

Description

This invention relates to apparatus for generating a velocity profile for movement of a body by a servo system.

Many current magnetic recording disk files employ servo systems for controlling the movement of one or more magnetic heads to different concentric recording tracks on the magnetic recording disk or disks (track seeking) and for maintaining the head or heads accurately positioned over the center of the selected track or tracks during read or write operations (track following). At the start of a track seeking operation, most of such systems generate a velocity command or curve which is a measure of the desired velocity of the heads in moving from one track to the selected new track location. As would be expected, this velocity command is a function of the distance to be moved by the head or heads, the desired velocity being higher the longer the distance to be moved. Prior art disk files usually generated different velocity curves or trajectories for different seek lengths using a number of different techniques.

However, velocity trajectory implementation has always presented practical difficulties to the servo designer. Some disk files use a multiplier technique, while others use a diode breakpoint network. Both the multiplier and the diode network have many deficiencies. The diode breakpoint causes large disturbances or "bumps" in the current waveform. The multiplier is not very flexible in terms of curve shape, suffers dc drift, and it suffers in the transition to the so-called linear region.

The use of a digital trajectory curve solves virtually all of the above problems associated with the diode breakpoint and multiplier techniques, but it has several problems of its own. The digital curve requires an unreasonable volume of points to be stored in a look-up table to get a reasonable resolution of position vs. velocity.

The present invention seeks to provide a system which overcomes the problems arising from the required storage volume and the resolution deficiencies of the standard digital curve.

US-A-4143310 discloses a servo system for positioning a body, which includes a memory in which a reference velocity table is stored and data processing means responsive to signals indicative of the current position and velocity of the body to address the memory to obtain a reference velocity signal, whereby the position region associated to each reference velocity signal decreases in the direction of the target.

According to the invention there is provided an apparatus for generating a velocity profile for movement of a body by a servo system to a target position, said velocity profile representing the desired velocity of the body dependent on its current position, the apparatus comprising means for generating a digital address signal indicative of the distance the body is from the target position, an addressable memory responsive to

said address signal to provide a predetermined number of values of the desired velocity and means for utilising the value currently put out by the memory as a velocity command, the apparatus being characterised by the body being a disk file transducer support arm, further by means for generating a difference count signal which is continuously indicative of the distance remaining to be moved by said body, means for generating a digitized position error signal, and means for combining said difference count signal and said position error signal to produce said digital address signal, the difference count representing the high-order bits and the position error signal representing the low-order bits, means for generating an output address format supplied to said memory, a first part of the output address selecting one of a plurality of segments of the distance, said servo system is to move said body, each of said segments being half the size of the preceding segment, and a second part of the output address selecting a predetermined number of values for the desired velocity of said body within a respective segment, the predetermined number being the same for each of said segments.

How the invention can be carried out will now be described by way of example, with reference to the accompanying drawings, in which:

Figs. 1A, 1B and 1C are diagrams showing different prior art implementations of velocity curve generation;

Fig. 2 represents apparatus embodying the invention;

Fig. 3 is a graph of an input/output relationship produced by apparatus embodying the invention;

Fig. 4 is a flow chart illustrating the operation of the present invention;

Fig. 5 is a graph of an input/output relationship generated in accordance with the present invention with a lower resolution than the curve of Fig. 3;

Fig. 6 is a velocity trajectory for a current magnetic disk file;

Fig. 7 is a modification of the trajectory curve of Fig. 6 using the sliding mask technique of the present invention;

Fig. 8 contains graphs of variations in the current, velocity and PES during a seek operation in a current disk file whose velocity trajectory is shown in Fig. 6; and

Fig. 9 shows the improvement in the current graph of Fig. 8 obtained by use of the present invention.

Figs. 1A, B, C show block diagrams of the aforementioned prior art techniques.

Fig. 2 shows how the sliding mask 31 of the present invention is inserted into a digital curve implementation. The key concept of the present sliding mask technique is that high resolution in position is not necessary at large values of velocity command. The resolution must be better and better as the servo approaches the target.

As seen in Fig. 2, one of the inputs to the sliding mask is the difference count, which is a count of

the difference between the present track location of the head and the location of the track to which the head is to be moved. This difference count is decremented with each track crossing by the head and reaches zero when the head reaches the selected track, as is well known in the art. The other input to the sliding mask 31 is the digitized position error signal (PES) from the digital servo system. This PES signal is generated from signals produced in the disk file servo read head during track crossings. These inputs are operated on to form an output address which is the input to a look-up table in the form of a programmable read only memory (PROM) 32. The output from PROM 32 is a group of digitized values for the velocity curve. If a digital servo is employed, these digitized values can be utilized directly as the digital velocity command. If an analog servo system is used, the digital values can be converted to analog values in a digital-to-analog converter (DAC) 33.

