)$  in (3) is set to the inverse of the data  $G(j\omega_k)$  so as to minimize a relative curve fit error

$$E(j\omega_k, \theta) = \frac{[G(j\omega_k) - P(e^{j\omega_k}, \theta)]}{G(j\omega_k)}.$$

The LS curve fitting procedure of de Callafon *et al.* (1996) is used and the results have been depicted in Figure 6.

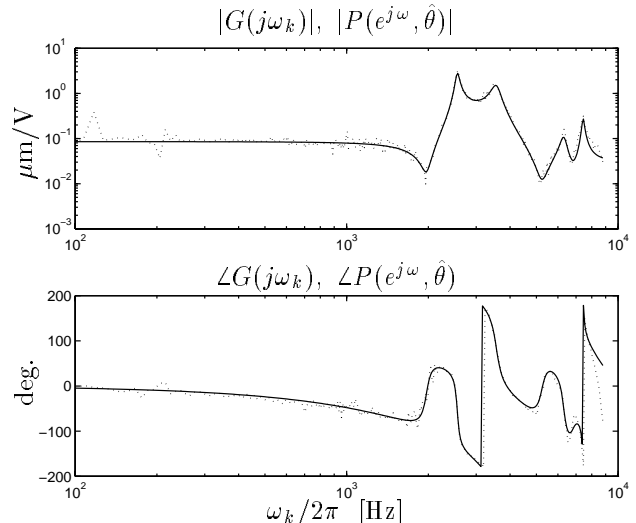


Fig. 6: Bode plot of measured frequency response (dotted) and 10th order linear time invariant model (solid)

It can be observed from Figure 6 that the dominant frequency modes have been modeled accurately by the estimated model  $P(z, \hat{\theta})$ . The model  $P$  can be used for the design of a servo controller for the milli-actuator. However, to design a robust controller, uncertainties and product variability in the milli-actuator have to be taken into account.

### 2.5 Modeling uncertainties

To design a robust performing servo controller for the milli-actuator, uncertainties in the modeled resonance modes of the actuator have to be taken into account. In this paper, the uncertainties in the milli-actuator are modeled by assuming that the nominal model  $\hat{P} = P(z, \hat{\theta})$  is allowed to be perturbed to a model  $P$  via a unstructured bounded multiplicative perturbation  $\Delta$  (Zhou *et al.*, 1996). In this way, a set of models  $\mathcal{P}$  is found that is given by

$$\mathcal{P} = \{P \mid P = \hat{P}(1 + \Delta), \|\mathcal{W}\Delta\|_{\infty} < 1\} \quad (4)$$

where  $W$  is stable and stably invertible frequency dependent weighting function.

In order to pursue the design of a robust controller, a choice for the weighting function  $W$  in (4) is made. The choice for  $W$  is based on the assumption that the frequency response of the nominal model  $\hat{P}$  around the zeros at 1.9 and 5.2 kHz and the two resonance modes at 2.5 and 3.5 kHz are allowed to vary. With a possible choice for the weighting filter  $W$  depicted in Figure 7 on the top, the a resulting mplitude Bode plot of the models  $P$  within the set  $\mathcal{P}$  of (4) is guaranteed to lie between the dashed lines depicted in Figure 7 at the bottom.

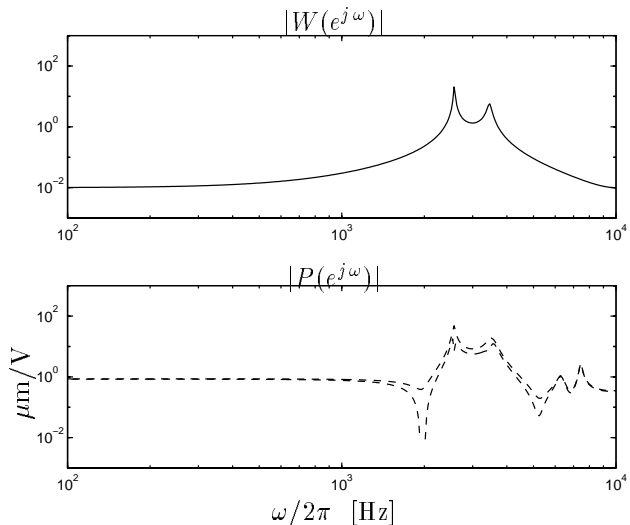


Fig. 7: Weighting function  $W$  (4th order) and amplitude Bode plot range of models  $P$  in (4)

Given the nominal model  $\hat{P}$  and the multiplicative uncertainty with the stable and stable invertible frequency dependent weighting function  $W$  in (4), a robust servo controller for the milli-actuator can be designed.

