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Title of the Invention
Disk Storage Apparatus and
Disk Storage Apparatus Control Method

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BACKGROUND OF THE INVENTION

1. Field of the Invention

The present invention relates to a disk storage apparatus for positioning a head to a target track of a disk which serves as a record medium, and to a technique of inhibiting a track dislocation of the head due to a disturbance to which the apparatus is subject.

2. Description of the Related Art

A positioning control system reads servo information previously recorded on a disk using a head, and minimizes a position error signal for a target track. In this case, to improve positioning accuracy, there is known a method of setting control frequency at high level and thereby accelerating track following operation. However, if control frequency is set high, the positioning control system becomes unstable due to the inherent mechanical resonance of the actuator of the head. This results in a limit to the increase of control frequency. Considering this disadvantage, there is proposed reducing a disturbance (such as pivot bearing friction, an elastic force, and an inertia force due to shock/vibration) which acts on the actuator. That is, based on a head position signal obtained from servo information and a drive signal for the actuator, the disturbance is estimated and compensated by feed-forward control. By doing so, head positioning accuracy is improved.

However, the head position signal based on the servo information discretely recorded on the disk is not a continuous signal. A control band in which disturbance estimation means can estimate a disturbance is affected by the sampling frequency of a sector servo, and has an upper limit. It is difficult to



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correctly estimate the disturbance and to compensate the disturbance so that the disturbance has no effect on the actual use of the control system. Furthermore, if the resistance of the drive coil of the actuator fluctuates or the resistance is changed following temperature rise after a drive current is carried to the drive coil to heat the drive coil, the positioning control system including the disturbance estimation means becomes disadvantageously unstable.

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SUMMARY OF THE INVENTION

To solve the above-stated disadvantages, the present invention takes the following measures. To negate a disturbance caused by a pivot bearing friction, an elastic force, an inertia force due to shock/vibration or the like exerted on actuator means, the magnitude of the disturbance is estimated. In estimating the magnitude of the disturbance, two elements are used. First, a voltage signal which is obtained as a detection result of detecting a voltage induced in driving the actuator means, is used. Second, a drive signal of the drive means for driving the actuator means is used. The drive signal of the drive means may be inputted into the drive means or outputted from the drive means. Alternatively, not the drive signal of the drive means but a position control signal, based on which the drive signal is produced, may be used. That is, disturbance estimation means for estimating the magnitude of the disturbance is provided. The disturbance estimation means receives a voltage signal, which is obtained by detecting the voltage induced in driving the actuator means by voltage detection means, and the drive signal or position control signal

of the drive means, and produces a disturbance estimation signal. The disturbance estimation signal produced based on the two elements, correctly estimates the magnitude of the disturbance exerted on the head. As a result, it is possible to correctly
5 estimate the magnitude of the disturbance exerted on the actuator means. The disturbance related to the estimation is indicated by the disturbance estimation signal. The disturbance estimation means produces the disturbance estimation signal based on either the drive signal or the
10 position control signal and the voltage signal induced in driving the actuator means. The voltage induced in driving the actuator means is a continuous signal. Due to this, compared with conventional art for estimating a disturbance using a discontinuous head position signal as a result of reading servo
15 information discretely recorded on the disk, it is possible to correctly estimate a disturbance.

Meanwhile, if there are fluctuations in the resistance value of the drive coil and changes of the resistance value, a phase with a gain crossover frequency with which open loop
20 gain becomes zero, has no phase margin, with the result that a control system becomes unstable. To solve this disadvantage, according to the present invention, the drive signal is produced based on the position control signal for a head position and the disturbance estimation signal, the high frequency component
25 of the disturbance estimation signal is cut off by filter means to thereby produce a filter signal. Thereafter, the position control signal for the head position is combined with the filter

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signal, thereby producing the drive signal.

By so constituting, the high frequency components of frequencies higher than a filter low-pass cut-off frequency are cut off by the filter means. The high frequency components of
5 the disturbance estimation signal outputted from the disturbance estimation signal are not included equivalently in the drive signal. As a result, even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible
10 to secure a phase margin with the gain crossover frequency and to constitute a stable head positioning control system.

Correction means combines the disturbance estimation signal after filtering (filter signal) with the position control signal from the position control means, and thereby
15 produces a drive signal so as to negate the disturbance exerted on the actuator means using the disturbance estimation signal thus correctly estimated. By driving the actuator means of the head using the drive signal, it is possible to stably negate a disturbance such as a pivot bearing friction, an elastic force
20 or an inertia force exerted on the actuator means. That is, it is possible to compensate the disturbance acting on the actuator means. Therefore, even if the fluctuation of the disturbance acting on the actuator means is large during following operation toward the target track, it is possible to
25 stably control positioning the head to the target track. Furthermore, even if the resistance value of the drive coil of the actuator means is changed by resistance fluctuation or

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temperature rise, it is possible to stably control positioning the head to the target track. That is, it is possible to improve positioning accuracy against more diverse conditional change. In addition, as an effect resulting from this improvement, it is possible to substantially increase track density and to accelerate the embodiment of a large capacity disk storage apparatus.

As another means for solving the disadvantages, the present invention takes the following measures. The disturbance estimation means produces the disturbance estimation signal based on a signal obtained by multiplying the drive signal by k_1 , where k_1 is a coefficient of a real number greater than 1, and the voltage signal. The correction means combines a signal obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with the position control signal, and produces a drive signal. By doing so, the change of open loop gain from the position error signal to the head position can be suppressed to be small. As a result, even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible to stabilize the position control system. In this case, if the filter means is employed, it is possible to attain a more preferable effect.

The present invention explained above will be described more concretely.

As the first solving means, the disk storage apparatus

according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator means in accordance with an input drive signal; voltage detection means for detecting a voltage induced in driving the actuator means, and for outputting a voltage signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from the drive signal and the voltage signal, and for producing a disturbance estimation signal; filter means for cutting off a high frequency component of the disturbance estimation signal, and for outputting a filter signal; position detection means for producing a position error signal corresponding to a current position of the head from servo information previously recorded on the disk and detected by the head, and for outputting the position error signal; position control means for producing a position control signal corresponding to the position error signal, and for outputting the position control signal; and correction means for combining the position control signal with the filter signal to produce the drive signal, and for outputting the drive signal.

With this constitution, the drive signal of the drive means may be a signal inputted into the drive means or a signal outputted from the drive signal. This applies hereafter.

The functions resulting from this first solving means are as follows. The disturbance estimation means can correctly estimate the magnitude of the disturbance exerted on the actuator means based on the drive signal applied to the drive means to drive the actuator means, and the voltage signal

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detected from the actuator means. A disturbance related to the estimation is a disturbance estimation signal. Here, it is particularly important that it is possible to correctly estimate the magnitude of the disturbance exerted on the actuator means from the drive signal and the voltage signal during following operation for allowing the head to follow up the target track. The reason is as follows. The voltage signal detected from the actuator means is a voltage induced in driving the actuator means. This signal, unlike servo information recorded on the disk discretely, is a continuous signal.

After the high frequency component of the disturbance estimation signal is cut off through the filter means so as to negate the disturbance exerted on the actuator means using the disturbance estimation signal thus correctly estimated, the resultant signal is combined with the position control signal outputted from the position control means to thereby produce the drive signal. By driving the actuator means using the drive signal, it is possible to stably negate the disturbance exerted on the actuator means. That is, since it is possible to compensate the disturbance exerted on the actuator means, the position control of the head toward the target track can be stable even if the fluctuation of the disturbance during the following operation for allowing the head to follow up the target track is large. In particular, even if the resistance value of the drive coil of the actuator means is changed by resistance fluctuation or temperature rise, in particular, it is possible to stably control positioning the head to the target

track. That is, it is possible to improve positioning accuracy against more diverse conditional change.

The first solving means will be described as a disk storage apparatus control method as follows. That is, the method
5 comprises the steps of: producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by the head; producing a position control signal corresponding to the position error signal; estimating a magnitude of a disturbance
10 exerted on the head from a drive signal of actuator means for positioning the head and from a voltage signal induced in driving the actuator means, and producing a disturbance estimation signal; cutting off a high frequency component of the disturbance estimation signal, and producing a filter
15 signal; combining the position control signal with the filter signal, and producing the drive signal; and positioning the head with respect to the disk by the drive signal. This disk storage apparatus control method can exhibit the same functions as stated above.

20 As the second solving means, the disk storage apparatus according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator in accordance with an input drive signal; voltage detection means for detecting a voltage induced in
25 driving the actuator means, and for outputting a voltage signal; position detection means for producing a position error signal corresponding to a current position of the head from servo

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information previously recorded on the disk and detected by the head, and for outputting the position error signal; position control means for producing a position control signal corresponding to the position error signal, and for outputting the position control signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from the voltage signal and the position control signal, and for producing a disturbance estimation signal; filter means for cutting off a high frequency component of the disturbance estimation signal, and for outputting a filter signal; and correction means for combining the position control signal with the filter signal to produce the drive signal, and for outputting the drive signal.

The functions resulting from this second solving means are as follows. The disturbance estimation means can correctly estimate the magnitude of the disturbance exerted on the actuator means based on the drive signal applied to the drive means to drive the actuator means, and the voltage signal detected from the actuator means. Here, it is particularly important that it is possible to correctly estimate the magnitude of the disturbance exerted on the actuator means from the drive signal and the voltage signal during following operation for allowing the head to follow up the target track. The reason is as follows. The voltage signal detected from the actuator means is, unlike servo information recorded on the disk discretely, a continuous signal.

After the high frequency component of the disturbance

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estimation signal is cut off through the filter means so as to negate the disturbance exerted on the actuator means using the disturbance estimation signal thus correctly estimated, the resultant signal is combined with the position control signal
5 outputted from the position control means to thereby produce the drive signal. By driving the actuator means using the drive signal, it is possible to stably negate the disturbance exerted on the actuator means. That is, it is possible to compensate the disturbance exerted on the actuator means. Therefore, even
10 if the fluctuation of the disturbance during the following operation for allowing the head to follow up the target track is large and even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible to stably
15 control positioning the head to the target track. That is, it is possible to improve positioning accuracy against more diverse conditional change.

The second solving means will be described as a disk storage apparatus control method as follows. That is, the
20 method comprises the steps of: producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by the head; producing a position control signal corresponding to the position error signal; estimating a magnitude of a disturbance
25 exerted on the head from the position control signal and a voltage signal induced in driving actuator means for positioning the head, and producing a disturbance estimation

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signal; cutting off a high frequency component of the disturbance estimation signal, and producing a filter signal; combining the position control signal with the filter signal, and producing the drive signal; and positioning the head with respect to the disk by the drive signal. This disk storage apparatus control method can exhibit the same functions as stated above.

As the third solving means, the disk storage apparatus according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator means in accordance with an input drive signal; voltage detection means for detecting a voltage induced in driving the actuator means, and for outputting a voltage signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying the drive signal by k_1 , where k_1 is a coefficient of a real number greater than 1, and from the voltage signal, and for producing a disturbance estimation signal; position detection means for producing a position error signal corresponding to a current position of the head from servo information previously recorded on the disk and detected by the head, and for outputting the position error signal; position control means for producing a position control signal corresponding to the position error signal, and for outputting the position control signal; and correction means for receiving the position control signal and the disturbance estimation signal, combining a signal obtained by multiplying the

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disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with the position control signal to produce the drive signal, and for outputting the drive signal.

5 The functions resulting from this third solving means are as follows. Besides the same functions as those resulting from the first solving means, it is possible to suppress the change of open loop gain from the position error signal to the head position to be small since the drive signal is applied to the
10 disturbance estimation means after being multiplied by k_1 ($k_1 \gg 1$) and the disturbance estimation signal is applied to the correction means after being multiplied by $1/k_2$ ($k_2 \gg 1$). As a result, even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation
15 or temperature rise, it is possible to stabilize the position control system. That is, it is possible to improve positioning accuracy against more diverse conditional change. In this case, if the filter means provided by the first solving means is used, it is possible to obtain a more preferable effect.

20 The third solving means will be described as a disk storage apparatus control method as follows. That is, the method comprises the steps of: producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by the
25 head; producing a position control signal corresponding to the position error signal; estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying a drive

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signal of actuator means for positioning the head by k_1 , where k_1 is a coefficient of a real number greater than 1, and from a voltage signal induced in driving the actuator means, and producing a disturbance estimation signal; combining a signal
5 obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with the position control signal, and producing the drive signal; and positioning the head with respect to the disk by the drive signal. This disk storage apparatus control method
10 can exhibit the same functions as stated above.

As the fourth solving means, the disk storage apparatus according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator means in accordance with an input drive
15 signal; voltage detection means for detecting a voltage induced in driving the actuator means, and for outputting a voltage signal; position detection means for producing a position error signal corresponding to a current position of the head from servo information previously recorded on the disk and detected
20 by the head, and for outputting the position error signal; position control means for producing a position control signal corresponding to the position error signal, and for outputting the position control signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from
25 a signal obtained by multiplying the position control signal by k_1 , where k_1 is a coefficient of a real number greater than 1, and from the voltage signal, and for producing a disturbance

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estimation signal; and correction means for receiving the position control signal and the disturbance estimation signal, combining a signal obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real
5 number greater than 1, with the position control signal to produce the drive signal, and for outputting the drive signal.

With this constitution, the disturbance estimation means can correctly estimate the magnitude of the disturbance exerted on the actuator means based on the position control signal
10 outputted from the position control means so as to be applied to the drive means for driving the actuator means and the voltage signal detected from the actuator means. It is possible to correctly estimate the magnitude of the disturbance exerted on the actuator means from the position control signal and the
15 voltage signal particularly during following operation for allowing the head to follow up the target track. The disturbance estimation signal is combined with the position control signal outputted from the position control means so as to negate the disturbance exerted on the actuator means using
20 the disturbance estimation signal thus correctly estimated, to thereby produce the drive signal. By driving the actuator means of the head using the drive signal, it is possible to stably negate the disturbance exerted on the actuator means. That is, it is possible to compensate the disturbance exerted on the
25 actuator means. Therefore, even if the fluctuation of the disturbance is large during the following operation for allowing the head to follow up the target track and even if the

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resistance value of the drive coil of the actuator means is
changed according to resistance fluctuation or temperature rise,
it is possible to stably control positioning the head to the
target track. That is, it is possible to improve positioning
5 accuracy against more diverse conditional change.