The sliding mask technique involves dividing the length of the desired velocity curve into a number of segments from the beginning of the curve, each segment being one half the size of the preceding segment. For each segment there is stored an equal number of values for the velocity curve for that segment and these velocity values are used to generate the velocity curve during each segment. This has the effect of reducing the resolution of the curve in the early or high velocity segments of the curve and providing much higher resolution in the critical lower portion of the curve as the head approaches the on track position. This is so because in the lower portions of the curve each segment is much smaller than the early segments, but each segment has the same number of velocity curve values available. This greatly reduces the memory size required to store the velocity value while giving totally acceptable or improved system performance.

The operation of the present invention can best be understood by reference to the curve of Fig. 3 and the flow chart of Fig. 4. The curve of Fig. 3 shows the generation of the addresses in PROM 32 by which velocity values stored in PROM 32 can be retrieved. As indicated, the curve is divided into segments, the first such segment being segment 0, with each succeeding segment being one half the length of the preceding segment. Referring to Fig. 4, this shows in flow chart form the operation of the present invention for a mask length M_1 of 5 bits, the number of difference count bits DC_n equal to 8 bits, and the number of digitized PES bits P_n equal to 5.

If the difference count is zero, the sliding mask technique of this invention is not used, since the servo system is in its linear range. If the difference count is not zero, the input address for the sliding mask is formed as represented by block 41. The format of the input address is shown to the right of box 41 and includes the eight difference count bits DC_0-DC_7 and the five digitized PES bits P_0-P_4 . The next step is to initialize the segment number, as represented by block 42. As indicated

to the right of box 42, the segment number is encoded in three bits NS_0-NS_2 , and at the start of a seek, it would be initialized to segment 0, as is apparent from Fig. 3.

Next, the 13 bit register R is loaded with the 13 bit input address, as represented in block 43. The value of the input address in register R is checked to determine if the value of the most significant bit therein, R_{12} , is 1. (block 44) If it is (as it would be at the start of a long seek, for example) the output address is formed (block 46) using the segment number N_s and the five bits $R_{11}-R_7$ to the right of bit R_{12} in register R. This output address is then used (block 47) to address locations in PROM 32 where the required velocity values are stored. Using a mask length M_1 of 5 bits permits the addressing of 32 PROM locations to retrieve 32 velocity curve values for each segment. This is shown in Fig. 3 with the 32 staircase values for the sliding mask output in segment 0, and the output velocities 32 staircase values in Fig. 7.

The sliding mask aspect of the invention occurs when R_{12} in register R no longer has a value of 1, indicating that the servo system has moved the head past the inner boundary of segment 0. When this occurs (block 48), the segment number N_s is incremented by one and register R is shifted one bit to the left so that bit R_{11} therein is now the most significant bit in the register. This produces a "yes" output from block 44 so that the output address is now formed from segment number S , and the five bits to the right of bit R_{11} in register R. This permits the addressing of 32 locations in PROM 32 to access 32 values for segment 1 of the velocity curve. Since segment 1 is only half as long as segment 0, it can be seen from Fig. 3 and Fig. 7 that this results in an increase in the resolution of the segment 1 portion of the curve relative to that of segment 0.

The above process continues through the eight segments which are encoded in the three segment number bits NS_0-NS_2 , resulting in the retrieval and use of 32 velocity curve values for each segment and producing a velocity curve of increasing resolution as the head approaches the on track position, as is apparent from Fig. 7.

The improved resolution obtainable using a mask length M_1 of 5 bits as compared to that resulting from a mask length of 3 bits (and hence 8 velocity curve values per segment) is apparent from a comparison of Figs. 3 and 5.

Thus, the output is formed by sliding a mask M_1 bits long to the right as the distance to the target gets smaller. The resolution in position (R_x) then varies with position,

$$N_s = \text{Segment Number} \\ M_1 = \text{Mask Length in Bits}$$

$$R_x(N_s) = \frac{2^{(-N_s-1)} X_{\max}}{2^{M_1}} \quad (1)$$

$$= 2^{(-N_s-M_1-1)} X_{\max} \quad (2)$$

where,

$X_{\max}$ = maximum distance for which curve is defined.

