



## PID-PSO DC MOTOR POSITION CONTROLLER DESIGN FOR ANKLE REHABILITATION SYSTEM



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**Faculty of Electronic and Computer Engineering**



**PID-PSO DC MOTOR POSITION CONTROLLER DESIGN FOR  
ANKLE REHABILITATION SYSTEM**

**Muhammad Azizul Raziq Bin Azizi**

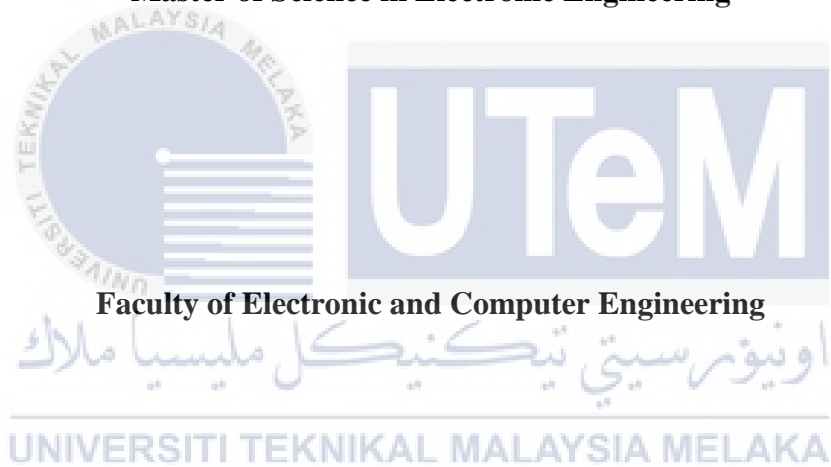
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**PID-PSO DC MOTOR POSITION CONTROLLER DESIGN FOR ANKLE  
REHABILITATION SYSTEM**

**MUHAMMAD AZIZUL RAZIQ BIN AZIZI**

**A thesis submitted  
in fulfillment of the requirements for the degree of  
Master of Science in Electronic Engineering**



**UNIVERSITI TEKNIKAL MALAYSIA MELAKA**

**2023**

## DECLARATION

I declare that this thesis entitled “PID-PSO DC Motor Position Controller Design For Ankle Rehabilitation System” is the result of my own research except as cited in the references. The thesis has not been accepted for any degree and is not concurrently submitted in the candidature of any other degree.

Signature

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Muhammad Azizul Raziq Bin Azizi

Date


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12/03/2023



## APPROVAL

I hereby declare that I have read this thesis, and in my opinion, this thesis is sufficient in terms of scope and quality for the award Master of Science in Electronic Engineering.

Signature : 

Supervisor Name : Dr. Khairuddin Bin Osman

Date : 12/03/2023



## DEDICATION

This thesis is dedicated to my beloved family, especially my father and mother who unconditionally supports and prays for my success. Special thanks to my supervisors Dr. Khairuddin Bin Osman and En. Anuar Bin Jaafar who has been guiding me from the beginning of this journey as well as Nur Khairunisha Kamel Binti Muhammad Kamel, Mohamad Yusry Lee Bin Ikhwan Lee and Amierul Syazrul Azril Bin Azman for the assistance and encouragement.