The fourth solving means will be described as a disk
storage apparatus control method as follows. That is, the
method comprises the steps of: producing a position error signal
corresponding to a current position of a head from servo
10 information previously recorded on a disk and detected by the
head; producing a position control signal corresponding to the
position error signal; estimating a magnitude of a disturbance
exerted on the head from a signal obtained by multiplying the
position control signal by k_1 , where k_1 is a coefficient of a
15 real number greater than 1, and from a voltage signal induced
in driving actuator means for positioning the head, and
producing a disturbance estimation signal; combining a signal
obtained by multiplying the disturbance estimation signal by
 $1/k_2$, where k_2 is a coefficient of a real number greater than
20 1, with the position control signal, and producing the drive
signal; and positioning the head with respect to the disk by
the drive signal. This disk storage apparatus control method
can exhibit the same functions as stated above.

Alternatively, the first solving means may be combined
25 with the third solving means. The second solving means may be
combined with the fourth solving means. These combination
means are fifth and sixth solving means, respectively.

As the fifth solving means, the disk storage apparatus according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator means in accordance with an input drive
5 signal; voltage detection means for detecting a voltage induced in driving the actuator means, and for outputting a voltage signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying the drive signal by k_1 , where k_1 is a coefficient
10 of a real number greater than 1, and from the voltage signal, and for producing a disturbance estimation signal; position detection means for producing a position error signal corresponding to a current position of the head from servo information previously recorded on the disk and detected by the
15 head, and for outputting the position error signal; position control means for producing a position control signal corresponding to the position error signal, and for outputting the position control signal; and correction means for receiving the position control signal and the disturbance estimation
20 signal, cutting off a high frequency component of a signal, which is obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, to produce a filter signal, combining the position control signal with the filter signal to produce the drive
25 signal, and for outputting the drive signal.

The fifth solving means will be described as a disk storage apparatus control method as follows. That is, the method

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comprises the steps of: producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by the head; producing a position control signal corresponding to the position error signal; estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying a drive signal of actuator means for positioning the head by k_1 , where k_1 is a coefficient of a real number greater than 1, and from a voltage signal induced in driving the actuator means, and producing a disturbance estimation signal; cutting off a high frequency component of a signal, which is obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, and producing a filter signal; combining the position control signal with the filter signal, and producing the drive signal; and positioning the head with respect to the disk by the drive signal.

Further, as the sixth solving means, the disk storage apparatus according to the present invention comprises: actuator means for positioning a head with respect to a disk; drive means for driving the actuator means in accordance with an input drive signal; voltage detection means for detecting a voltage induced in driving the actuator means, and for outputting a voltage signal; position detection means for producing a position error signal corresponding to a current position of the head from servo information previously recorded on the disk and detected by the head, and for outputting the position error signal; position control means for producing a

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position control signal corresponding to the position error signal, and for outputting the position control signal; disturbance estimation means for estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying the position control signal by k_1 , where k_1 is a coefficient of a real number greater than 1, and from the voltage signal, and for producing a disturbance estimation signal; and correction means for receiving the position control signal and the disturbance estimation signal, cutting off a high frequency component of a signal, which is obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, to produce a filter signal, combining the position control signal with the filter signal to produce the drive signal, and for outputting the drive signal.

The sixth solving means will be described as a disk storage apparatus control method as follows. That is, the method comprises the steps of: producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by the head; producing a position control signal corresponding to the position error signal; estimating a magnitude of a disturbance exerted on the head from a signal obtained by multiplying the position control signal by k_1 , where k_1 is a coefficient of a real number greater than 1, and from a voltage signal induced in driving actuator means for positioning the head, and producing a disturbance estimation signal; cutting off a high

frequency component of a signal, which is obtained by multiplying the disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, and producing a filter signal; combining the position control signal with the
5 filter signal, and producing the drive signal; and positioning the head with respect to the disk by the drive signal.

The fifth and sixth solving means have synergistic effects. That is, even if the change width of the resistance value of the drive coil is quite large, it is possible to
10 implement stable head positioning control over higher control frequency bands.

According to the third to sixth solving means, it is preferable that the coefficients k_1 and k_2 are set almost equal to each other.

15 By doing so, in the substantial transfer function from the position control signal to the drive current to the actuator means, components related to the resistance value of the drive coil of the actuator means can be ignored. Accordingly, even if the resistance value of the drive coil of the actuator means
20 is changed by resistance fluctuation or temperature rise, it is possible to sufficiently, stably control positioning the head to the target track.

According to the first, third or fifth solving means in which the drive signal out of the drive signal and the position
25 control signal is applied to the disturbance estimation means, it is preferable to constitute the apparatus as follows. The disturbance estimation means comprises: comparison means for

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receiving the voltage signal detected by the voltage detection means; first multiplication means for multiplying the drive signal or a signal obtained by multiplying the drive signal by k_1 , by a coefficient consisting of a first transfer function; 5 second multiplication means for multiplying an output of the comparison means by a coefficient consisting of a second transfer function; first integration means for integrating the output of the comparison means; and second integration means for integrating a value obtained by subtracting the added value 10 of the output of the second multiplication means and the output of the first integration means from the output of the first multiplication means, and the comparison means is configured to compare the voltage signal with the output of the second integration means, and to output a comparison result to the 15 second multiplication means and the first integration means.

The functions resulting from this constitution are as follows. The output of the first multiplication means which inputs the drive signal or a signal obtained by multiplying the drive signal by k_1 , becomes a drive torque estimation signal 20 corresponding to the drive torque acting on the actuation means. The output of the second integration means becomes a feedback element for the voltage signal inputted from the voltage detection means. The output of the comparison means which obtains the difference between the voltage signal and the 25 feedback element from the second integration means, is applied to the first integration means and the second multiplication means. The output of the first integration means which

integrates the difference, becomes a disturbance estimation signal corresponding to the disturbance exerted on the actuator means. The output of the second multiplication means obtained by multiplying the difference by a predetermined coefficient, 5 is added to the disturbance estimation signal. The added value is subtracted from the drive torque estimation signal and the result is applied to the second integration means.

As a result, the disturbance estimation signal outputted from the first integration means corresponds to the correct 10 estimate of the disturbance exerted on the actuator means. Further, using the disturbance estimation signal thus correctly estimated, feed-forward control is implemented so as to negate the disturbance exerted on the actuator means. It is, therefore, possible to compensate the disturbance acting on the actuator 15 means during following operation. Even if the fluctuation of the disturbance in the actuator means is large during the following operation, and even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible to 20 stably control positioning the head to the target track, and to improve positioning accuracy against more diverse conditional changes.

According to the second, fourth or sixth solving means in which the position control signal out of the drive signal 25 and the position control signal is applied to the disturbance estimation means, it is preferable to constitute the apparatus as follows. The disturbance estimation means comprises:

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comparison means for receiving the voltage signal detected by the voltage detection means; first multiplication means for multiplying the position control signal or the signal, which is obtained by multiplying the position control signal by k_1 ,
5 by a coefficient consisting of a first transfer function; second multiplication means for multiplying an output of the comparison means by a coefficient consisting of a second transfer function; first integration means for integrating the output of the comparison means; and second integration means
10 for integrating a value obtained by subtracting the output of the second multiplication means from the output of the first multiplication means, and the comparison means compares the voltage signal with the output of the second integration means, and outputs a comparison result to the second multiplication
15 means and the first integration means.

The functions resulting from this constitution are as follows. The output of the first multiplication means which inputs the position control signal from the position control means signal or a signal obtained by multiplying the position
20 control signal by k_1 , becomes a drive torque estimation signal corresponding to the drive torque acting on the actuation means. The output of the second integration means becomes a feedback element for the voltage signal inputted from the voltage detection means. The output of the comparison means which
25 obtains the difference between the voltage signal and the feedback element from the second integration means, is applied to the first integration means and the second multiplication

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means. The output of the first integration means which integrates the difference, becomes a disturbance estimation signal corresponding to the disturbance exerted on the actuator means. The output of the second multiplication means obtained
5 by multiplying the difference by a predetermined coefficient, is subtracted from the drive torque estimation signal and the result is applied to the second integration means.

As a result, the disturbance estimation signal outputted from the first integration means corresponds to the correct
10 estimate of the disturbance exerted on the actuator means. Further, using the disturbance estimation signal thus correctly estimated, feed-forward control is implemented so as to negate the disturbance exerted on the actuator means. It is, therefore, possible to compensate the disturbance acting on the actuator
15 means during following operation. Even if the fluctuation of the disturbance in the actuator means is large during the following operation, and even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible to
20 stably control positioning the head to the target track, and to improve positioning accuracy. Besides, the addition of the first integration means and the second multiplication means which the first solving means requires, is unnecessary. It is, therefore, possible to omit addition means and to thereby
25 simplify the constitution.

Further, according to the above-stated invention, it is preferable that an estimation frequency of the disturbance

estimation signal produced by the disturbance estimation means is set at a value larger than a control frequency band of the position control means.

The functions resulting from the above are as follows.

- 5 To widen the control frequency band of the positioning control system means to increase proportional gain. However, the gain has an upper limit by the sampling frequency of the sector servo of the disk storage apparatus or the inherent mechanical resonance frequency of the actuator means. In contrast, the
10 disturbance estimation means is not affected by the sampling frequency of the sector servo of the disk storage apparatus. Accordingly, in the disturbance estimation means, it is possible to set the estimation frequency band of the disturbance estimation signal produced by the disturbance estimation means,
15 higher than the control frequency band of the positioning control system. As a result, it is possible to make the head correctly follow up the target track over higher control frequency bands.

- Further, according to the above-stated invention, it is
20 preferable that a cut-off frequency of the filter means is set at a value smaller than a control band of the position control means.

- The functions resulting from this are as follows. Normally, there is a fluctuation in the resistance value of the
25 drive coil of the actuator means. In addition, by conducting a drive current to the drive coil, the drive coil is heated to raise temperature and the temperature rise changes the

resistance value. Consequently, the change of the resistance value of the drive coil of the actuator means makes the positioning control system including the disturbance estimation means unstable, with the result that the system oscillates with frequency near the control band of the position control means. To solve this disadvantage, the drive signal is produced based on the position control signal for the head position and the disturbance estimation signal. The high frequency component of the disturbance estimation signal is cut off by the filter means to thereby produce a filter signal. The position control signal for the head position is combined with the filter signal to thereby produce the drive signal. In this case, if the cut-off frequency of the filter signal by the filter means or correction means is set lower than the control band of the position control means, then the disturbance estimation signal having higher frequency components than the cut-off frequency is cut off by the filter means and not fed back to the positioning control system. Therefore, even if the resistance value of the drive coil of the actuator means is changed according to resistance fluctuation or temperature rise, it is possible to stabilize the position control system.

Furthermore, according to the above-stated invention, it is preferable that the actuator means is configured by a permanent magnet fixedly attached to at least one yoke of a pair of yokes in a cavity of the pair of yokes opposite to each other through the cavity, and a drive coil provided in a magnetic cavity formed by the permanent magnet and the yokes, and that

a circuit having a capacitor and a resistor connected in series, is connected to the drive coil in parallel.

The functions resulting from this are as follows. Normally, the drive coil which constitutes the actuator means
5 contains not only a resistance component but also an inductance component. Since the inductance component is smaller than the coil resistance, it is difficult to accurately constitute a circuit therefor. Further, since the inductance component is a derivative element, it tends to be affected by noise. As a
10 result, if the control band of the disturbance estimation means is set high, the control system becomes unstable due to the influence of this inductance. This results in a limit in increasing the control band of the disturbance estimation means. Considering this disadvantage, the circuit having the capacitor
15 and the resistor connected in series is connected to the drive coil in parallel, whereby the influence of the inductance of the drive coil can be eliminated and the control band thereof can be set higher than the control band of the positioning control system. As a result, it is possible to make the head
20 correctly follow up the target track over higher control bands. In addition, in the constitution of a circuit, it is unnecessary to take account of the inductance component which requires high accuracy, so that the voltage detection means can be simplified.

Moreover, according to the above-stated invention, it is
25 preferable that the capacitor and the resistor connected to the drive coil in parallel are set to have a capacitance value C and a resistance value r as expressed by $C=L_a/R_a^2$, and $r=R_a$,

or approximate to $C=L_a/R_a^2$, and $r=R_a$, respectively, wherein R_a is a resistance value of the drive coil.

By so setting, the composite impedance of the impedance of the drive coil and that of the parallel circuit becomes
5 substantially equal to the resistance of the drive coil, making it possible to equivalently negate the inductance component of the drive coil. Accordingly, even if there is a fluctuation in the inductance component which tends to be affected by the noise because it is a derivative element, it is possible to
10 stably implement positioning control without being influenced by the noise.

As is obvious from the above explanation, the position control means, the disturbance estimation means, the correction means, and the filter means, which are the constituent elements
15 of the disk storage apparatus, may be configured by hardware or software.

Additionally, as is evident from the above explanation, the comparison means, the respective multiplication means, and the respective integration means, which are the constituent
20 elements of the disk storage apparatus, may be by hardware or software.

While the present invention functions most advantageously if being applied to a magnetic disk storage apparatus, the present invention is not limited to the magnetic
25 disk storage apparatus but can be applied to the other information recording apparatuses such as an optical disk storage apparatus and a magneto-optical storage apparatus.

According to the invention in the first aspect there is a provided a disk storage apparatus as claimed in claim 1.

According to the invention in the second aspect there is a provided a disk storage apparatus as claimed in claim 6.

5 According to the invention in the third aspect there is a provided a disk storage apparatus as claimed in claim 11.

According to the invention in the fourth aspect there is a provided a disk storage apparatus as claimed in claim 15.

10 According to the invention in the fifth aspect there is a provided a disk storage apparatus as claimed in claim 19.

According to the invention in the sixth aspect there is a provided a disk storage apparatus as claimed in claim 24.

According to the invention in the seventh aspect there is a provided a disk storage apparatus control method as claimed in claim 29.

15 According to the invention in the eighth aspect there is a provided a disk storage apparatus control method as claimed in claim 31.

According to the invention in the ninth aspect there is a provided a disk storage apparatus control method as claimed in claim 33.

20 According to the invention in the tenth aspect there is a provided a disk storage apparatus control method as claimed in claim 36.

According to the invention in the eleventh aspect there is a provided a disk storage apparatus control method as claimed in claim 39.

According to the invention in the twelfth aspect there is a provided a disk storage apparatus control method as claimed in claim 42.

The foregoing and other aspects will become apparatus from the following description of the invention when considered in conjunction with the accompanying drawing figures.