An important point is that in almost any velocity trajectory technique, when the linear region is met (usually X is less than $TW/2$), the velocity command comes directly from the PES, or input address, and the curve or look up table is bypassed.

The storage size of the look-up table required for the present invention is:

$$N_{sm} = N_{dc} 2^{M_1} \quad (3)$$

where

N_{sm} = PROM storage size required (words)

N_{dc} = number of bits in difference count

M_1 = mask length in bits

For the standard digital curve technique, the required storage size is:

$$N_{sc} = 2^{N_{dc}} \times 2^{N_{pes}} \quad (4)$$

where

N_{sc} = standard digital curve look up table size

N_{pes} = number of bits in digitized PES.

For a comparison of storage size requirements, assume $N_{dc} = 8$, $N_{pes} = 5$, $M_1 = 5$.

For the present technique, $N_{sm} = 256$ words.

For the standard digital method, $N_{sc} = 8096$ words.

So the sliding mask technique of the present invention requires 32 times less storage for the same resolution at low velocities. (With given assumptions).

Fig. 6 shows the diode breakpoint velocity trajectory used in a current disk file. Fig. 7 shows the same curve implemented with the sliding mask technique of this invention. The absence of diode breakpoints can be clearly seen in Fig. 7.

Fig. 8 shows basic seek waveforms for the current disk file whose velocity trajectory is shown in Fig. 6. For exactly the same servo, with a sliding mask digital curve, the same basic seek waveforms appear in Fig. 9. The improved current waveform for the sliding mask can be noted. Also, it has been found that the sliding mask method produces increased speed in total seek time.

Claims

1. Apparatus for generating a velocity profile for movement of a body by a servo system to a target position, said velocity profile representing the desired velocity of the body dependent on its current position, the apparatus comprising means for generating a digital address signal indicative of the distance the body is from the target position, an addressable memory responsive to said address signal to provide a predetermined number of values of the desired velocity and means for utilising the value currently put out by the memory as a velocity command, the apparatus being characterised by the body being a disk file transducer support arm, further by

means for generating a difference count signal ($DC_0 \dots 7$) which is continuously indicative of the distance remaining to be moved by said body, means for generating a digitized position error signal ($P_4 \dots 0$), and means (31) for combining said difference count signal and said position error signal to produce said digital address signal ($R_{12} \dots 0$), the difference count representing the high order bits and the position error signal representing the low-order bits, means for generating an output address format (OA) supplied to said memory, a first part ($NS_2 \dots 0$) of the output address selecting one of a plurality of segments of the distance said servo system is to move said body, each of said segments being half the size of the preceding segment, and a second part ($R_{11} \dots 7$) of the output address selecting a predetermined number of values for the desired velocity of said body within a respective segment, the predetermined number being the same for each of said segments.

2. Apparatus as claimed in claim 1, in which said body is a magnetic disk file actuator arm carrying at least one position transducer, and said position error signal is generated in said transducer as said transducer crosses different concentric tracks on one of the disks in said disk file.

3. Apparatus as claimed in claim 2, in which said memory is a programmable read only memory.

4. Apparatus as claimed in any preceding claim, in which said desired velocity values are in digital form.

5. Apparatus as claimed in claim 4, further including converter means for converting said desired digital values in digital form into analog form.

Patentansprüche

1. Vorrichtung zur Erzeugung eines Geschwindigkeitsprofils für die Bewegung eines Körpers durch ein Servosystem in eine Ziellage, wobei das Geschwindigkeitsprofil die gewünschte Geschwindigkeit des Körpers abhängig von seiner aktuellen Lage darstellt, wobei die Vorrichtung Mittel zur Erzeugung eines digitalen Adressensignals, welches den Abstand, in dem sich der Körper von seiner Ziellage befindet, angibt, einen adressierbaren Speicher, welcher auf das Adressensignal mit der Lieferung einer bestimmten Anzahl von Werten der gewünschten Geschwindigkeit anspricht, und Mittel zur Verwendung des aktuell durch den Speicher ausgegebenen Werts als Geschwindigkeitsbefehl umfaßt, wobei die Vorrichtung dadurch gekennzeichnet ist, daß der Körper ein Wandlerträgerarm einer Plattendatei ist, ferner gekennzeichnet ist durch Mittel zur Erzeugung eines Differenzzählsignals ($DC_0 \dots 7$), welches kontinuierlich den Abstand angibt, um den sich der Körper noch bewegen muß, Mittel zur Erzeugung eines digitalisierten Lagefehlersignals ($P_4 \dots 0$), und Mittel (31) zur Kombinierung des Differenzzählsi-

where,

$X_{\max}$ = maximum distance for which curve is defined.