## ABSTRACT

In rehabilitation system application, precise output responses are important for position control on the mechanism's joint to avoid injury that occurs during physiotherapy. Hence, position control of DC motors has attracted considerable research with applied control system algorithms. This research aims to determine the mathematical modeling gain of the third-order transfer function for the DC motor that represents the features parameter of the Ankle Rehabilitation System. The transfer function is a model in Matlab software to validate the performance of the control system through simulation compared with real-time experiments. Next, the control algorithms are proposed to design and implement the Proportional-Integral-Derivative (PID) with Particle Swarm Optimization (PSO) controller technique for optimal Proportional ( $K_p$ ), Integral ( $K_i$ ) and Derivative ( $K_d$ ) gains. The control algorithms also aim to be analyzed using an incremental rotary encoder sensor device as closed-loop feedback for dorsiflexion and plantarflexion movement. This rotary encoder sensor device converts rotary motion into electrical signals or pulse signals to count per revolution of the gearbox output shaft. The H-Bridge module is used for bi-directional motor control with pulse-width modulation (PWM) from the Arduino microcontroller. The control pulse-width modulation is calculated and realized by tuning the value of Proportional ( $K_p$ ), Integral ( $K_i$ ) and Derivative ( $K_d$ ) with soft computing optimization techniques PSO controller. This proposed approach to develop optimal controller tuning parameters for proper computational performances position control efficiency and stable convergence characteristics. The simulation result of the PID-PSO controller with variables  $K_p= 6.542$ ,  $K_i= 0.103$  and  $K_d= 0.255$  provide good performance with the rise time ( $T_R$ ) is 0.0659sec, settling time ( $T_s$ ) is 0.1183sec and maintain the steady-state error with zero overshoot. This gain tuning of  $K_p$ ,  $K_i$  and  $K_d$  from the simulation was also implemented in real-time hardware for validation producing effectiveness for the controller to improve the Ankle Rehabilitation System position control analysis. The statistical trajectory tracking error is evaluated using mean square error (MSE) and root mean square error (RMSE) achieving a small value. The percentage improvement for simulation from PID controller to PID-PSO shows the MSE made is almost 91% while the RMSE is 71%. The real-time experiment performance also have high percentage improvement with MSE is 97% and RMSE is 84%. It concludes that the PID-PSO controller effectiveness control strategies of DC motor can accurately track the sinusoidal setpoint rotational angle movement of the Ankle Rehabilitation System.

# **REKA BENTUK PENGAWAL KEDUDUKAN MOTOR DC PID-PSO UNTUK SISTEM PEMULIHAN PERGELANGAN KAKI**

## **ABSTRAK**

*Dalam aplikasi sistem rehabilitasi, tindak balas yang tepat adalah penting untuk kawalan kedudukan pada sendi mekanisme bagi mengelakkan kecederaan yang berlaku semasa fisioterapi. Oleh itu, kawalan kedudukan motor DC telah menarik banyak penyelidikan dengan penggunaan sistem algoritma kawalan. Penyelidikan ini bertujuan untuk menentukan pendapatan pemodelan matematik untuk fungsi pemindahan tertib ketiga bagi motor DC yang mewakili ciri parameter Sistem Pemulihan Buku lali. Fungsi pemindahan adalah model dalam perisian Matlab untuk mengesahkan prestasi sistem kawalan melalui simulasi berbanding dengan eksperimen masa nyata. Seterusnya, algoritma kawalan dicadangkan untuk mereka bentuk dan melaksanakan Berkadaran-Integral-Derivatif (PID) dengan Pengoptimuman Kawanan Zarah (PSO) teknik pengawalan untuk mendapatkan Berkadaran ( $K_p$ ), Integral ( $K_i$ ) dan Derivatif ( $K_d$ ) yang optimum. Algoritma kawalan juga bertujuan untuk dianalisis menggunakan peranti penderia pengekod berputar tambahan sebagai sistem maklum balas litar tertutup untuk pergerakan dorsiflexion dan plantarflexion. Peranti pengesan pengekod berputar ini menukarkan gerakan berputar kepada isyarat elektrik atau isyarat nadi untuk mengira setiap putaran aci keluaran kotak gear. Modul H-Bridge digunakan untuk kawalan motor dwiarah dengan modulasi lebar nadi (PWM) daripada mikropengawal Arduino. Modulasi lebar nadi kawalan dikira dan direalisasikan dengan menala nilai Berkadaran ( $K_p$ ), Integral ( $K_i$ ) dan Derivatif ( $K_d$ ) dengan teknik komputer pengawal pengoptimuman PSO. Pendekatan yang dicadangkan ini bertujuan untuk membangunkan parameter penalaan pengawal yang optimum untuk prestasi pengiraan yang betul kecekapan kawalan kedudukan dan ciri penumpuan yang stabil. Hasil simulasi pengawal PID-PSO dengan pembolehubah  $K_p= 6.542$ ,  $K_i= 0.103$  dan  $K_d= 0.255$  memberikan prestasi yang baik dengan masa naik (TR) ialah 0.0659sec, masa menetap ( $T_s$ ) ialah 0.1183sec dan mengekalkan kadar ralat dalam keadaan tetap dengan terlebih tembakan sifar. Penalaan kadar  $K_p$ ,  $K_i$  dan  $K_d$  daripada simulasi ini juga dilaksanakan dalam peralatan masa nyata untuk pengesanan dan menghasilkan keberkesanan bagi pengawal untuk menambah baik analisis kawalan kedudukan Sistem Pemulihan Buku lali. Ralat penjejakan trajektori statistik dinilai menggunakan ralat min kuasa dua (MSE) dan ralat min kuasa dua punca (RMSE) yang mencapai nilai yang kecil. Peratusan penambahbaikan bagi simulasi daripada pengawal PID kepada PID-PSO menunjukkan MSE yang dibuat adalah hampir 91% manakala RMSE ialah 71%. Prestasi percubaan masa nyata juga mempunyai peningkatan peratusan yang tinggi dengan MSE ialah 97% dan RMSE ialah 84%. Ia menyimpulkan bahawa keberkesanan pengawal PID-PSO strategi kawalan untuk motor DC boleh menjejaki dengan tepat titik tetapan sinusoidal pergerakan sudut putaran Sistem Pemulihan Buku lali.*