5 BRIEF DESCRIPTION OF THE DRAWINGS

Fig 1 is a block diagram showing the configuration of a disk storage apparatus in the first embodiment according to the present invention;

10 Fig. 2 is a block diagram showing the whole configuration of the positioning control system of the disk storage apparatus in the first embodiment according to the present invention;

Fig. 3A is a block diagram for explaining the disturbance estimation operation of the disturbance estimation means of the disk storage apparatus in the first embodiment according to the present invention, Fig. 3B is a block diagram obtained by
15 equivalently transforming the block diagram of Fig. 3A, and Fig. 3C is a block diagram collectively expressing the block diagram of Fig. 3A;

Fig. 4A is a block diagram for explaining an operation
20 of inhibiting a disturbance exerted on the disk storage apparatus in the first embodiment according to the present invention, and Fig. 4B is a block diagram obtained by equivalently transforming the block diagram of Fig. 4A;

Fig. 5 is a cut-off frequency characteristic graph for
25 the disturbance exerted on the disk storage apparatus in the first embodiment according to the present invention;

Fig. 6A is a waveform chart of the fluctuation of the

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disturbance exerted on the disk storage apparatus and a disturbance estimation signal outputted from the disturbance estimation means with respect to time response in the first embodiment according to the present invention, Fig. 6B is a waveform chart of a drive current with respect to time response in a case where the disturbance estimation signal outputted from the disturbance estimation means is inputted into correction means and in a case where the distance estimation signal is not inputted into the correction means, and Fig. 6C is a waveform chart of a track error with respect to time response in a case where the disturbance estimation signal outputted from the disturbance estimation means is inputted into the correction means to negate the fluctuation of the disturbance;

Fig. 7A is a frequency gain characteristic view of the open loop of a positioning control system in a case where the disturbance estimation means of the disk storage apparatus in the first embodiment according to the present invention takes account of the inductance of a drive coil, and Fig. 7B is a frequency to phase characteristic view corresponding to Fig. 7A;

Fig. 8A is a frequency gain characteristic view of the open loop of a positioning control system in a case where the disturbance estimation means of the disk storage apparatus in the first embodiment according to the present invention does not take account of the inductance of the drive coil, and Fig. 8B is a frequency to phase characteristic view corresponding to Fig. 8A;

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Fig. 9 is a circuit configuration view of a capacitor and a resistance connected in parallel to the drive coil of the disk storage apparatus in the first embodiment according to the present invention;

5 Fig. 10 is a block diagram showing the changed parts of the disturbance estimation means of the disk storage apparatus in the first embodiment according to the present invention;

Fig. 11A is a frequency gain characteristic view of the open loop of the positioning control system of the disk storage apparatus in the first embodiment according to the present invention in a case where a filter is not inserted between the output of the disturbance estimation means and the input of the correction means (indicated by a solid line) and in a case where the disturbance estimation means does not take account of the inductance of the drive coil (indicated by a broken line), and Fig. 11B is a frequency phase characteristic view corresponding to Fig. 11A;

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Fig. 12 is a block diagram showing the configuration of a disk storage apparatus in the second embodiment according to the present invention;

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Fig. 13 is a block diagram showing the whole configuration of the positioning control system of the disk storage apparatus in the second embodiment according to the present invention;

Fig. 14 is a block diagram showing the configuration of a disk storage apparatus in the third embodiment according to the present invention;

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Fig. 15 is a block diagram showing the whole configuration

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of the positioning control system of the disk storage apparatus in the third embodiment according to the present invention;

Fig. 16A is a frequency gain characteristic view of the open loop of the positioning control system in a case where the resistance value of the drive coil is not equal to a nominal value in the disturbance estimation means in the third embodiment according to the present invention, and Fig. 16B is a frequency phase characteristic view corresponding to Fig. 16A;

Fig. 17A is a block diagram showing the whole configuration of the positioning control system of the disk storage apparatus in the third embodiment according to the present invention, Fig. 17B is a block diagram obtained by equivalently transforming the block diagram of Fig. 17A, and Fig. 17C is a block diagram showing the changed parts of the positioning control system in a case where the resistance value of the drive coil is not equal to the nominal value;

Fig. 18 is a re-drawn block diagram of the configuration of the disk storage apparatus (Fig. 14) in the third embodiment according to the present invention;

Fig. 19 is a re-drawn block diagram of the whole configuration of the positioning control system (Fig. 15) of the disk storage apparatus in the third embodiment according to the present invention;

Fig. 20 is a block diagram showing the configuration of a disk storage apparatus in the fourth embodiment according to the present invention;

Fig. 21 is a block diagram showing the whole configuration of the positioning control system of the disk storage apparatus in the fourth embodiment according to the present invention;

Fig. 22 is a re-drawn block diagram of the configuration of the disk storage apparatus (Fig. 14) in the third embodiment according to the present invention;

Fig. 23 is a re-drawn block diagram of the whole configuration of the positioning control system (Fig. 15) of the disk storage apparatus in the third embodiment according to the present invention;

Fig. 24 is a block diagram showing the configuration of a disk storage apparatus in an embodiment which is a combination of the first and third embodiments according to the present invention; and

Fig. 25 is a block diagram showing the configuration of a disk storage apparatus in an embodiment which is a combination of the second and fourth embodiments according to the present invention.

In all these figures, like components are indicated by the same numerals.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

With reference to the drawings, concrete embodiments of a disk storage apparatus and a disk storage apparatus control method according to the present invention will be explained hereinafter in detail. It is noted that components having the same functions are denoted by the same reference numerals, respectively.

First Embodiment

Fig. 1 is a block diagram showing the configuration of an example of a disk storage apparatus of the present invention in the first embodiment.

5 In Fig. 1, the numeral 1 indicates a magnetic disk rotated by a spindle motor (not shown); the numeral 2, a magnetic head for recording/reproducing data for the disk 1; and the numeral 3, an arm which moves the head 2 to a target track on the disk 1 by pivoting the head 2 mounted on the one end of the arm 3 around a bearing 4. The numeral 5 indicates a drive coil provided on the rear end of the arm 3; and the numeral 6, a stator (yoke) in which a magnet (a permanent magnet, not shown) is arranged on the surface opposite to the drive coil 5. The stator 6 consists, through a gap, of a pair of opposite yokes, and within 10 the gap, the above-mentioned magnet is fixed to at least one of the yokes. The interaction between the magnetic flux generated by the magnet arranged on the stator 6 and the magnetic field produced by the current conducted through the drive coil 5 causes the arm 3 to be subject to a rotational force. An actuator 7 is configured by the arm 3, the bearing 4, the drive coil 5 and the stator 6. 20

 The numeral 10 indicates drive means; and the numeral 11, voltage detection means, which is included in the drive means 10, detects a voltage generated across the drive coil 5, and 25 outputs a voltage signal E_d . The numeral 12 indicates disturbance estimation means which estimates a disturbance torque τ_d exerted on the arm 3 from the voltage signal E_d outputted by the voltage detection means 11 and from a drive signal u as an input of the drive means 10, and outputs a disturbance estimation signal τ_{dest} . A position signal of the track, which 30 has been previously recorded as servo information on respective sectors of the disk 1, is read by the head 2. Position detection means 13 detects a current position of the head 2 from the

position signal read by the head 2, and produces a position error signal e indicating a difference from a target position r of the target track. Position control means 14 receives the position error signal e produced by the position detection means 13, amplifies and phase compensates the signal, and produces a position control signal c .

The numeral 16 indicates filter means which cuts off high frequency components of the disturbance estimation signal τ_{dest} applied from the disturbance estimation means 12 to correction means 15 and which does not output the high frequency components to the correction means 15 so as to stabilize a positioning control system. The filter means 16 outputs a filter signal f obtained by cutting off the high frequency components from the disturbance estimation signal τ_{dest} , to the correction means 15.

The numeral 15 indicates the correction means which receives the position control signal c from the position control means 14 and the filter signal f from the filter means 16. The correction means 15 performs a correction computation, and then outputs the drive signal u to the drive means 10.

The drive means 10 is configured such that it conducts a drive current I_a to the drive coil 5 in response to the inputted drive signal u , pivots the arm 3 about the bearing 4 as a center, rotationally moves the head 2 mounted on the top end of the arm 3, and positions, with high accuracy, the head 2 to the target track formed at narrow track pitches in order to record/reproduce data on the disk 1.

Using Fig. 2, the operation of the positioning control system of the disk storage apparatus in the first embodiment will be explained hereinafter. Fig. 2 is a block diagram showing the whole configuration of the positioning control system of the disk storage apparatus in the first embodiment.

A portion 30 surrounded with a single-dot chain line in

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the figure is a block of the disturbance estimation means 12. Similarly, a portion 47 surrounded with a single-dot chain line in the figure is a block of correction means 15. A portion 55 surrounded with a single-dot chain line in the figure is a block of the voltage detection means 11. In Fig. 2, the symbol s indicates Laplace operator. In Fig. 2, hold elements by the sampling of the sector servo are omitted to simplify the explanation.

In Fig. 2, expressing the current track position detected by the head 2 as x , the position error signal e with respect to the target track position r is expressed by formula 1, which position error signal e is obtained at a comparator (which is also referred to as "comparison means") 20.

$$e = r - x \quad \dots\dots (1)$$

The position control means 14 expressed by a block 21 in Fig. 2 applies a digital filter processing of a transfer function $G_x(z)$ to the position error signal e outputted from the comparator 20, produces the position control signal c , and outputs it to the correction means 15 expressed by a block 47. The positioning control system is applied with a normal PID control, and the transfer function of the position control means 14 can be expressed by formula 2:

$$G_x(z) = K_x \left\{ 1 + a_d(1 - z^{-1}) + a_i \frac{z^{-1}}{1 - z^{-1}} \right\} \quad \dots\dots (2)$$

Here, the symbol z^{-1} indicates a one-sample delay, and the symbol K_x indicates a proportional gain of the positioning control system. The coefficients a_d , a_i indicate constants for expressing frequency characteristic, in which the coefficient a_d is a derivative coefficient, while the coefficient a_i is an

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integral coefficient. The position control signal c passes through an adder 46, and becomes the drive signal u . The drive signal u is converted from the voltage signal to a g_m -time current signal at the drive means 10 of a block 22 (the transfer function is g_m), where the drive current I_a is outputted. In the actuator 7 expressed by a block 23, the drive current I_a is converted by a transfer function K_t to the drive torque τ by an interaction between the magnetic field produced by the drive current I_a and the above-mentioned magnetic flux of the stator 6. Here, the transfer function K_t is a torque constant of the actuator 7. A transfer function ($L_b/J \cdot s$) of a block 24 expresses a transfer characteristic from the drive torque τ exerted on the arm 3 to a moving velocity v of the head 2. Here, the symbol J indicates an inertia moment of the arm 3, and the symbol L_b indicates a distance from the bearing 4 of the arm 3 to the head 2. A block 25 indicates an integrator (which is also referred to as "integration means"), where the transfer function is expressed by $1/s$, and the moving velocity v of the head 2 is converted to the current track position x .

In the actuator 7, a block 26 outputs an induced voltage E_a generated across the drive coil 5 by the rotation of the actuator 7, while a block 27 outputs a voltage drop $(R_a + L_a \cdot s) \cdot I_a$ generated by the conduction of the drive current I_a into the drive coil 5, and outputs a terminal voltage V_a of the actuator 7 by adding the induced voltage and the voltage drop to each other at an adder 28. That is, the relationship therebetween is as follows:

$$V_a = E_a + (R_a + L_a \cdot s) I_a \quad \dots\dots (3)$$

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Wherein R_a indicates coil resistance of the drive coil 5 and L_a indicates the inductance of the drive coil 5.

A disturbance τ_d exerted on the arm 3 such as a pivot

bearing friction of the actuator 7, an elastic force of an FPC connecting the actuator 7 with an electronic circuit board, and an inertia force received by the actuator 7 due to shock or vibration exerted on the disk storage apparatus from the outside
 5 can be expressed as a form inputted into the front stage of the block 24 at a comparator 29.

The portion 55 surrounded with a single-dot chain line in Fig. 2 shows the detail of the voltage detection means 11, which block 55 includes a block 39 having the same transfer
 10 function as that of the block 27 included in the actuator 7, and a subtracter 36. The block 39 outputs voltage drop $(R_a n + L_a n \cdot s) \cdot I_a$ which is generated by conducting the drive current I_a to the drive coil 5, and outputs the drive signal E_d by subtracting the voltage drop from the terminal voltage
 15 V_a of the actuator 7 using the subtracter 36.

The portion 30 surrounded with a single-dot chain line in Fig. 2 shows the detail of the disturbance estimation means 12, which block 30 includes a block 32 having the same transfer
 20 function as that of the block 22 as the drive means 10, a block 33 having the same transfer function as that of the block 23 as the actuator 7, a block 34 having the same transfer function as that of the block 24, and a block 35 having the same transfer function as that of the block 26. The first multiplier (which is also referred to as "multiplication means") 41 is configured
 25 by the combination of the block 32 and the block 33. The numeral 43 indicates a first integrator and 44 indicates a second multiplier. The second integrator 42 is configured by the combination of the block 34 and the block 35. Here, respective constants with the suffix "n" in the block 30 indicate nominal
 30 values, and variables with the suffix "_{est}" indicate estimates.

The drive signal u inputted into the block 22 is also inputted into the block 32 constituting the disturbance estimation means 12, and a multiplication of $g_{mn} \cdot K_{tn}$ times the

drive signal u in the block 32 and the block 33 causes the same drive torque estimation signal τ_{est} as the drive torque τ exerted on the arm 3 to be obtained.

In Fig. 2, a velocity estimation signal v_{est} is outputted from the block 34. In the block 35, an induced voltage estimation signal E_{aest} obtained by increasing the velocity estimation signal v_{est} by K_{vn} times is inputted into a comparator 37 and is compared with the voltage signal E_d actually detected. A resultant deviation signal α ($=E_{aest}-E_d$) is inputted into the first integrator 43 and the second multiplier 44. The first integrator 43 integrates the deviation signal α by g_2 times, and outputs a disturbance estimation signal τ_{dest} for disturbance. The deviation signal α is inputted into the second multiplier 44, and increased by g_1 times, and then added to an adder 38. The output of the adder 38 is inputted into a subtracter 31, where a resultant value γ obtained by subtracting the output of the adder 38 from the drive torque estimation signal τ_{est} outputted from the block 33 is outputted to the block 34.