### 3 Control of milli-actuator

#### 3.1 Robust control design

For the design of a controller, consider the block scheme depicted in Figure 8.

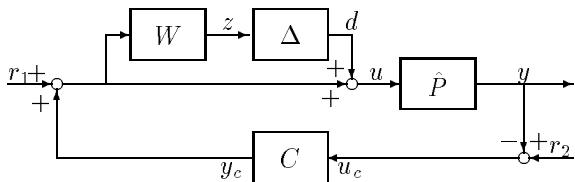


Fig. 8: Feedback controller  $C$  design of nominal model  $\hat{P}$  with multiplicative uncertainty

In Figure 8, the models  $P$  within the set  $\mathcal{P}$  of (4) are represented by the nominal model  $\hat{P}$  and a weighted  $W$  multiplicative uncertainty  $\Delta$ . In case  $\Delta = 0$ , Figure 8 simply represents the feedback connection of the nominal model  $\hat{P}$  and the controller  $C$ . In that case, the map between  $col(r_2, r_1)$  and  $col(y, u)$  is given by the transfer function matrix  $T(\hat{P}, C)$  with

$$T(\hat{P}, C) = \begin{bmatrix} \hat{P} \\ I \end{bmatrix} (I + C\hat{P})^{-1} \begin{bmatrix} C & I \end{bmatrix} \quad (5)$$

where  $r_2$  indicates the suspension tip position reference signal and  $r_1$  a piezo voltage feedforward signal.

For the design of a feedback controller  $C$  that robustly stabilizes the feedback connection depicted in Figure 8 for all  $P \in \mathcal{P}$  given in (4), a  $\mu$ -synthesis is used (Zhou *et al.*, 1996). For that purpose, the block diagram of Figure 8 is rewritten in the standard plant configuration of Figure 9.

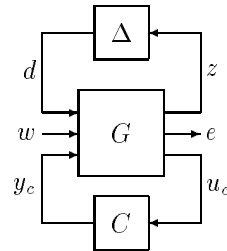


Fig. 9: Standard plant configuration

Most of the signals used in Figure 9 can be found back in Figure 8. Using the signal  $w$  and  $e$  to indicate respectively  $col(r_2, r_1)$  and  $col(y, u)$  it can be seen that  $G$  in Figure 9 is given by

$$G = \begin{bmatrix} 0 & 0 & W & W \\ \hat{P} & 0 & \hat{P} & \hat{P} \\ I & 0 & I & I \\ -\hat{P} & I & -\hat{P} & -\hat{P} \end{bmatrix} \quad (6)$$

and consists of the previously determined nominal model  $\hat{P}$  and weighting function  $W$ . Additionally, the (performance) signals  $w$  and  $e$  can be weighted to incorporate additional performance specifications.

The standard plant configuration can be used in a  $\mu$ -synthesis to design a robustly stabilizing or robustly performing feedback controller  $C$ . Subsequently, the designed feedback controller has to be reduced in order to be implementable in a DSP environment. The feedback controller  $C$  designed with the  $\mu$ -synthesis toolbox (Balas *et al.*, 1995) has a McMillan degree of 25. This can be reduced to the

order of 5 using a closed-loop reduction technique (Wortelboer, 1993) without significant performance deterioration of the designed feedback system. The Bode plot of the final design of a 5th order linear discrete time controller that can be implemented on the milli-actuator is depicted in Figure 10.

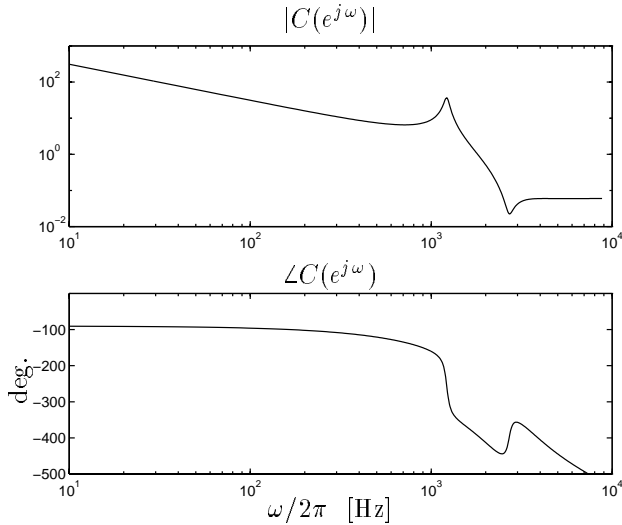


Fig. 10: Bode plot of 5th order robust linear feedback controller

As can be seen from Figure 10, the designed feedback controller  $C$  has integral action and has a sharp role-off at the area where the model uncertainty becomes larger.