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## TABLE OF CONTENTS

	<b>PAGE</b>
<b>DECLARATION</b>	
<b>APPROVAL</b>	
<b>DEDICATION</b>	
<b>ABSTRACT</b>	<b>i</b>
<b>ABSTRAK</b>	<b>ii</b>
<b>ACKNOWLEDGEMENTS</b>	<b>iii</b>
<b>TABLE OF CONTENTS</b>	<b>iv</b>
<b>LIST OF TABLES</b>	<b>vi</b>
<b>LIST OF FIGURES</b>	<b>ix</b>
<b>LIST OF SYMBOLS AND ABBREVIATIONS</b>	<b>xv</b>
<b>LIST OF PUBLICATIONS</b>	<b>xvi</b>
<b>CHAPTER 1 INTRODUCTION</b>	<b>1</b>
1.1 Research Background	1
1.2 Problem Statement	4
1.3 Motivation	6
1.4 Research Objective	7
1.5 Scope of Research	7
1.6 Methodology	8
1.7 Contribution of Research	9
1.8 Thesis Outline	11
<b>CHAPTER 2 LITERATURE REVIEW</b>	<b>13</b>
2.1 Background of Sprain Ankle	13
2.1.1 Medical View Sprain Ankle	13
2.1.2 Cause of Sprain Ankle	15
2.1.3 Treatment of Sprain Ankle	15
2.2 Robotic Technology Rehabilitation	17
2.3 Controller Design of Position Angle Control for Ankle Rehabilitation System	19
2.3.1 Proportional-Integral-Derivative (PID) Controller	20
2.4 Optimization Algorithms	23
2.4.1 Particle Swarm Optimization Technique	25
2.5 Previous Studies	29
2.5.1 Research Control for Ankle Joint Rehabilitation Device	29

2.5.2	Auditory Biofeedback on Tracking Task For Ankle Joint	32
2.5.3	Mechanism Design and ADAMS-MATLAB-Simulation of a Novel Ankle Rehabilitation Robot	35
2.6	Summary	38
<b>CHAPTER 3 METHODOLOGY</b>		<b>47</b>
3.1	Introduction	47
3.2	Mathematical Modeling for DC Motor on Ankle Rehabilitation System	49
3.2.1	Validation Stability of Transfer Function Using MATLAB	54
3.3	Developing Simulation and Experiment Setup on Ankle Rehabilitation System Using DC Motor	58
3.3.1	Validation Simulation Process on DC Motor Using MATLAB	58
3.3.2	Validation Real-Time Experiment on Ankle Rehabilitation System	69
3.4	Determination Real-Time Data Process for Ankle Rehabilitation System	78
3.5	Summary	82
<b>CHAPTER 4 RESULTS AND DISCUSSION</b>		<b>84</b>
4.1	Introduction	84
4.2	Evaluation of the Simulation on Ankle Rehabilitation System for Open-Loop System Response	85
4.3	Evaluation of the Simulation and Experiment Setup on Ankle Rehabilitation System for Closed Loop System Response	86
4.3.1	Analysis Simulation and Experiment Without Controller for Ankle Rehabilitation System	86
4.3.2	Analysis Simulation and Experiment With PID Controller for Ankle Rehabilitation System	103
4.3.3	Analysis Simulation and Experiment With PID-PSO Controller For Ankle	120
4.3.4	Analysis and Comparison For Simulation and Real-Time Experiment	137
4.4	Summary of Chapter 4	149
<b>CHAPTER 5 CONCLUSION AND RECOMMENDATIONS</b>		<b>150</b>
5.1	Conclusion	150
5.2	Research Impact	151
5.3	Recommendations	152
<b>REFERENCES</b>		<b>154</b>