A coefficient g_1 of the second multiplier 44 and a coefficient g_2 of the first integrator 43 are constants for stabilizing the operation of the disturbance estimation means 12, the detail of which will be described later.

In Fig. 2, a block 54 is a block diagram of the filter means 16. The filter means 16 expressed by the block 54 subjects the disturbance estimation signal τ_{dest} outputted from the disturbance estimation means 12 to a filter processing of a transfer function $F(s)$, generates a filter signal f , and outputs the filter signal f to the correction means 15 expressed by the block 47. The transfer function of the filter means 16 can be expressed by formula 4:

$$F(s) = \frac{1}{1 + T_x \cdot s} \quad \dots\dots (4)$$

Here, T_x indicates a time constant of a filter and T_x and a filter low-pass cut-off frequency f_x hold the following relationship:

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$$T_x = \frac{1}{2 \pi f_x} \dots\dots (5)$$

In Fig. 1, a state in which the filter signal f is outputted from the filter means 16 to the correction means 15 is shown.

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The filter of the block 54 is to stabilize the operation of the positioning control system of the disk storage apparatus in the first embodiment, the detail of which will be described later.

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In Fig. 2, a block 47 surrounded with a single-dot chain line is a block diagram of the correction means 15. A block 45 included in the correction means 15 produces a correction signal β to the drive means 10 required to make the arm 3 generate a drive force having a magnitude equivalent to the disturbance estimation signal τ_{dest} by increasing the disturbance estimation signal τ_{dest} by $1/(g_{mn} \cdot K_{tn})$ times. The correction signal β is added to the position control signal c at an adder 46.

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With reference to Fig. 3, the operation of the disturbance estimation means 12 of the block 30 will be explained hereinafter.

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Fig. 3A is a block diagram obtained by changing the block 30 of Fig. 2, and shows the transfer from the input of the drive signal u to the output of the disturbance estimation signal τ_{dest} . Fig. 3B is a block diagram obtained in the block diagram of Fig. 3A by transfer moving equivalently the input position (at the comparator 37) of the voltage signal E_d , thereby transforming the block diagram of Fig. 3A. Here, to simplify the explanation, assuming that the value g_m of the block 22 is equal to the value

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g_{mn} of the block 32 in Fig. 2 as shown in the following formula, the drive current $I_a (=g_m \cdot u)$ is considered to be equal to the estimation current $I_{aest} (=g_{mn} \cdot u)$.

5
$$g_m = g_{mn} \quad \dots\dots (6)$$

By increasing the magnitude of the voltage signal E_d by $(J_n \cdot s) / (L_{bn} \cdot K_{vn})$ times, the input position of the comparator 37 of Fig. 3A can be equivalently move to the input position of a subtracter 48 shown in Fig. 3B.

Noting the subtracter 48 of Fig. 3B, the value δ as the output of the subtracter 48 is expressed as shown in formula 7:

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$$\delta = K_{in} \cdot I_a - \frac{J_n \cdot s}{L_{bn} \cdot K_{vn}} E_d \quad \dots\dots (7)$$

Here, to simplify the formula 7, assuming that there exists a relationship as shown in formulas 8 and 9 as ideal conditions:

20
$$R_a = R_{an} \quad \dots\dots (8)$$

$$L_a = L_{an} \quad \dots\dots (9)$$

25 Noting the subtracter 36 and substituting the formula (3), the voltage signal E_d is expressed by the following formula 10:

$$\begin{aligned} E_d &= V_a - (R_{an} + L_{an} \cdot s) I_a \\ &= E_a + (R_a + L_a \cdot s) I_a - (R_{an} + L_{an} \cdot s) I_a \quad \dots\dots (10) \\ &= E_a \end{aligned}$$

30 Then, noting the comparator 29, and the blocks 24 and 26

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of Fig.2, there exists a relationship as shown in the formula 11:

$$E_a = \frac{L_b \cdot K_v}{J \cdot s} (K_t \cdot I_a - \tau_d) \quad \dots\dots (11)$$

5

Here, assuming the relationships shown in formulas 12 and 13 as ideal conditions, and substituting the formulas 10, 6, and 7 in the formula 7, the formula 7 is transformed as shown in the formula 14:

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$$K_t = K_{th} \quad \dots\dots (12)$$

$$\frac{L_b \cdot K_v}{J} = \frac{L_{bn} \cdot K_{vn}}{J_n} \quad \dots\dots (13)$$

15

$$\delta = \tau_d \quad \dots\dots (14)$$

$$\delta = \tau_d$$

That is, the value δ as the output of the subtracter 48 is equal to the disturbance τ_d exerted on the arm 3.

Therefore, determining a transfer function from the disturbance τ_d exerted on the arm 3 to the disturbance estimation signal τ_{dest} , the function is obtained as shown in the formula 15:

$$\tau_{dest} = \frac{\frac{L_{bn}}{J_n} \cdot K_{vn} \cdot g_2}{s^2 + \frac{L_{bn}}{J_n} \cdot K_{vn} \cdot g_1 \cdot s + \frac{L_{bn}}{J_n} \cdot K_{vn} \cdot g_2} \cdot \tau_d \quad \dots\dots (15)$$

From the formula 15, the disturbance estimation means 12 is understood that the actual disturbance τ_d can be estimated in a secondary delay system from the drive signal u and the voltage signal E_d by the loop in the block 30 surrounded with a single-dot chain line of Fig. 2.

Here, expressing the natural angular frequency (estimated angular frequency) of the secondary delay system as ω_0 and the damping factor as ζ_0 , the constants g_1 and g_2 to stabilize the operation of the disturbance estimation means 12 are expressed by the following formulas 16 and 17, respectively:

$$g_1 = 2\zeta_0 \cdot \omega_0 \cdot \frac{J_n}{L_{bn} \cdot K_{vn}} \quad \dots\dots (16)$$

$$g_2 = \omega_0^2 \cdot \frac{J_n}{L_{bn} \cdot K_{vn}} \quad \dots\dots (17)$$

Here, setting the estimated angular frequency ω_0 at a value higher than a position control band f_c , and selecting the damping factor as ζ_0 as 0.7 through 1, the disturbance τ_d such as a pivot bearing friction, an elastic force and an inertia force can be correctly estimated by the disturbance estimation means 12.

Transforming the formula 15 by the use of the formulas 16 and 17, the following formula 18 is obtained:

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That is, the block diagram of the disturbance estimation means 12 of Fig. 3A can be simplified as shown in a block 52 of Fig. 3C.

With reference to Fig. 4, the operation of the correction means 15 shown in the block 47 will be explained in detail hereinafter, on the assumption that the transfer function $F(s)$ of the filter means 16 is 1 to simplify the explanation. This corresponds to the operation of the positioning control system with a basic configuration in which the filter means 16 is not provided between the disturbance estimation means 12 and the correction means 15.

The block 47 of a portion surrounded with a single-dot chain line of Fig. 2 indicates the detail of the correction means 15. The block 45 outputs the correction signal β obtained by increasing the disturbance estimation signal τ_{dest} by $1/(g_{mn} \cdot K_{tn})$ times to the adder 46. That is, by increasing the disturbance estimation signal τ_{dest} by $1/(g_{mn} \cdot K_{tn})$ times, the correction signal β required to make the actuator 7 generate a drive force having a magnitude equivalent to the disturbance estimation signal τ_{dest} is outputted to the adder 46. Further, the correction signal β is increased $g_{mn} \cdot K_{tn}$ times by the blocks 22 and 23, so that the disturbance estimation signal τ_{dest} is previously increased $1/(g_{mn} \cdot K_{tn})$ times to match the magnitude with each other.

Concluding the above explanation, it can be said that the disk storage apparatus of the first embodiment is configured such that the disturbance estimation signal τ_{dest} is made to be exerted on the actuator 7 in a manner to negate the disturbance τ_d due to a pivot bearing friction of the actuator 7, an elastic

force of FPC connecting the actuator 7 with an electronic circuit board, an inertia forces exerted on the actuator 7 by a shock or vibration exerted on the disk storage apparatus from the outside, and the like.

5 Fig. 4A is a block diagram obtained by picking portions from the adder 46 to the comparator 29, and the block 24 relating the operation of the correction means 15. Fig. 4B is a block diagram in which the disturbance τ_d exerted on the comparator 29 and the one exerted on a block 52 are integrated into one
10 disturbance τ_d . Components having the same function as those in the block diagram of Fig. 2 are indicated by the same symbols to omit a duplicated explanation.

15 In the block diagram of Fig. 4A, the block 52 is equivalent to the block 52 of Fig. 3C, and has a transfer function expressed by the formula 15.

Therefore, from Fig. 4B, the disturbance τ_d exerted on the arm 3 from the outside can be considered to be exerted through a filter expressed by a transfer function of the formula 19 on the head positioning control system.

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$$G_d(s) = 1 - \frac{\omega_o^2}{s^2 + 2\zeta_o \cdot \omega_o \cdot s + \omega_o^2} \dots\dots (19)$$

$$= \frac{s^2 + 2\zeta_o \cdot \omega_o \cdot s}{s^2 + 2\zeta_o \cdot \omega_o \cdot s + \omega_o^2}$$

25 Fig. 5 shows the frequency characteristic of a transfer function $G_d(s)$ expressed by the formula 19 as a polygonal line approximation. From the frequency characteristic of the transfer function $G_d(s)$ shown in Fig. 5, at an angular frequency

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lower than the angular frequency ω_0 , the gain is 0 dB or less, and as the angular frequency ω drops, the gain is damped at a damping ratio of -20 dB/decade. The decade means ten times. That is, from Fig. 5, transfer function $G_d(s)$ has a low frequency
 5 cut-off filter characteristic capable of inhibiting a frequency lower than the angular frequency ω_0 .

That is, the disk storage apparatus of the first embodiment is configured such that even when the disturbance τ_d due to a pivot bearing friction, an elastic force, an inertia
 10 force or the like is exerted on the arm 3, the disturbance τ_d is estimated by the disturbance estimation means 12, and controlled in a manner to negated the disturbance τ_d exerted from the outside with the disturbance estimation signal τ_{dest} . Therefore, the disturbance τ_d exerted from the outside acts as
 15 if the disturbance τ_d is exerted through a filter having the cut-off frequency characteristic of the formula 19 and Fig. 5 on the head positioning control system.

Therefore, at a frequency lower than the angular frequency ω_0 , the first-order low frequency cut-off
 20 characteristic can inhibit the disturbance due to a pivot bearing friction of the actuator 7, an elastic force of FPC connecting the actuator 7 with an electronic circuit board, an inertia forces exerted on the actuator 7 by a shock or vibration exerted on the disk storage apparatus from the outside, and the
 25 like.

That is, even when a vibration or a shock is applied to the apparatus to cause the disturbance τ_d to be exerted on the actuator 7, the disturbance τ_d is estimated by the disturbance estimation means 12, and controlled in a manner to negated the
 30 disturbance τ_d exerted from the outside, so that there is an effect as if the disk storage apparatus is provided with a mechanical vibration-proof mechanism.

Figs. 6A to 6C are time response waveform views for

explaining the disturbance inhibiting effect of the disturbance estimation means 12 of the disk storage apparatus in the first embodiment in more detail.

Fig. 6A shows a waveform 61 (shown by the broken line) of the disturbance τ_d due to an inertia force exerted on the actuator 7 and a waveform 62 of the disturbance estimation signal τ_{dest} outputted by the disturbance estimation means 12 when a half-sine wave-shaped rotational shock with the maximum angular acceleration $d\omega_0/dt$ of 5000 radian/ sec² is exerted on the disk storage apparatus from the outside. Expressing an inertia moment J about the bearing 4 of the actuator 7 as 0.1g·cm², the maximum value of the disturbance τ_d becomes as follows:

$$\begin{aligned}\tau_{dmax} &= J \cdot \frac{d\omega_0}{dt} \quad \dots\dots (20) \\ &= 500dyn \cdot cm\end{aligned}$$

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Here, selecting the values of an estimation frequency f_0 ($\omega_0=2\pi f_0$) and a damping factor ζ_0 for determining control parameters of the formulas 16 and 17 as 3 kHz and 1, respectively, and setting the control band of the positioning control system at 800 Hz, a simulation has been performed.

The disturbance estimation means 12 estimates the disturbance torque τ_d exerted on the actuator 7 from the drive signal u as the input of the drive means 10 and from the voltage signal E_d outputted by the voltage detection means 11, and outputs the disturbance estimation signal τ_{dest} substantially similar to the actual disturbance τ_d , though a little time delay exists.

Fig. 6B shows a waveform 64 of the drive current I_a when the disturbance estimation signal τ_{dest} has been exerted on the

actuator 7 in a manner that the disturbance estimation signal τ_{dest} outputted by the disturbance estimation means 12 is inputted into the correction means 15 to negate a fluctuation due to the disturbance τ_d , and shows a simulation result of a waveform 63 of the drive current I_a when the disturbance estimation signal τ_{dest} is not inputted into the correction means 15. The torque constant K_t of the actuator 7 is 23 dyn·cm/mA.

Servo information recorded on the disk 1 has been recorded on the disk in a discrete condition having a certain sampling period, so that the head position signal is not a continuous signal. Therefore, the position control signal c of the position control means 14 for implementing digital processing is changed into a step-shaped one. As a result, the waveform of the drive current I_a of the actuator 7 when the disturbance estimation signal τ_{dest} is not inputted into the correction means 15 becomes the same waveform as that of the position control signal c , so that the waveform is changed into a step-shaped one as shown in the waveform 63 of Fig. 6B ($I_a = g_m \cdot c = g_m \cdot u$). The waveform 64 of the drive current I_a of the actuator 7 when the disturbance estimation signal τ_{dest} has been inputted into the correction means 15 is produced by adding the disturbance estimation signal τ_{dest} of the disturbance estimation means 12 to the control signal c of the position control means 14 by the correction means 15, so that the time delay thereof from a point ($t=0$) when a rotational shock is exerted on the disk storage apparatus is smaller than that of the waveform 63 of Fig. 6B. In addition, the waveform 64 is changed smoothly.

Fig. 6C shows a waveform 66 of the track position error signal e when the disturbance estimation signal τ_{dest} has been exerted on the actuator 7 in a manner that the disturbance estimation signal τ_{dest} outputted by the disturbance estimation means 12 is inputted into the correction means 15 to negate a fluctuation due to the disturbance, and shows a simulation

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result of a waveform 65 of the position error signal e when the disturbance estimation means 12 is not applied. Even when a half-sine wave-shaped rotational shock is exerted on the disk storage apparatus from the outside, if the disturbance estimation means 12 is applied, the position error signal e is not largely fluctuated as with the waveform 66, so that compared to the waveform 65 when the disturbance estimation means 12 is not applied, the disturbance inhibiting effect has been improved.