### 3.2 Implementation of control

The experimental setup depicted in Figure 3 is used to implement the designed feedback controller on the DSP system using a sample frequency of 20 kHz. To illustrate the effect of the feedback control on the dynamical behavior of the milli-actuator, first an experimentally obtained closed-loop frequency response of the milli-actuator is presented in Figure 11.

The amplitude Bode plot in Figure 11 represent the estimated frequency response of the transfer function  $P(I+CP)^{-1}C$  between suspension tip position reference signal  $r_2$  and suspension tip displacement  $y$  in Figure 8. Similar as the previously discussed experimental results, the frequency response is estimated while the suspension is applied to a rotating disk. Compared to the open-loop frequency response depicted in Figure 5, it can be seen that a significant reduction of the resonance modes has been obtained. Furthermore, the milli-actuator is able to track signals up to approximately 1.5 kHz.

The improved control of the flexible resonance modes in the suspension with the milli-actuator can

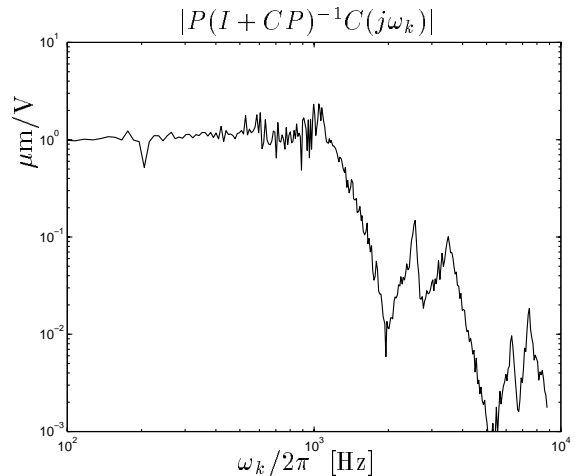


Fig. 11: Amplitude bode plot of measured closed-loop frequency response between suspension tip position reference and suspension tip displacement

also be seen from an experimentally obtained closed-loop step response. To illustrate the attainable closed-loop controlled static displacement, a closed-loop step response has been depicted in Figure 12.

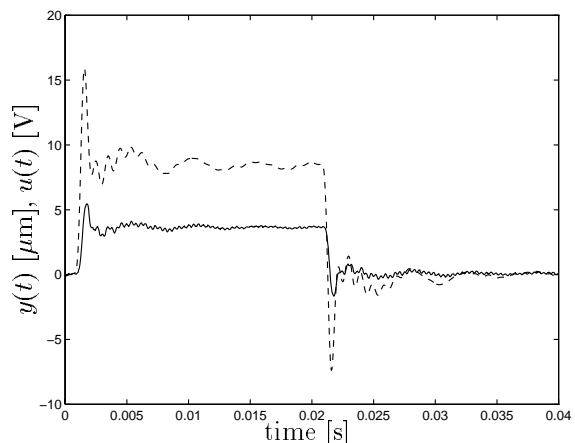


Fig. 12: Measured tip position  $y(t)$  in  $\mu\text{m}$  (—) and feedback control signal  $u(t)$  in voltage (--) to a step on suspension tip position reference signal  $r_2$

Compared to the open-loop step response depicted in Figure 4, it can be seen from Figure 12 that indeed a significant reduction of the flexible modes in the suspension and the milli-actuator has been achieved. Moreover, the milli-actuator is able to achieve the position accuracy requirement of  $0.1\mu\text{m}$  in the step tests and has a settling time of less than 10ms.

## 4 Conclusions

In this paper the results on the modeling and control of a piezo-based milli-actuator are presented. The modeling is based on an experimental data and uses frequency domain identification techniques to curve fit an estimated frequency response. Modeling uncertainties and product variability in the milli-actuator are taken into account by assuming a weighted multiplicative uncertainty for the nominal model being estimated. For that purpose, a frequency dependent weighting function is chosen. However, it is worthwhile to develop a systematic procedure to estimate the contributions of modeling uncertainties in more detail on the basis of experimental data.

The model and suggested modeling uncertainty are used in a robust control design. The order of the designed controller is reduced for to address implementation issues on a DSP. The implementation of the feedback controller provides a high bandwidth and accurate positioning of the tip of the suspension and illustrates the efficiency of the piezo-based milli-actuator. The piezo stack are not only able to move the tip of the suspension but are also able to control the flexibilities in the suspension for increased position performance requirements of the read/write head. Although only the control of the milli-actuator is addressed in this paper, extension to dual-stage control that includes the voice coil motor are in line of the work presented in this paper.

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