## LIST OF TABLES

TABLE	TITLE	PAGE
2.1	Ankle Range limitation data	19
2.2	Effect of the responses towards the parameter of the system	22
2.3	Literature review study for this research	41
3.1	Symbol/abbreviation meaning	50
3.2	DC motor parameter value	54
4.1	Observation value for 50° target position without controller	89
4.2	Sine response between position target and simulation results 50° without using a controller	90
4.3	Sine response between position target and real-time results of 50° without using a controller	92
4.4	Observation value for 60° target position without controller	94
4.5	Sine response between position target and simulation results 60° without using a controller	95
4.6	Sine response between position target and real-time results of 60° without using a controller	97
4.7	Observation value for 70° target position without controller	99
4.8	Sine response between position target and simulation results	101
4.9	Sine response between position target and real-time results of 70° without using a controller	102
4.10	Observation value for 50° target position with PID controller	105
4.11	Sine response between position target and simulation results	107

4.12	Sine response between position target and real-time results of 50° using PID controller	108
4.13	Observation value for 60° target position with PID controller	111
4.14	Sine response between position target and simulation results	112
4.15	Sine response between position target and real-time results of 60° using PID controller	114
4.16	Observation value for 70° target position with PID controller	116
4.17	Sine response between position target and simulation results	118
4.18	Sine response between position target and real-time results of 70° using PID controller	119
4.19	Calculated parameters variable value by PSO algorithms	121
4.20	Observation value for 50° target position with PID-PSO controller	123
4.21	Sine response between position target and simulation results	124
4.22	Sine response between position target and real-time results of 50° using PID-PSO controller	126
4.23	Observation value for 60° target position with PID-PSO controller	128
4.24	Sine response between position target and simulation results	129
4.25	Sine response between position target and real-time results of 60° using PID-PSO controller	131
4.26	Observation value for 70° target position with PID-PSO controller	133
4.27	Sine response between position target and simulation results	135
4.28	Sine response between position target and real-time results of 70° using PID-PSO controller	136
4.29	Comparative simulation analysis of various tuning methods	138

4.30	Comparative real-time analysis of various tuning methods	140
4.31	The statistical trajectory tracking performance of ankle rehabilitation system between the proposed method	148



## LIST OF FIGURES

FIGURE	TITLE	PAGE
1.1	Simplified research K-chart with methodology process	9
2.1	The model of an ankle-foot structure and ligament stretch structure	14
2.2	Example exercise with an elastic band (a); roller foams (b); and wobble boards (c)	17
2.3	The system configuration	20
2.4	The PID controller in a closed-loop system	21
2.5	Classification of optimization algorithms	24
2.6	Swarm of an eagle searching for rat	26
2.7	The illustration movement of particles for optimization technique	27
2.8	The rehabilitation ankle device	30
2.9	Block diagram of closed-loop control of PD controller in Matlab Simulink	30
2.10	Result of the simulation of the PD controller response	31
2.11	The trajectory tracking error pattern for sinusoidal response	32
2.12	The experimental setup and instrumentation	33
2.13	A plot of single tracking movement	33
2.14	Visual biofeedback vs auditory biofeedback experimental result for tracking task	34
2.15	Average and standard deviation of the mean absolute error of ankle angle positioning of tracking task with VBF or ABF	35
2.16	The prototype of the ankle rehabilitation robot	36
2.17	Construction Closed-Loop DC motor with PID controller	37