As a result, the disk storage apparatus of the first embodiment correctly detects the disturbance due to an inertia force exerted on the actuator 7 by a vibration or a shock exerted from the outside by the use of the disturbance estimation means 12 to allow a track dislocation due to the disturbance to be inhibited, whereby the head 2 is controlled at a high accuracy to be positioned to the target track. Therefore, the tracking control stable against the shock or vibration can be implemented, thereby improving the reliability of the disk storage apparatus.

Figs. 7A and 7B are open loop frequency characteristic views showing the transfer from the position error signal e to a head position x in the block diagram of the positioning control system of the disk storage apparatus of the first embodiment shown in Fig. 2. As can be understood from the gain characteristic view of Fig. 7A, a gain crossover frequency f_c with which the open loop gain becomes zero is 800Hz. In addition, as can be understood from the phase characteristic view of Fig. 7B, with the gain crossover frequency f_c , a phase margin θ_m is 50 degrees, thus constituting a stable head positioning control system. The reason is as follows. In the block 55 of the voltage detection means 11 surrounded with a single-dot chain line shown in Fig. 2, the block 39 with the voltage drop $(R_{an} + L_{an} \cdot s)$ is faithfully expressed to obtain the voltage drop

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of a coil resistance R_{an} and a coil inductance L_{an} generated by conducting the drive current I_a to the drive coil 5. Using the formula 10, the voltage signal E_d of the voltage detection means 11 is the pure output of a induced voltage E_a induced across the drive coil 5 by the rotation of the actuator 7.

Actually, however, since the coil inductance L_{an} is lower than the coil resistance R_{an} , it is difficult to accurately configure a circuit. Further, since $L_{an} \cdot s$ is a derivative element, it tends to be particularly influenced by noise and attention should be particularly taken to configure a circuit.

Figs. 8A and 8B are open loop frequency characteristic views showing the transfer from the position error signal e to the head position x if only the voltage drop of the coil resistance R_{an} is considered among those generated by conducting the drive current I_a to the drive coil 5 while ignoring the voltage drop of the coil inductance L_{an} in the block 39 included in the voltage detection means 11 in the block diagram of the positioning control system shown in Fig. 2.

As is obvious from the gain characteristic view of Fig. 8A and the phase characteristic view of Fig. 8B, if the coil inductance L_{an} of the drive coil 5 is omitted for simplification in the block 39 included in the voltage detection means 11, the head positioning control system including the disturbance estimation means 12 becomes unstable. That is, as can be understood from the gain characteristic view of Fig. 8A, the gain crossover frequency f_c with which the open loop gain becomes zero is 900 Hz and the phase at that time is a lag phase from -180 degrees, so that the control system becomes unstable. The voltage drop caused by the coil inductance L_{an} included in the drive coil 5 is smaller than that caused by the coil resistance R_{an} . However, the term $(L_{an} \cdot s)$ included in the block 39 included in the voltage detection means 11 is an important element to stabilize the positioning control system shown in

Fig. 2.

The positioning control system shown in Fig. 2 becomes unstable if the term $(L_{an} \cdot s)$ included in the block 39 is omitted for the following reason. Although the actual drive coil 5 contains the component of the coil resistance R_a and that of the coil inductance L_a , the voltage detection means 11 does not include the component of the coil inductance L_{an} . Therefore, to stabilize the positioning control system, the coil inductance of the drive coil 5 may be made equivalently zero.

Fig. 9 shows a circuit configuration to stabilize the positioning control system, in which a circuit having a capacitor C and a resistor r connected in series is connected to the drive coil 5 in parallel. In Fig. 9, a composite impedance Z_a if the circuit having the capacitor C and the resistor r connected in series is connected to the drive coil 5 in parallel is expressed by the following formula 21. In the formula 21, R_a indicates the coil resistance of the drive coil 5 and L_a indicates the inductance thereof.

$$Z_a = \frac{(R_a + L_a \cdot s) \left(r + \frac{1}{C \cdot s} \right)}{R_a + r + L_a \cdot s + \frac{1}{C \cdot s}} \quad \dots\dots (21)$$

Selecting the values of the resistor r and the capacitor C as shown in formulas 22 and 23, respectively, Z_a in the formula 21 can be expressed by formula 24.

$$r = R_a \quad \dots\dots (22)$$

$$C = \frac{L_a}{R_a^2} \quad \dots\dots (23)$$

$$Z_a = R_a \quad \dots\dots (24)$$

That is, if the values of the resistor r and the capacitor C which constitute the circuit shown in Fig. 9 are set at those
 5 shown in the formulas 22 and 23, respectively, the composite impedance Z_a generated across the drive coil 5 is equal to a resistance R_a as seen in the formula 24, so that the drive coil 5 does not equivalently include the coil inductance L_a .
 Therefore, as shown in Fig. 9, by connecting the circuit having
 10 the resistor r and the capacitor C connected in series, to the drive coil 5 in parallel, it suffices to consider only the voltage drop caused by the coil resistance R_{an} generated by the conductance of the drive current I_a to the drive coil 5 in the block 39 included in the voltage detection means 11 in the block
 15 diagram of the positioning control system shown in Fig. 2, and to use a block 49 shown in Fig. 10 instead of the block 39 included in the voltage detection means 11 shown in Fig. 2. As a result, it is possible to configure the voltage detection means 11 more simply.

20 In Figs. 8A and 8B, waveforms indicated by dotted lines are open loop frequency characteristics which show the transfer from the position error signal e to the head position x if the block 39 is replaced by the block 49 shown in Fig. 10 and if the circuit having the resistor r and the capacitor C , expressed
 25 by the formulas 22 and 23, respectively, connected in series is connected in parallel to the drive coil 5 of the actuator 7 across the coil 5, in the block diagram of the positioning control system of the disk storage apparatus of the first embodiment shown in Fig. 2. As can be understood from Figs.
 30 8A and 8B, the open loop frequency characteristics are almost equal to those shown in Figs. 7A and 7B.

In the above-mentioned explanation, the stability of the positioning control system if the coil resistance R_{an} of the

block 49 included in the voltage detection means 11 is equal to the coil resistance R_a of the drive coil 5 of the actuator 7, i.e., the formula 8 ($R_a=R_{an}$) is satisfied and the transfer function $F(s)$ of the filter means 16 is 1, is shown.

5 However, the coil resistance R_a of the drive coil 5 of the actuator 7 has a fluctuation of resistance value and the resistance value is changed following temperature rise after a drive current I_a is carried to the drive coil 5 to heat the drive coil 5. Therefore, even if the coil resistance R_a of the
10 drive coil 5 of the actuator 7 is initially equal to a nominal value R_{an} , the resistance value of the drive coil 5 is changed by the temperature rise during the operation, with the result that the formula 8 ($R_a=R_{an}$) is not satisfied.

 In Figs. 11A and 11B, waveforms indicated by solid lines
15 are open loop frequency characteristics which show the transfer from the position error signal e to the head position x if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} , in the block diagram of the positioning control system shown in Fig. 2.

20 In a simulation, the component of a coil inductance L_{an} is omitted in the block 39 included in the voltage detection means 11, and frequency characteristics if the coil resistance R_a of the drive coil 5 of the actuator 7 is larger than the nominal value R_{an} by 5% is obtained while the circuit having the resistor r and
25 the capacitor c connected in series and determined by the formulas 22 and 23 is connected in parallel to the drive coil (Fig. 9). That is, as can be understood from the gain characteristic view of Fig. 11A, the gain crossover frequency f_c with which the open loop gain becomes zero is 500 Hz. As
30 shown in Fig. 11B, phase at that time is approximately -180 degrees. Because of insufficient phase margin, the control system is unstable.

Next, the significance of providing the filter means 16 between the disturbance estimation means 12 and the correction means 15 will be described.

In the disk storage apparatus in the first embodiment shown in Fig. 2, if the disturbance estimation signal τ_{dest} outputted from the disturbance estimation means 12 is applied to the positioning control system as it is through the correction means 15 while the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} , the positioning control system becomes unstable. To stabilize the positioning control system, therefore, the disturbance estimation signal τ_{dest} outputted from the disturbance estimation means 12 expressed by the block 30 in Fig. 2 is outputted to the correction means 15 of the block 47 through the filter means 16 of the block 54.

The filter means 16 conducts filter processing as expressed by the transfer function $F(s)$ of the formulas 4 and 5, produces a filter signal f , and inputs the filter signal into the correction means 15. That is, the high frequency components higher in frequency than the filter low-pass cut-off frequency f_x are cut off by the filter means 16. As a result, the high frequency components of the disturbance estimation signal τ_{dest} outputted from the disturbance estimation means 12 are not equivalently outputted to the correction means 15. That is the significance of providing the filter means 16 between the disturbance estimation means 12 and the correction means 15. The significance will be described concretely below.

In Figs. 11A and 11B, waveforms indicated by dotted lines are open loop frequency characteristics which show the transfer from the position error signal e to the head position x if the disturbance estimation signal τ_{dest} outputted from the disturbance estimation means 12 is outputted to the correction means 15 of the block 47 through the filter means 16 of the block 54, in the block diagram of the positioning control system of the disk storage apparatus in the first embodiment shown in Fig. 2.

In a simulation, frequency characteristics if the filter low-pass cut-off frequency f_x is set at 400 Hz in the block 54 showing the filter means 16, and the coil resistance R_a of the drive coil 5 of the actuator 7 is higher than the nominal value R_{an} by 5%. As can be understood from the gain characteristic view of Fig. 11A, the gain crossover frequency f_c with which the open loop gain becomes zero is 500 Hz. In addition, as can be understood from the phase characteristic view of Fig. 11B, with the gain crossover frequency f_c , the phase margin θ_m is 40 degrees, thus constituting a stable head positioning control system.

That is, by inserting the filter means 16 between the output of the disturbance estimation means 12 and the input of the correction means 15, it is possible to stabilize the positioning control system even if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value by the resistance fluctuation or temperature rise.

The disk storage apparatus of the first embodiment explained above is configured such that the drive signal u outputted from the block 47 is inputted as one of the input signals for the disturbance estimation means 12. Needless to say, the same effect can be attained even if the drive current I_a outputted from the drive means 10 outputted from the block

22 instead of the drive signal u is used.

Second Embodiment

Fig. 12 is a block diagram showing the configuration of a magnetic disk storage apparatus which is one example of a disk storage apparatus in the second embodiment according to the present invention. Fig. 13 is a block diagram showing the whole configuration of a head positioning control system in the magnetic disk storage apparatus in the second embodiment. It is noted that components having the same functions as those in the first embodiment are denoted by the same reference numerals, respectively and will not be repeatedly explained.

The disk storage apparatus in the second embodiment of Fig. 12 is different from that in the first embodiment of Fig. 1 in a signal inputted into the disturbance estimation means. While the first embodiment of Fig. 1 has been configured such that the voltage signal E_d and the drive signal u produced by the voltage detection means 11 are inputted into the disturbance estimation means 12, in the second embodiment of Fig. 12, the voltage signal E_d produced by the voltage detection means 11 and the position control signal c produced by the position control means 14 are inputted into disturbance estimation means 17.

The disturbance estimation signal τ_{dest} produced by the disturbance estimation means 17 of Fig. 12 is inputted into the correction means 15 through the filter means 16. The correction means 15, into which the position control signal c outputted from the position control means 14, the disturbance estimation signal τ_{dest} produced by the disturbance estimation means 17, and the filter signal f passing through the filter means 16 are inputted, implements a correction computing and then outputs the drive signal u to the drive means 10.

The block 60 surrounded with a single-dot chain line in

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Fig. 13 is a block diagram of the disturbance estimation means 17. Inputted into the disturbance estimation means 17 are the voltage signal E_d produced by the voltage detection means 11 as the output of the adder 36 and the position control signal c produced by the position control means 14 expressed by the block 21.

In the above-mentioned disturbance estimation means 12 of the first embodiment, the computing has been implemented as follows: A signal obtained by multiplying a deviation signal α from a comparator 37 by the coefficient g_2/s of the first integrator 43, and a signal obtained by multiplying a deviation signal α by the coefficient g_1 of the second multiplier 44 are added to each other at the adder 38. A signal obtained by the addition and the drive torque estimation signal τ_{est} produced by multiplying a drive signal u by the coefficient $g_{mn} \cdot K_{tn}$ of the first multiplier 41 are inputted into the subtracter 31. The signal γ obtained by the subtraction of the subtracter 31 has been inputted into the second integrator 42. That is, the drive signal u obtained by adding the correction signal β to the control signal c has been inputted into the disturbance estimation means 12, so that the adder 38 of Fig. 2 has been required.

However, the disturbance estimation means 17 of the second embodiment is configured such that the position control signal c is inputted before the correction signal β is added, so that the adder 38 as shown in Fig. 2 is not required.

Compared to the operation of the disturbance estimation means 12 of the first embodiment, the operation of the disturbance estimation means 17 of the disk storage apparatus of the second embodiment configured as explained above will be explained hereinafter referring to Figs. 2 and 13.

First, in Fig. 2, expressing the input of the second integrator 42 constituting the disturbance estimation means 12

of the first embodiment as γ , by noting the subtracter 31, the signal γ is expressed as follows:

$$\begin{aligned} \gamma &= \tau_{est} - (\tau_{dest} + g_1 \cdot \alpha) \\ &= g_{mn} \cdot K_{tn} \cdot u - (\tau_{dest} + g_1 \cdot \alpha) \quad \dots\dots (25) \end{aligned}$$

While by noting the adder 46 of Fig. 2, the drive signal u is expressed by the formula 26:

$$\begin{aligned} u &= c + \beta \\ &= c + \frac{1}{g_{mn} \cdot K_{tn}} \cdot \tau_{dest} \quad \dots\dots (26) \end{aligned}$$

Therefore, from the formulas 25 and 26, the signal γ can be expressed by the formula 27:

$$\gamma = g_{mn} \cdot K_{tn} \cdot c - g_1 \cdot \alpha \quad \dots\dots (27)$$

Based on the formula 27, the block diagram 30 of the disturbance estimation means 12 of the first embodiment shown in Fig. 2 is changed to the block diagram 60 of the disturbance estimation means 17 shown in Fig. 13. As shown in Fig. 13, the position control signal c produced by the position control means 14 (block 21) is inputted into the multiplier 32, and the output of the multiplier 32 is inputted into the multiplier 33. Hence, multiplying the position control signal c by the coefficient $g_{mn} \cdot K_{tn}$ allows the drive torque estimation signal τ_{est} to be

obtained.