An important point is that in almost any velocity trajectory technique, when the linear region is met (usually X is less than $TW/2$), the velocity command comes directly from the PES, or input address, and the curve or look up table is bypassed.

The storage size of the look-up table required for the present invention is:

$$N_{sm} = N_{dc} 2^{M_1} \quad (3)$$

where

N_{sm} = PROM storage size required (words)

N_{dc} = number of bits in difference count

M_1 = mask length in bits

For the standard digital curve technique, the required storage size is:

$$N_{sc} = 2^{N_{dc}} \times 2^{N_{pes}} \quad (4)$$

where

N_{sc} = standard digital curve look up table size

N_{pes} = number of bits in digitized PES.

For a comparison of storage size requirements, assume $N_{dc}=8$, $N_{ps}=5$, $M_1=5$.

For the present technique, $N_{sm}=256$ words.

For the standard digital method, $N_{sc}=8096$ words.

So the sliding mask technique of the present invention requires 32 times less storage for the same resolution at low velocities. (With given assumptions).

Fig. 6 shows the diode breakpoint velocity trajectory used in a current disk file. Fig. 7 shows the same curve implemented with the sliding mask technique of this invention. The absence of diode breakpoints can be clearly seen in Fig. 7.

Fig. 8 shows basic seek waveforms for the current disk file whose velocity trajectory is shown in Fig. 6. For exactly the same servo, with a sliding mask digital curve, the same basic seek waveforms appear in Fig. 9. The improved current waveform for the sliding mask can be noted. Also, it has been found that the sliding mask method produces increased speed in total seek time.

Claims

1. Apparatus for generating a velocity profile for movement of a body by a servo system to a target position, said velocity profile representing the desired velocity of the body dependent on its current position, the apparatus comprising means for generating a digital address signal indicative of the distance the body is from the target position, an addressable memory responsive to said address signal to provide a predetermined number of values of the desired velocity and means for utilising the value currently put out by the memory as a velocity command, the apparatus being characterised by the body being a disk file transducer support arm, further by

means for generating a difference count signal ($DC_0 \dots 7$) which is continuously indicative of the distance remaining to be moved by said body, means for generating a digitized position error signal ($P_4 \dots 0$), and means (31) for combining said difference count signal and said position error signal to produce said digital address signal ($R_{12} \dots 0$), the difference count representing the high order bits and the position error signal representing the low-order bits, means for generating an output address format (OA) supplied to said memory, a first part ($NS_2 \dots 0$) of the output address selecting one of a plurality of segments of the distance said servo system is to move said body, each of said segments being half the size of the preceding segment, and a second part ($R_{11} \dots 7$) of the output address selecting a predetermined number of values for the desired velocity of said body within a respective segment, the predetermined number being the same for each of said segments.

2. Apparatus as claimed in claim 1, in which said body is a magnetic disk file actuator arm carrying at least one position transducer, and said position error signal is generated in said transducer as said transducer crosses different concentric tracks on one of the disks in said disk file.

3. Apparatus as claimed in claim 2, in which said memory is a programmable read only memory.

4. Apparatus as claimed in any preceding claim, in which said desired velocity values are in digital form.

5. Apparatus as claimed in claim 4, further including converter means for converting said desired digital values in digital form into analog form.

Patentansprüche

1. Vorrichtung zur Erzeugung eines Geschwindigkeitsprofils für die Bewegung eines Körpers durch ein Servosystem in eine Ziellage, wobei das Geschwindigkeitsprofil die gewünschte Geschwindigkeit des Körpers abhängig von seiner aktuellen Lage darstellt, wobei die Vorrichtung Mittel zur Erzeugung eines digitalen Adressensignals, welches den Abstand, in dem sich der Körper von seiner Ziellage befindet, angibt, einen adressierbaren Speicher, welcher auf das Adressensignal mit der Lieferung einer bestimmten Anzahl von Werten der gewünschten Geschwindigkeit anspricht, und Mittel zur Verwendung des aktuell durch den Speicher ausgegebenen Werts als Geschwindigkeitsbefehl umfaßt, wobei die Vorrichtung dadurch gekennzeichnet ist, daß der Körper ein Wandlerträgerarm einer Plattendatei ist, ferner gekennzeichnet ist durch Mittel zur Erzeugung eines Differenzzählsignals ($DC_0 \dots 7$), welches kontinuierlich den Abstand angibt, um den sich der Körper noch bewegen muß, Mittel zur Erzeugung eines digitalisierten Lagefehlersignals ($P_4 \dots 0$), und Mittel (31) zur Kombination des Differenzzählsi-