2.18	The curve of position accuracy experiment	38
3.1	Research methodology flow chart	47
3.2	Equivalent circuit of an armature-controlled DC motor	50
3.3	Location of poles and zero corresponding transient response	55
3.4	Matlab command to obtain the equation of motor system transfer function	56
3.5	Output transfer function equation of Open-Loop for Ankle Rehabilitation System	56
3.6	Number of zero and poles result to identify the stability of the transfer function	57
3.7	Identify the stability of transfer function using the position of (a) zero and poles map (b) as root locus plot graph	58
3.8	Overall simulation process of DC motor for Ankle Rehabilitation System	59
3.9	Simulink model of the block diagram for DC motor without controller	61
3.10	Simulink model of the block diagram for DC motor implemented PID controller	62
3.11	The PID controller algorithms block tuning parameters system	63
3.12	The tuning block response from an initial condition of block response to a better-tuned response	64
3.13	The block diagram of the PID-PSO controller	65
3.14	Parameter of PID to optimal in Matlab	65
3.15	Formula of particle position and velocity to generate initial population randomly	66
3.16	Fitness function used to optimize the overshoot in response	67
3.17	The personal best agent code used to update	67



3.18	The global best code used to update	67
3.19	The equation to update particle velocity in Matlab	68
3.20	The equation used to update particle position in Matlab	68
3.21	Overall hardware experiment validation process	70
3.22	Overall DC motor position control components of Ankle Rehabilitation System	71
3.23	Ankle Rehabilitation System prototype	72
3.24	Circuit design of Ankle Rehabilitation System	72
3.25	Arduino (UNO) Microcontroller	73
3.26	The Arduino workspace for coding	74
3.27	The function of the rotary encoder	74
3.28	The program code to set the direction and speed of the motor	75
3.29	The equation to define the error value in program code	76
3.30	The equation for the integral term in program code	76
3.31	Equation changes from current time into microseconds and defines the delta t	76
3.32	The equation for the derivative term in program code	77
3.33	The PID control algorithms in programming code	77
3.34	Flowchart of collective real-time data process	79
3.35	Arduino program code workspace to run	80
3.36	Tera Term connection through Serial Port	81
3.37	The collect data analysis from the microcontroller to Tera Term Software (a) and Microsoft Excel (b)	81
3.38	The command on the workspace to export data in the Excel sheet file	82
4.1	Open-loop system block diagram	85

4.2	Output response for open loop system	85
4.3	Closed-loop system configuration	87
4.4	Simulation response without controller implementation of target 50°	88
4.5	Real-time step response without controller implementation of target 50°	88
4.6	The average best step response from the overall real-time result for angle 50°	89
4.7	Simulation sine response without controller implementation of target 50°	91
4.8	Real-time sine response without controller implementation of target 50°	92
4.9	Simulation step response without controller implementation of target 60°	93
4.10	Real-time step response without controller implementation of target 60°	93
4.11	The average best response from the overall real-time result for angle 60°	94
4.12	Simulation sine response without controller implementation of target 60°	96
4.13	Real-time sine response without controller implementation of target 60°	97
4.14	Simulation step response without controller implementation of target 70°	98
4.15	Real-time step response without controller implementation of target 70°	99
4.16	The average best response from the overall real-time result for angle 70°	100
4.17	Simulation sine response without controller implementation of target 70°	101
4.18	Real-time sine response without controller implementation of target 70°	103
4.19	Simulation step response with PID controller for target 50°	104
4.20	Real-time step response with PID controller for target 50°	105
4.21	The average best response of real-time result for input 50° with PID controller	106
4.22	Simulation sine response with PID controller for target 50°	107
4.23	Real-time sine response with PID controller for target 50°	109
4.24	Simulation step response with PID controller for target 60°	110
4.25	Real-time step response with PID controller for target 60°	110