On the other hand, the disturbance estimation signal τ_{dest} is inputted into the correction means 15 expressed by the block 47 through the filter means 16 expressed by the block 54.

5 Therefore, similarly the first embodiment, the disk storage apparatus of the second embodiment estimates the disturbance torque acting on the arm 3 from the voltage signal E_d produced by the voltage detection means 11 and the position control signal c produced by the position control means 14, and outputs
10 the disturbance estimation signal τ_{dest} by the function of the disturbance estimation means 17. The disturbance estimation signal τ_{dest} is inputted into the correction means 15 so as to negate the disturbance τ_d such as a pivot bearing friction, an elastic force, and an inertia force exerted on the arm 3.

15 Further, similarly to the disk storage apparatus of the first embodiment, since the filter means 16 is inserted between the output of the disturbance estimation means 17 and the input of the correction means 15, it is possible to stabilize the positioning control system even if the coil resistance R_a of
20 the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value by the resistance fluctuation or temperature rise.

Therefore, the disk storage apparatus of the second embodiment can correctly detect the disturbance such as an
25 inertia force acting on the actuator 7 due to shock/vibration applied from the outside by the disturbance estimation means 17. This disk storage apparatus is configured such that even if the disturbance τ_d acts on the actuator 7, such as pivot bearing friction, an elastic force of the FPC, and an inertia
30 force due to shock/vibration exerted from the outside, the disturbance estimation means 17 is controlled to estimate this disturbance τ_d and the disturbance τ_d exerted from the outside is negated by the disturbance estimation signal τ_{dest} thus

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estimated. Therefore, similarly to the first embodiment, the disturbance τ_d exerted from the outside acts as if the disturbance τ_d is exerted through a filter having the cut-off frequency characteristic of the formula 19 and Fig. 5 on the positioning control system. Hence, according to the disk storage apparatus of the second embodiment, with a frequency lower than the angular frequency ω_0 , it is possible to inhibit the disturbance by the first-order low frequency cut-off characteristic, and to inhibit a track dislocation due to the disturbance, whereby the head 2 is controlled at a high accuracy to be positioned to the target track. Therefore, the tracking control stable against the shock or vibration can be implemented, thereby improving the reliability of the disk storage apparatus.

As can be seen, according to the disk storage apparatus of the second embodiment, the number of adders required to constitute the disturbance estimation means 17 can be reduced compared with the disk storage apparatus of the first embodiment. Therefore, compared with the first embodiment, the disk storage apparatus of the second embodiment can estimate the disturbance τ_d acting on the arm 3 such as a pivot bearing friction, an elastic force and an inertia force acting on the head positioning control system as the disturbance, by simple configuration, stably control head positioning, and position the head 2 to the target track formed at narrow track pitches with high accuracy.

Furthermore, according to the disk storage apparatus of the second embodiment, the number of the adders can be reduced, so that when the positioning control system is embodied with a hardware such as an analog circuit, the adjustment of such circuit can be simplified. Further, when the positioning control system is embodied with a software, the computing time delay by computing process can be shortened.

The disturbance estimation means 12 configured similarly

to the block 30 shown in Fig.2, is not affected by the sampling frequency of the sector servo of the disk storage apparatus. Therefore, the control band of the disturbance estimation means 12 can be set higher than that of the positioning control system.

5 Moreover, according to the disk storage apparatus of the second embodiment, the number of the adders constituting the disturbance estimation means 17 can be reduced. Therefore, when the control system is embodied with a hardware such as an analog circuit, the adjustment of such circuit can be simplified.
10 Further, when the control system is embodied with a software, the computing time delay by computing process can be shortened, thereby making it possible to set the control band higher.

Additionally, according to the disk storage apparatus of the second embodiment, by inserting the filter means 16 between
15 the output of the disturbance estimation means 12 and the input of the correction means 15, it is possible to stabilize the positioning control system even if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value by the
20 resistance fluctuation or temperature rise.

Third Embodiment

Fig. 14 is a block diagram showing the configuration of a magnetic disk storage apparatus which is one example of a disk
25 storage apparatus in the third embodiment according to the present invention. Fig. 15 is a block diagram showing the whole configuration of the positioning control system of the magnetic disk storage apparatus in the third embodiment. In the third embodiment, the filter means 16 and the block 54 having the
30 transfer function $F(s)$ in the first embodiment are not provided. Disturbance estimation means 12A and correction means 15A partially differ from the disturbance estimation means 12 and correction means 15 in the first embodiment. The

configurations of the other components are the same as those in the first embodiment shown in Figs. 1 and 2. It is noted that components or members having the same functions as those shown in the first embodiment are denoted by the same numerals,
 5 respectively and will not be repeatedly explained herein.

Next, the operation of the positioning control system of the disk storage apparatus in the third embodiment will be explained hereinafter.

In Figs. 16A and 16B, waveforms indicated by broken lines
 10 are open loop frequency characteristics which show the transfer from the position error signal e to the head position x if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} , in the block diagram of the positioning control system shown in Fig. 15. In a simulation,
 15 frequency characteristics if the component of the coil inductance L_{an} is omitted in the block 39 included in the voltage detection means 11 and if the coil resistance R_a of the drive coil 5 of the actuator 7 is larger than the nominal value R_{an} by 5%, is obtained. That is, as can be understood from the gain
 20 characteristic view indicated by a broken line in Fig. 16A, the gain crossover frequency f_c with which the open loop gain becomes zero is 300 Hz and the phase is almost equal to -210 degrees. Because of lack of phase margin, the positioning control system is unstable.

25 Next, explanation will be given to a case where the gain crossover frequency with which the open loop gain becomes zero is greatly decreased from that shown in Fig. 7 ($R_a=R_{an}$) if the coil resistance R_a of the drive coil 5 of the actuator 7 is higher than the nominal value R_{an} by 5%.

30 If the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} , the voltage signal E_a is expressed by the following formula 28:

$$E_d = E_a + (R_a - R_{an}) \cdot I_a \quad \dots\dots (28)$$

That is, the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value caused by the resistance fluctuation or temperature rise, the voltage signal E_d of the voltage detection means 11 is equal to the output of the addition result of adding the induced voltage E_a induced across the drive coil 5 by the rotation of the actuator 7 to the voltage drop $(R_a - R_{an}) \cdot I_a$ generated by the conduction of the drive current I_a into the drive coil 5.

Figs. 17A and 17B are block diagrams for explaining that the gain changes if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value caused by the resistance fluctuation or temperature rise.

Fig. 17A is a block diagram obtained by changing the block diagram of Fig. 3B while noting the second term of the formula 28. Fig. 17B is a block diagram equivalently transformed from the block diagram of Fig. 17A. Fig. 17C is a block diagram obtained by changing a part of the block diagram of Fig. 15 based on the block diagram of Fig. 17B. That is, if R_a is not equal to R_{an} , this is equivalent to the addition of the negative feedback loop of the blocks 54, 52 and 45 to the block 22 (the transfer function is g_m) in the block diagram of Fig. 15.

In the block diagram of Fig. 17C, the composite transfer frequency $G_m(s)$ from the position control signal c to the drive current I_a is expressed by the following formula 29.

$$G_m(s) = \frac{g_m}{1 + \frac{g_m}{g_{mn}} \cdot \frac{J_n(R_a - R_{an})}{L_{bn} \cdot K_{vn} \cdot K_{tn}} \cdot \frac{\omega_o^2}{s^2 + 2\zeta_o \cdot \omega_o \cdot s + \omega_o^2} \cdot s} \quad \dots\dots (29)$$

In the formula 29, the estimation frequency f_o ($=\omega_o/2\pi$) is set sufficiently higher than the position control band f_c , so that formula 30 is established. As a result, the formula 29 can be simplified to formula 31.

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$$\frac{\omega_o^2}{s^2 + 2\zeta_o \cdot \omega_o \cdot s + \omega_o^2} = 1 \quad \dots\dots (30)$$

$$G_m(s) = \frac{g_m}{1 + \frac{g_m}{g_{mn}} \cdot \frac{J_n(R_a - R_{an})}{L_{bn} \cdot K_{vn} \cdot K_{in}} \cdot s} \quad \dots\dots (31)$$

10 In the formula 31, at $R_a = R_{an}$, $G_m(s) = g_m$; however, at $R_a \neq R_{an}$, the gain $G_m(s)$ decreases.

Here, if g_{mn} is substituted as shown in the following formula 32, the formula 31 is transformed to formula 33.

15 $g_{mn} = k \cdot g_m \quad \dots\dots (32)$

$$G_m(s) = \frac{g_m}{1 + \frac{1}{k} \cdot \frac{J_n(R_a - R_{an})}{L_{bn} \cdot K_{vn} \cdot K_{in}} \cdot s} \quad \dots\dots (33)$$

20 Here, selecting, as the coefficient k of a real number, a number sufficiently greater than 1 ($k \gg 1$), the term including $(R_a - R_{an})$ in the denominator of the formula 33 can be regarded as 0. Even if $R_a \neq R_{an}$, the formula 33 can be expressed by formula 34 by approximation.

25 $G_m(s) = g_m \quad \dots\dots (34)$

As stated above, according to the third embodiment, even if the coil resistance R_a of the drive coil 5 of the actuator

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7 is not equal to the nominal value R_{an} due to the change of the resistance value by the resistance fluctuation or temperature rise, the composite transfer function $G_m(s)$ from the position control signal c to the drive current I_a does not
 5 change and the formula 34 is always established by setting the coefficient k of the actual number sufficiently greater. The significance of this formula is that it does not include R_a and R_{an} . Therefore, even if the coil resistance R_a changes due to the resistance fluctuation or temperature rise, the open loop
 10 gain of the positioning control system does not greatly change, making it possible to stabilize the positioning control system.

In Figs. 16A and 16B, waveforms indicated by solid lines are open loop frequency characteristics which show the transfer from the position error signal e to the head position x if the
 15 coefficient k of the formula 32 is 50 in the block diagram of the positioning control system shown in Fig. 15. In a simulation, similarly to the cases indicated by broken lines ($k=1$) in Figs. 16A and 16B, frequency characteristics are obtained if the coil resistance R_a of the drive coil 5 of the
 20 actuator 7 is higher than the nominal value R_{an} by 5%. As can be understood from the gain characteristic view indicated by the solid line in Fig. 16A, the gain crossover frequency f_c with which the open loop gain becomes zero is 800 Hz. In addition, as can be understood from the phase characteristic view
 25 indicated by the solid line in Fig. 16B, with the gain crossover frequency f_c , the phase margin θ_m is 50 degrees, thus constituting a stable head positioning control system.

That is, setting the coefficient g_{mn} of the block 32 in the block 30A of the disturbance estimation means 12A and the
 30 coefficient g_{mn} of the denominator of the block 45 of the correction means 15A shown in Fig. 15 to be k times ($k \gg 1$) of the transfer function g_m of the block 22, it is possible to stabilize the positioning control system even if the coil

resistance R_a of the drive coil of the actuator 7 is not equal to the nominal value R_{an} due to the change of the resistance value by the resistance fluctuation or temperature rise.

In the block 30A of the disturbance estimation means 12A in Fig. 15, the block 32 of the first multiplier 41 into which the drive signal u is inputted has a coefficient g_{mn} , meaning that the block 32 multiplies the drive signal u by g_{mn} . This g_{mn} is expressed by approximation ($g_{mn}=k \cdot g_m$) in the formula 32.

Here, the block 32 can be considered while dividing the block 32 into a block having a coefficient g_m and a block having a coefficient k_1 ($=k$). In this case, similarly to the formula 6 in the first embodiment, the following formula 35 can be set:

$$g_{mn}=g_m \quad \dots\dots (35)$$

15

If changing Fig. 15 by changing the block 32 to a block having the coefficient g_{mn} equal to the coefficient g_m and the block 71 to a block having the coefficient having a coefficient k_1 , a block diagram as shown in Fig. 19 is obtained. The coefficient of the block 45, into which the disturbance estimation signal τ_{dest} is inputted from the first integrator 43, is $(1/g_{mn} \cdot K_{tn})$ and includes g_{mn} . Therefore, in Fig. 19, a block 72 having a coefficient $(1/k_2)$ is arranged between the first integrator 43 and the block 45. Here, the relationship between k_1 of the block 71 and k_2 of the block 72 is basically as shown in the following formula 36.

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$$k_1=k_2 \quad \dots\dots (36)$$

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Practically, however, the condition of the formula 36 is not always essential but k_1 and k_2 may be approximate to each other with a certain degree of allowance. That is, ks can be expressed by formula 37 wherein an allowance coefficient η is

close to 1.

$$k_2 = \eta \cdot k_1 \quad \dots\dots (37)$$

5 The concrete value of the allowance coefficient η may be appropriately set according to the specification of the actual apparatus. Empirically, the allowance coefficient η may be in a range of 0.7 to 1.3, preferably 0.8 to 1.2, more preferably 0.9 to 1.1. These can be expressed as shown in formulas 38,
10 39 and 40, respectively.

$$0.7k_1 \leq k_2 \leq 1.3k_1 \quad \dots\dots (38)$$

$$0.8k_1 \leq k_2 \leq 1.2k_1 \quad \dots\dots (39)$$

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$$0.9k_1 \leq k_2 \leq 1.1k_1 \quad \dots\dots (40)$$

It is ideal that the coefficient η is 1.0.

If changing Fig. 14 to correspond to Fig. 19, the block
20 diagram becomes that shown in Fig. 18. That is, the disturbance estimation means 12A of the third embodiment is the combination of the disturbance estimation means 12 of the first embodiment and the first correction multiplication means 18 of the third embodiment. In addition, the correction means 15A of the third
25 embodiment is the combination of the correction means 15 of the first embodiment and the second correction multiplication means 19 of the third embodiment. The first correction multiplication means 18 having the transfer function of k_1 is inserted into the path for transferring the drive signal u from
30 the correction means 15 to the disturbance estimation means 12, and the second correction multiplication means 19 having the transfer function of k_2 is inserted into the path for transferring the disturbance estimation signal τ_{dest} from the

disturbance estimation means 12 to the correction means 15. In Fig. 19, the block 71 corresponds to the first correction multiplication means 18, and block 72 corresponds to the second correction multiplication means 19.