gnals und des Lagefehlersignals zur Erzeugung des digitalen Adresssignals ($R_{12} \dots 0$), wobei die Differenzählung die Bits hoher Ordnung und das Lagefehlersignal die Bits niedriger Ordnung darstellt, Mittel zur Erzeugung eines dem Speicher zugeführten Ausgangsadressenformats (OA), wobei ein erster Teil ($NS_2 \dots 0$) der Ausgangsadresse eines aus einer Anzahl von Segmenten des Abstandes, um welchen das Servosystem den Körper bewegen soll, auswählt, wobei jedes der Segmente halb so groß ist wie das vorhergehende Segment, und ein zweiter Teil ($R_{11} \dots 7$) der Ausgangsadresse eine bestimmte Anzahl von Werte für die gewünschte Geschwindigkeit des Körpers innerhalb eines betreffenden Segments auswählt, wobei die bestimmte Anzahl die gleiche für jedes der Segmente ist.

2. Vorrichtung nach Anspruch 1, bei welcher der Körper ein Magnetplattendatei-Stellerarm ist, welcher wenigstens einen Lagesensor trägt, und das Lagefehlersignal in dem Sensor erzeugt wird, wenn der Sensor verschiedene konzentrische Spuren auf einer der Platten in der Plattendatei überquert.

3. Vorrichtung nach Anspruch 2, bei welcher der Speicher ein programmierbarer Lesespeicher ist.

4. Vorrichtung nach irgendeinem vorstehenden Anspruch, bei welcher die gewünschten Geschwindigkeitswerte digitale Form haben.

5. Vorrichtung nach Anspruch 4, welche ferner Umsetzungsmittel zur Umsetzung der gewünschten Digitalwerte in digitaler Form in analoge Form enthält.

Revendications

1. Dispositif destiné à générer un profil de vitesse pour le mouvement d'un corps vers une position objectif, sous la commande d'un système d'asservissement, ce profil de vitesse représentant la vitesse désirée du corps en fonction de sa position courante, le dispositif comprenant des moyens destinés à générer un signal d'adresse numérique représentatif de la distance du corps par rapport à la position objective, une mémoire adressable qui fonctionne sous la dépendance du signal d'adresse de façon à fournir un nombre

prédéterminé de valeurs de la vitesse désirée, et des moyens destinés à utiliser la valeur courante émise par la mémoire en tant qu'ordre de vitesse, le dispositif étant caractérisé par le fait que le corps est un bras de support de transducteur d'unité de disques, et en outre par des moyens destinés à générer un signal de compte de différence ($DC_0 \dots 7$) qui représente continuellement la distance restant à parcourir par le corps, des moyens destinés à générer un signal d'erreur de position numérisé ($P_4 \dots 0$), et des moyens (31) destinés à combiner le signal de compte de différence et le signal d'erreur de position, pour produire le signal d'adresse numérique ($R_{12} \dots 0$), le compte de différence représentant les bits d'ordre supérieur et le signal d'erreur de position représentant les bits d'ordre inférieur, des moyens destinés à générer un format d'adresse de sortie (OA) qui est appliqué à la mémoire, une première partie ($NS_2 \dots 0$) de l'adresse de sortie sélectionnant un segment parmi un ensemble de segments de la distance sur laquelle le système d'asservissement doit déplacer le corps, chacun des segments ayant une taille égale à la moitié de celle du segment précédent, et une seconde partie ($R_{11} \dots 7$) de l'adresse de sortie sélectionnant un nombre prédéterminé de valeurs pour la vitesse désirée du corps dans un segment respectif, le nombre prédéterminé étant le même pour chacun des segments.

2. Dispositif selon la revendication 1, dans lequel le corps est un bras d'actionneur d'unité de disques magnétiques, qui porte au moins un transducteur de position, et le signal d'erreur de position est généré dans ce transducteur au moment où le transducteur traverse des pistes concentriques différentes sur l'un des disques dans l'unité de disques.

3. Dispositif selon la revendication 2, dans lequel la mémoire est une mémoire morte programmable.

4. Dispositif selon l'une quelconque des revendications précédentes, dans lequel les valeurs de vitesse désirées sont sous forme numérique.

5. Dispositif selon la revendication 4, comprenant en outre des moyens convertisseurs destinés à convertir les valeurs numériques désirées de la forme numérique à la forme analogique.



60

65

5