4.26	The average best response of real-time result for input 60° with PID controller	111
4.27	Simulation sine response with PID controller for target 60°	113
4.28	Real-time sine response with PID controller for target 60°	114
4.29	Simulation step response with PID controller for target 70°	115
4.30	Real-time step response with PID controller for target 70°	116
4.31	The average best response of real-time result for input 70° with PID controller	117
4.32	Simulation sine response with PID controller for target 70°	118
4.33	Real-time sine response with PID controller for target 70°	120
4.34	Simulation step response with PID-PSO controller for target 50°	122
4.35	Real-time step response with PID-PSO controller for target 50°	122
4.36	The average best response of real-time result for input 50° with PID-PSO controller	123
4.37	Simulation sine response with PID-PSO controller for target 50°	125
4.38	Real-time step response with PID-PSO controller for target 50°	126
4.39	Simulation step response with PID-PSO controller for target 60°	127
4.40	Real-time step response with PID-PSO controller for target 60°	127
4.41	The average best response of real-time result for input 60° with PID-PSO controller	128
4.42	Simulation sine response with PID-PSO controller for target 60°	130
4.43	Real-time step response with PID-PSO controller for target 60°	131
4.44	Simulation step response with PIDPSO controller for target 70°	132
4.45	Real-time step response with PID-PSO controller for target 70°	133
4.46	The average best response of real-time result for input 70° with PID-PSO controller	134

4.47	Real-time step response with PID-PSO controller for target 70°	135
4.48	Simulation sine response with PID-PSO controller for target 70°	137
4.49	Comparison of the overall controller step responses for simulation 50°	139
4.50	Comparison of the overall controller step responses for simulation 60°	139
4.51	Comparison of the overall controller step responses for simulation 70°	140
4.52	Comparison of overall controller step responses for real-time experiment 50°	141
4.53	Comparison of overall controller step responses for real-time experiment 60°	142
4.54	Comparison of overall controller step responses for real-time experiment 70°	142
4.55	Comparison of overall controller sine responses for simulation experiment 50°	143
4.56	Comparison of overall controller sine responses for simulation experiment 60°	144
4.57	Comparison of overall controller sine responses for simulation experiment 70°	144
4.58	Comparison of overall controller sine response for real-time experiment 50°	145
4.59	Comparison of overall controller sine response for real-time experiment 60°	146
4.60	Comparison of overall controller sine response for real-time experiment 70°	146

## LIST OF SYMBOLS AND ABBREVIATIONS

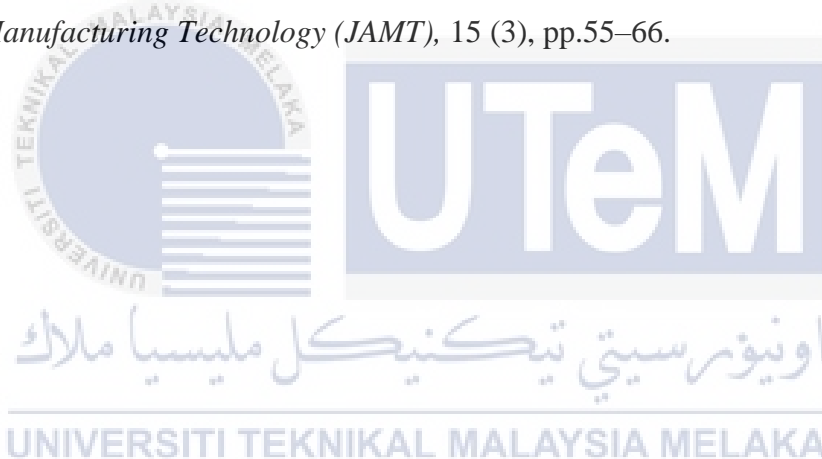
ABF	-	Auditory Biofeedback
AC	-	Alternating Current
ACO	-	Ant Colony Optimization
ATFL	-	Anterior Talofibular Ligament
ANN	-	Artificial Neural Network
CFL	-	Calcaneo Fibular Ligament
DC	-	Direct Current
FPGA	-	Field Programmable Gate Array
IDE	-	Integrated Development Environment
MRI	-	Magnetic Resonance Imaging
MAE	-	Mean Absolute Error
MHz	-	Mega Hertz
MSE	-	Mean Square Error
PSO	-	Particle Swarm Optimization
PID	-	Proportional-Integral Derivative
PWM	-	Pulse Width Modulation
PTFL	-	Posterior Talofibular Ligaments
$\%e_{ss}$	-	Percentage Steady-State Error
%OS	-	Percentage Overshoot
RMSE	-	Root Mean Square Error
$T_R$	-	Rise Time
$T_s$	-	Settling Time
Sec	-	Second
$t$	-	Time
VBF	-	Visual Biofeedback