5 If the third embodiment is described based on Figs. 18 and 19, the disturbance estimation means 12A is configured to generate the disturbance estimation signal τ_{dest} from the signal obtained by multiplying the drive signal u by k_1 and the voltage signal E_d . The correction means 15A is configured to combine
10 the position control signal c with the signal obtained by multiplying the disturbance estimation signal τ_{dest} by $1/k_2$.

 The disk storage apparatus in the third embodiment is configured such that the drive signal u outputted from the block 47A is inputted into one of the input signals for the disturbance
15 estimation means 12A. Needless to say, the same effect can be attained even if the drive current I_a outputted from the drive means 10 outputted from the block 22 instead of the drive signal u is used.

20 Fourth Embodiment

 Fig. 20 is a block diagram showing the configuration of a magnetic disk storage apparatus which is one example of a disk storage apparatus in the fourth embodiment according to the present invention. Fig. 21 is a block diagram showing the whole
25 configuration of the positioning control system of the magnetic disk storage apparatus in the fourth embodiment. In the fourth embodiment, the filter means 16 and the block 54 having the transfer function $F(s)$ in the second embodiment are not provided. Inputs to the disturbance estimation means 17A of the fourth
30 embodiment differ from those of the disturbance estimation means 12A of the third embodiment. That is, the voltage signal E_d from the voltage detection means 11 and the position control signal c from the position control means 14 are inputted into

the disturbance estimation means 17A. The configurations of the other components are the same as those in the third embodiment shown in Figs. 14 and 15. It is noted that components or members having the same functions as those shown in the third
5 embodiment are denoted by the same numerals, respectively and will not be repeatedly explained herein.

The relationship between the disk storage apparatus of the fourth embodiment shown in Fig. 20 and that of the third embodiment shown in Fig. 14 corresponds to the relationship
10 between the disk storage apparatus of the second embodiment shown in Fig. 12 and that of the first embodiment shown in Fig. 1. However, the filter means 16 is not provided. In the third embodiment shown in Fig. 14, the voltage signal E_d produced by the voltage detection means 11 and the drive signal u are
15 inputted into the disturbance estimation means 12A. In the fourth embodiment shown in Fig. 20, the voltage signal E_d produced by the voltage detection means 11 and the position control signal c produced by the position control means 14 are inputted into the disturbance estimation means 17A.

20 Therefore, in the fourth embodiment, the formulas 25 to 27 are established. Accordingly, if the block 30A of the disturbance estimation means 12A of the third embodiment shown in Fig. 15 is changed, it becomes equal to the block 60A of the disturbance estimation means 17A shown in Fig. 21. This
25 corresponds to Fig. 13 in the second embodiment. However, the block 54 corresponding to the filter 16 is not provided.

Further, by configuring the apparatus similarly to the third embodiment, the formulas 28 to 40 are established in the fourth embodiment. In the formula 32, by setting the
30 coefficient k of the actual number sufficiently greater, it is possible to stabilize the positioning control system even if the coil resistance R_a of the drive coil 5 of the actuator 7 is not equal to the nominal value R_{an} due to the change of the

resistance value by the resistance fluctuation or temperature rise.

As a result, according to the disk storage apparatus of the fourth embodiment, the disturbance such as an inertia force acting on the actuator 7 due to shock/vibration exerted from the outside can be correctly detected by the disturbance estimation means 17A. Even if the disturbance τ_d acts on the actuator 7, such as pivot bearing friction, an elastic force of the FPC, and an inertia force due to shock/vibration exerted from the outside, the disturbance estimation means 17A is controlled to estimate this disturbance τ_d and the disturbance τ_d exerted from the outside is negated by the disturbance estimation signal τ_{dest} thus estimated. Therefore, similarly to the third embodiment, the disturbance τ_d exerted from the outside acts as if the disturbance τ_d is exerted through a filter having the cut-off frequency characteristic of the formula 19 and Fig. 5 on the positioning control system. Hence, according to the disk storage apparatus of the fourth embodiment, with a frequency lower than the angular frequency ω_0 , it is possible to inhibit the disturbance by the first-order low frequency cut-off characteristic, and to inhibit a track dislocation due to the disturbance, whereby the head 2 is controlled at a high accuracy to be positioned to the target track. Therefore, the tracking control stable against the shock or vibration can be implemented, thereby improving the reliability of the disk storage apparatus.

As can be seen, according to the disk storage apparatus of the fourth embodiment, the number of adders required to constitute the disturbance estimation means 17A can be reduced compared with the disk storage apparatus of the third embodiment. Therefore, compared with the third embodiment, the disk storage apparatus of the fourth embodiment can estimate the disturbance τ_d acting on the arm 3 such as a pivot bearing friction, an elastic

force and an inertia force acting on the head positioning control system as the disturbance, by simple configuration, stably control head positioning, and position the head 2 to the target track formed at narrow track pitches with high accuracy.

5 Furthermore, according to the disk storage apparatus of the fourth embodiment, the number of the adders can be reduced, so that when the positioning control system is embodied with a hardware such as an analog circuit, the adjustment of such circuit can be simplified. Further, when the positioning
10 control system is embodied with a software, the computing time delay by computing process can be shortened.

Similarly to the third embodiment, the disturbance estimation means 17A is not affected by the sampling frequency of the sector servo of the disk storage apparatus. Therefore,
15 the control band of the disturbance estimation means 17A can be set higher than that of the positioning control system.

Moreover, according to the disk storage apparatus of the fourth embodiment, the number of the adders constituting the disturbance estimation means 17A can be reduced. Therefore,
20 when the control system is embodied with a hardware such as an analog circuit, the adjustment of such circuit can be simplified. Further, when the control system is embodied with a software, the computing time delay by computing process can be shortened, thereby making it possible to set the control band higher.

25 If changing Figs. 20 and 21 using the coefficients k_1 and k_2 , similarly to the third embodiment, the block diagrams become those shown in Fig. 22 and 23, respectively. That is, the disturbance estimation means 17A of the fourth embodiment is the combination of the disturbance estimation means 17 of the
30 second embodiment and the first correction multiplication means 18 of the fourth embodiment. In addition, the correction means 15A of the fourth embodiment is the combination of the correction means 15 of the second embodiment and the second

correction multiplication means 19 of the fourth embodiment. The first correction multiplication means 18 having the transfer function of k_1 is inserted into the path for transferring the drive signal u from the correction means 15
 5 to the disturbance estimation means 17, and the second correction multiplication means 19 having the transfer function of k_2 is inserted into the path for transferring the disturbance estimation signal τ_{dest} from the disturbance estimation means 17 to the correction means 15. In Fig. 23, the block 71 corresponds
 10 to the first correction multiplication means 18, and block 72 corresponds to the second correction multiplication means 19.

If the fourth embodiment is described based on Figs. 22 and 23, the disturbance estimation means 17A is configured to generate the disturbance estimation signal τ_{dest} from the signal
 15 obtained by multiplying the position control signal c by k_1 and the voltage signal E_d . The correction means 15A is configured to combine the position control signal c with the signal obtained by multiplying the disturbance estimation signal τ_{dest} by $1/k_2$.

20 The following embodiments may be employed besides the above-mentioned embodiments. As shown in Fig. 24, the first and third embodiments may be combined. As shown in Fig. 25, the second and fourth embodiments may be combined. That is, in either embodiment, the filter means 16 for cutting off the
 25 high frequency components of the disturbance estimation signal τ_{dest} is added to the correction means 15A.

In the disk storage apparatus in the first to fourth embodiment explained so far, the multipliers and integrators are configured by analog filters. Alternatively, they can be
 30 configured by digital filters. Further, the respective components constituting the positioning control system in each embodiment may be embodied in a software by a microcomputer.

While the disk storage apparatuses of the first to fourth

embodiments have been explained as the magnetic disk storage apparatuses, the present invention is not limited to this, and can be applied to the other information recording apparatuses such as an optical disk storage apparatus and a magneto-optical disk storage apparatus.

As stated so far, according to the disk storage apparatus of the present invention, to estimate the disturbance such as a pivot bearing friction, an elastic force or an inertia force exerted on the actuator means, the disturbance estimation signal is produced by combining one of the drive signal and the position control signal with the voltage signal induced across the drive coil of the actuator means. Since the voltage signal is a continuous signal, it is possible to correctly detect the disturbance, compared with the conventional art using discrete servo information. Accordingly, even if the fluctuation of the disturbance during following operation directed toward the target track is large, it is possible to surely compensate this fluctuation and to improve the positioning accuracy of the head with respect to the target track. Besides, by negating the inertia force exerted on the actuator means due to shock/vibration from the outside, it is possible to improve the shock resistance characteristic of the disk storage apparatus and to stably implement head positioning control.

According to the disk storage apparatus of the present invention, besides the above-stated functions and effects, to produce the drive signal based on the position control signal for the head position and the disturbance estimation signal, the high frequency components of the disturbance estimation signal are cut off by the filter means to thereby produce a filter signal, and the filter signal is combined with the position control signal for the head position to thereby produce the drive signal. Therefore, it is possible to stabilize the positioning control system even if the coil resistance of the

drive coil of the actuator means is not equal to the nominal value due to the change of the resistance value by the resistance fluctuation or temperature rise.

Moreover, the disturbance estimation means is configured to produce the disturbance estimation signal based on the signal obtained by multiplying the drive signal or position control signal by k_1 and the voltage signal, and the correction means is configured to produce the drive signal by combining the signal obtained by multiplying the disturbance estimation signal by $1/k_2$ with the position control signal ($k_1 \gg 1$, $k_2 \gg 1$). By so configuring, it is possible to stabilize the positioning control system even if the coil resistance of the drive coil of the actuator means is not equal to the nominal value due to the change of the resistance value by the resistance fluctuation or temperature rise.

Hence, particularly if the influence of the disturbance, which is exerted on the actuator means, on the positioning control system increases as the actuator means is made small in size and light in weight and the resistance fluctuation of the drive coil and the change of the resistance value occur, the disk storage apparatus of the present invention can deal with more diverse conditional changes by improving the head positioning accuracy and improve the track density compared from the conventional apparatus. It is, therefore, possible to realize a large capacity disk storage apparatus.

What is claimed is:

1. A disk storage apparatus comprising:

actuator means for positioning a head with respect to
a disk;

5 drive means for driving said actuator means in
accordance with an input drive signal;

drive coil voltage detection means for detecting a
drive coil voltage induced in driving said actuator means,
and for outputting a voltage signal;

10 disturbance torque estimation means for estimating a
magnitude of a disturbance torque exerted on said head from
said drive signal and said voltage signal, and for
producing a disturbance estimation signal;

filter means for cutting off a high frequency
15 component of said disturbance estimation signal, and for
outputting a filter signal;

position detection means for producing a position
error signal corresponding to a current position of said
head from servo information previously recorded on said
20 disk and detected by said head, and for outputting the
position error signal;

position control means for producing a position
control signal corresponding to said position error signal,
and for outputting the position control signal; and

correction means for combining said position control signal with said filter signal to produce said drive signal, and for outputting the drive signal.

2. A disk storage apparatus according to claim 1,
5 wherein said disturbance torque estimation means comprises:

comparison means for receiving the voltage signal detected by said voltage detection means;

first multiplication means for multiplying said drive
10 signal by a coefficient consisting of a first transfer function;

second multiplication means for multiplying an output of said comparison means by a coefficient consisting of a second transfer function;

15 first integration means for integrating the output of said comparison means; and

second integration means for integrating a value obtained by subtracting the added value of the output of said second multiplication means and the output of said
20 first integration means from the output of said first multiplication means, and

said comparison means compares said voltage signal with the output of said second integration means, and

outputs a comparison result to said second multiplication means and said first integration means.

3. A disk storage apparatus according to claim 1, wherein

5 an estimation frequency of said disturbance estimation signal produced by said disturbance estimation means is set at a value higher than a control frequency band of said position control means.

4. A disk storage apparatus according to claim 1, 10 wherein

a cut-off frequency of said filter means is set at a value lower than a control band of said position control means.

5. A disk storage apparatus according to claim 1, 15 wherein

said actuator means is configured by a permanent magnet fixedly attached to at least one yoke of a pair of yokes in a cavity of the pair of yokes opposite to each other through the cavity, and a drive coil provided in a 20 magnetic cavity formed by said permanent magnet and said yokes.

a circuit having a capacitor and a resistor connected in series, is connected to said drive coil in parallel,

said capacitor and said resistor connected to said drive coil in parallel are set to have a capacitance value C and a resistance value r as expressed by

$$C=La/Ra^2, \text{ and } r=Ra, \text{ or}$$

5 approximate to $C=La/Ra^2$, and $r=Ra$, respectively.

6. A disk storage apparatus, comprising:

actuator means for positioning a head with respect to a disk;

drive means for driving said actuator means in
10 accordance with an input drive signal;

drive coil voltage detection means for detecting a drive coil voltage induced in driving said actuator means, and for outputting a voltage signal;

position detection means for producing a position
15 error signal corresponding to a current position of said head from servo information previously recorded on said disk and detected by said head, and for outputting the position error signal;

position control means for producing a position
20 control signal corresponding to said position error signal, and for outputting the position control signal;

disturbance torque estimation means for estimating a magnitude of a disturbance torque exerted on said head from

said voltage signal and said position control signal, and
for producing a disturbance estimation signal;

filter means for cutting off a high frequency
component of said disturbance estimation signal, and for
5 outputting a filter signal; and

correction means for combining said position control
signal with said filter signal to produce said drive
signal, and for outputting the drive signal.

7. A disk storage apparatus according to claim 6,
10 wherein

said disturbance torque estimation means comprises:

comparison means for receiving the voltage signal
detected by said voltage detection means;

first multiplication means for multiplying said
15 position control by a coefficient consisting of a first
transfer function;

second multiplication means for multiplying an output
of said comparison means by a coefficient consisting of a
second transfer function;

20 first integration means for integrating the output of
said comparison means; and

second integration means for integrating a value
obtained by subtracting the output of said second

multiplication means from the output of said first
multiplication means, and

said comparison means compares said voltage signal
with the output of said second integration means, and
5 outputs a comparison result to said second multiplication
means and said first integration means.

8. A disk storage apparatus according to claim 6,
wherein

an estimation frequency of said disturbance estimation
10 signal produced by said disturbance torque estimation means
is set at a value higher than a control frequency band of
said position control means.

9. A disk storage apparatus according to claim 6,
wherein

15 a cut-off frequency of said filter means is set at a
value smaller than a control band of said position control
means.

10. A disk storage apparatus according to claim 6,
wherein

20 said actuator means is configured by a permanent
magnet fixedly attached to at least one yoke of a pair of
yokes in a cavity of the pair of yokes opposite to each
other through the cavity, and a drive coil provided in a

magnetic cavity formed by said permanent magnet and said yokes,

a circuit having a capacitor and a resistor connected in series, is connected to said drive coil in parallel,

5 said capacitor and said resistor connected to said drive coil in parallel are set to have a capacitance value C and a resistance value r as expressed by

$$C = L_a / R_a^2, \text{ and } r = R_a, \text{ or}$$

approximate to $C = L_a / R_a^2$, and $r = R_a$, respectively.

10 11. A disk storage apparatus comprising:

actuator means for positioning a head with respect to a disk;

drive means for driving said actuator means in accordance with an input drive signal;

15 drive coil voltage detection means for detecting a drive coil voltage induced in driving said actuator means, and for outputting a voltage signal;

disturbance estimation means for estimating a magnitude of a disturbance exerted on said head from a
20 signal obtained by multiplying said drive signal by k_1 , where k_1 is a coefficient of a real number not smaller than 1, and from said voltage signal, and for producing a disturbance estimation signal;

position detection means for producing a position error signal corresponding to a current position of said head from servo information previously recorded on said disk and detected by said head, and for outputting the
5 position error signal;

position control means for producing a position control signal corresponding to said position error signal, and for outputting the position control signal; and

correction means for receiving said position control
10 signal and said disturbance estimation signal, combining a signal obtained by multiplying said disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with said position control signal to produce said drive signal, and for outputting the drive
15 signal.

12. A disk storage apparatus according to claim 11, wherein

said coefficients k_1 and k_2 are set almost equal to each other.

20 13. A disk storage apparatus according to claim 11, wherein

said disturbance estimation means comprises:

comparison means for receiving the voltage signal detected by said voltage detection means;

first multiplication means for multiplying the signal,
which is obtained by multiplying said drive signal by k_1 ,
by a coefficient consisting of a first transfer function;

second multiplication means for multiplying an output
5 of said comparison means by a coefficient consisting of a
second transfer function;

first integration means for integrating the output of
said comparison means; and

second integration means for integrating a value
10 obtained by subtracting the added value of the output of
said second multiplication means and the output of said
first integration means from the output of said first
multiplication means, and

said comparison means compares said voltage signal
15 with the output of said second integration means, and
outputs a comparison result to said second multiplication
means and said first integration means.

14. A disk storage apparatus according to claim 11,
wherein

20 an estimation frequency of said disturbance estimation
signal produced by said disturbance estimation means is set
at a value higher than a control frequency band of said
position control means.

15. A disk storage apparatus comprising:

actuator means for positioning a head with respect to
a disk;

drive means for driving said actuator means in
accordance with an input drive signal;

5 drive coil voltage detection means for detecting a
drive coil voltage induced in driving said actuator means,
and for outputting a voltage signal;

position detection means for producing a position
error signal corresponding to a current position of said
10 head from servo information previously recorded on said
disk and detected by said head, and for outputting the
position error signal;

position control means for producing a position
control signal corresponding to said position error signal,
15 and for outputting the position control signal;

disturbance estimation means for estimating a
magnitude of a disturbance exerted on said head from a
signal obtained by multiplying said position control signal
by k_1 , where k_1 is a coefficient of a real number greater
20 than 1, and from said voltage signal, and for producing a
disturbance estimation signal; and

correction means for receiving said position control
signal and said disturbance estimation signal, combining a
signal obtained by multiplying said disturbance estimation

signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with said position control signal to produce said drive signal, and for outputting the drive signal.

5 16. A disk storage apparatus according to claim 15, wherein

 said coefficients k_1 and k_2 are set almost equal to each other.

 17. A disk storage apparatus according to claim 15,
10 wherein

 said disturbance estimation means comprises:

 comparison means for receiving the voltage signal detected by said voltage detection means;

 first multiplication means for multiplying the signal,
15 which is obtained by multiplying said position control signal by k_1 , by a coefficient consisting of a first transfer function;

 second multiplication means for multiplying an output of said comparison means by a coefficient consisting of a
20 second transfer function;

 first integration means for integrating the output of said comparison means; and

 second integration means for integrating a value obtained by subtracting the output of said second

multiplication means from the output of said first multiplication means, and

said comparison means compares said voltage signal with the output of said second integration means, and
5 outputs a comparison result to said second multiplication means and said first integration means.

18. A disk storage apparatus according to claim 15, wherein

an estimation frequency of said disturbance estimation
10 signal produced by said disturbance estimation means is set at a value higher than a control frequency band of said position control means.

19. A disk storage apparatus comprising:

actuator means for positioning a head with respect to
15 a disk;

drive means for driving said actuator means in accordance with an input drive signal;

drive coil voltage detection means for detecting a drive coil voltage induced in driving said actuator means,
20 and for outputting a voltage signal;

disturbance estimation means for estimating a magnitude of a disturbance exerted on said head from a signal obtained by multiplying said drive signal by k_1 , where k_1 is a coefficient of a real number greater than 1,

and from said voltage signal, and for producing a disturbance estimation signal;

position detection means for producing a position error signal corresponding to a current position of said head from servo information previously recorded on said disk and detected by said head, and for outputting the position error signal;

position control means for producing a position control signal corresponding to said position error signal, and for outputting the position control signal; and

correction means for receiving said position control signal and said disturbance estimation signal, cutting off a high frequency component of a signal, which is obtained by multiplying said disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, to produce a filter signal, combining said position control signal with said filter signal to produce said drive signal, and for outputting the drive signal.

20. A disk storage apparatus according to claim 19, wherein

said coefficients k_1 and k_2 are set almost equal to each other.

21. A disk storage apparatus according to claim 19, wherein

said disturbance estimation means comprises:

comparison means for receiving the voltage signal
detected by said voltage detection means;

first multiplication means for multiplying the signal,
5 which is obtained by multiplying said drive signal by k_1 ,
by a coefficient consisting of a first transfer function;

second multiplication means for multiplying an output
of said comparison means by a coefficient consisting of a
second transfer function;

10 first integration means for integrating the output of
said comparison means; and

second integration means for integrating a value
obtained by subtracting an added value of the output of
said second multiplication means and the output of said
15 first integration means from the output of said first
multiplication means, and

said comparison means compares said voltage signal
with the output of said second integration means, and
outputs a comparison result to said second multiplication
20 means and said first integration means.

22. A disk storage apparatus according to claim 19,
wherein

an estimation frequency of said disturbance estimation
signal produced by said disturbance estimation means is set

at a value higher than a control frequency band of said position control means.

23. A disk storage apparatus according to claim 19, wherein

5 a cut-off frequency of the filter signal of said correction means is set at a value smaller than a control frequency band of said position control means.

24. A disk storage apparatus comprising:

actuator means for positioning a head with respect to
10 a disk;

drive means for driving said actuator means in accordance with an input drive signal;

drive coil voltage detection means for detecting a drive coil voltage induced in driving said actuator means,
15 and for outputting a voltage signal;

position detection means for producing a position error signal corresponding to a current position of said head from servo information previously recorded on said disk and detected by said head, and for outputting the
20 position error signal;

position control means for producing a position control signal corresponding to said position error signal, and for outputting the position control signal;

disturbance estimation means for estimating a
magnitude of a disturbance exerted on said head from a
signal obtained by multiplying said position control signal
by k_1 , where k_1 is a coefficient of a real number greater
5 than 1, and from said voltage signal, and for producing a
disturbance estimation signal; and

correction means for receiving said position control
signal and said disturbance estimation signal, cutting off
a high frequency component of a signal, which is obtained
10 by multiplying said disturbance estimation signal by $1/k_2$,
where k_2 is a coefficient of a real number greater than 1,
to produce a filter signal, combining said position control
signal with said filter signal to produce said drive
signal, and for outputting the drive signal.

15 25. A disk storage apparatus according to claim 24,
wherein

said coefficients k_1 and k_2 are set almost equal to
each other.

20 26. A disk storage apparatus according to claim 24
wherein

said disturbance estimation means comprises:

comparison means for receiving the voltage signal
detected by said voltage detection means;

first multiplication means for multiplying the signal,
which is obtained by multiplying said position control
signal by k_1 , by a coefficient consisting of a first
transfer function;

5 second multiplication means for multiplying an output
of said comparison means by a coefficient consisting of a
second transfer function;

first integration means for integrating the output of
said comparison means; and

10 second integration means for integrating a value
obtained by subtracting the output of said second
multiplication means from the output of said first
multiplication means, and

 said comparison means compares said voltage signal
15 with the output of said second integration means, and
outputs a comparison result to said second multiplication
means and said first integration means.

27. A disk storage apparatus according to claim 24,
wherein

20 an estimation frequency of said disturbance estimation
signal produced by said disturbance estimation means is set
at a value higher than a control frequency band of said
position control means.

28. A disk storage apparatus according to claim 24,

wherein

a cut-off frequency of the filter signal of said correction means is set at a value lower than a control frequency band of said position control means.

5 29. A disk storage apparatus control method comprising the steps of:

producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by said head;

10 producing a position control signal corresponding to said position error signal; and

estimating a magnitude of a disturbance torque exerted on said head from a drive signal of actuator means for positioning said head and from a drive coil voltage signal induced in driving said actuator means, and producing a
15 disturbance estimation signal;

cutting off a high frequency component of said disturbance estimation signal, and producing a filter signal;

20 combining said position control signal with said filter signal, and producing said drive signal; and

positioning said head with respect to said disk by said drive signal.

30. A disk storage apparatus control method according to claim 29, wherein

an estimation frequency of said disturbance estimation signal is set at a value higher than a control frequency band of said position control signal.

31. A disk storage apparatus control method, comprising the steps of:

producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by said head;

producing a position control signal corresponding to said position error signal; and

estimating a magnitude of a disturbance torque exerted on said head from said position control signal and a drive coil voltage signal induced in driving said actuator means, and producing a disturbance estimation signal;

cutting off a high frequency component of said disturbance estimation signal, and producing a filter signal;

combining said position control signal with said filter signal, and producing said drive signal; and

position said head with respect to said disk by said drive signal.

32. A disk storage apparatus control method according

to claim 31, wherein

an estimation frequency of said disturbance estimation signal is set at a value higher than a control frequency band of said position control signal.

5 33. A disk storage apparatus control method, comprising the steps of:

producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by said head;

10 producing a position control signal corresponding to said position error signal; and

estimating a magnitude of a disturbance exerted on said head from a signal obtained by multiplying a drive signal of actuator means for positioning said head by k_1 ,
15 where k_1 is a coefficient of a real number not smaller than 1, and from a drive coil voltage signal induced in driving said actuator means, and producing a disturbance estimation signal;

combining a signal obtained by multiplying said
20 disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with said position control signal, and producing said drive signal; and

positioning said head with respect to said disk by
said drive signal.

34. A disk storage apparatus control method according
to claim 33, wherein

5 said coefficients k_1 and k_2 are set almost equal to
each other.

35. A disk storage apparatus control method according
to claim 33, wherein

an estimation frequency of said disturbance estimation
10 signal is set at a value higher than a control frequency
band of said position control signal.

36. A disk storage apparatus control method,
comprising the steps of:

producing a position error signal corresponding to a
15 current position of a head from servo information
previously recorded on a disk and detected by said head;

producing a position control signal corresponding to
said position error signal;

estimating a magnitude of a disturbance exerted on
20 said head from a signal obtained by multiplying said
position control signal by k_1 , where k_1 is a coefficient of
a real number greater than 1, and from a drive coil voltage
signal induced in driving actuator means, and producing a
disturbance estimation signal;

combining a signal obtained by multiplying said disturbance estimation signal by $1/k_2$, where k_2 is a coefficient of a real number greater than 1, with said position control signal, and producing said drive signal;

5 and

positioning said head with respect to said disk by said drive signal.

37. A disk storage apparatus control method according to claim 36, wherein

10 said coefficients k_1 and k_2 are set almost equal to each other.

38. A disk storage apparatus control method according to claim 36 wherein

15 an estimation frequency of said disturbance estimation signal is set at a value higher than a control frequency band of said position control signal.

39. A disk storage apparatus control method, comprising the steps of:

20 producing a position error signal corresponding to a current position of a head from servo information previously recorded on a disk and detected by said head;

producing a position control signal corresponding to said position error signal; and

estimating a magnitude of a disturbance exerted on
said head from a signal obtained by multiplying a drive
signal of actuator means for positioning said head by k_1 ,
where k_1 is a coefficient of a real number greater than 1,
5 and from a drive coil voltage signal induced in driving
said actuator means, and producing a disturbance estimation
signal;

cutting off a high frequency component of a signal,
which is obtained by multiplying said disturbance
10 estimation signal by $1/k_2$, where k_2 is a coefficient of a
real number greater than 1, and producing a filter signal;

combining said position control signal with said
filter signal, and producing said drive signal; and

positioning said head with respect to said disk by
15 said drive signal.

40. A disk storage apparatus control method according
to claim 39, wherein

said coefficients k_1 and k_2 are almost equal to each
other.

20 41. A disk storage apparatus control method according
to claim 39, wherein

an estimation frequency of said disturbance estimation
signal is set at a value higher than a control frequency
band of said position control signal.

42. A disk storage apparatus control method,
comprising the steps of:

- producing a position error signal corresponding to a
current position of a head from servo information
- 5 previously recorded on a disk and detected by said head;
producing a position control signal corresponding to
said position error signal; and
- estimating a magnitude of a disturbance exerted on
said head from a signal obtained by multiplying said
- 10 position control signal by k_1 , where k_1 is a coefficient of
a real number greater than 1, and from a drive coil voltage
signal induced in driving actuator means, and producing a
disturbance estimation signal;
- cutting off a high frequency component of a signal,
- 15 which is obtained by multiplying said disturbance
estimation signal by $1/k_2$, where k_2 is a coefficient of a
real number greater than 1, and producing a filter signal;
- combining said position control signal with said
filter signal, and producing said drive signal; and
- 20 position said head with respect to said disk by said
drive signal.

43. A disk storage apparatus control method according
to claim 42, wherein

said coefficients k_1 and k_2 are set almost equal to each other.

44. A disk storage apparatus control method according to claim 42, wherein

5 an estimation frequency of said disturbance estimation signal is set at a value higher than a control frequency band of said position control signal.