## LIST OF PUBLICATIONS

### Indexed Journal

Azizi, M.A.R., Jaafar, A., and Osman, K., 2020. Performance analysis for sprain ankle rehabilitation system using gyro sensor. *International Journal of Advanced Science and Technology*, 29 (6), pp.860–872.

Azizi, M.A.R., Jaafar, A., Osman, K., and Suzumori, K., 2021. PID controller design for DC motor position analysis and application to ankle rehabilitation system. *Journal of Advanced Manufacturing Technology (JAMT)*, 15 (3), pp.55–66.



# CHAPTER 1

## INTRODUCTION

### 1.1 Research Background

Recently, the evolution of innovative robotic technology constantly developed in the robotic field, especially in the medical field (Qian and Bi, 2015; Guo et al., 2021). These new trends in the robotic field have drawn the attention of researchers conducting studies in terms of development for the rehabilitation robots application such as power-assist devices integrating sensors (Kawase et al., 2017). The invasion of robots application in medical industries helps to improve faster recovery for rehabilitation treatment control systems and provides power assistance with data acquisition (Gao et al., 2020). Rehabilitation is a mainstay treatment where robots can give a significant impact on patients treatment who suffer from injuries (Gassert and Dietz, 2018). Several studies revealed that a sprained ankle injury can happen to almost everybody especially active people because turned unexpected movement directions (Roos et al., 2017). This injury causes damage severity to the ankle ligament which can stretch or tear either partially or fully in the worst situation (Delahunt et al., 2018). The rehabilitation application system is created to perform therapeutic exercises with repetitive movement and measure mechanical parameters objectively using sensors for ankle strength recovery (Atlihan et al., 2014).

The existing sprain ankle rehabilitation system consists of two types which are traditional manual rehabilitation and robotic technology rehabilitation. The traditional manual rehabilitation treatment approach mainly uses a simple device available at any physiotherapist outlet or clinical (Shi et al., 2021). Examples of primitive passive device or simple devices for manual rehabilitation therapists is elastic bands, roller foams and wobble boards. Unfortunately, these primitive passive devices or only can perform with the

patient's effort strength, restrict patient training time and lack of function to produce any data acquisition for patients resulting outcomes exercise (Saglia et al., 2019; Collins and Jackson, 2013). As compared to robotic rehabilitation is capable of providing more intensive training with more motivation, better quantitative feedback and improved functional outcomes for patients (Chen et al., 2013). It also could give moral motivation with interesting strategies for patients to involve in the training session and recover from ankle injuries.

Nowadays, electric motors actuator such as Direct Current (DC) motor is widely used in industry application constantly developed for robot manipulators, electric traction and the medical industry (Mohamed et al., 2020). Robotic rehabilitation system technology used for medical needs to be concerned with several mechatronic device elements in terms of actuator mechanism's joint, control system, mechanical design structure and safety (Khalid et al., 2015). In this research, the actuator mechanism's joint using a DC motor was chosen that can achieve speed control and position by varying the terminal voltage incorporated with an incremental encoder as the closed-loop feedback. The encoder pulse is counted when the disk is rotating while the rotary encoder consists of two output sensors to determine the steps each time the signal changes. However, there are uncertain and nonlinear characteristics that affect the robustness and stability of the system especially when there is load disturbance (Guermouche et al., 2015). Therefore, control system algorithms are applied in the DC motor application plant system for robust control of position and velocity. The angular position is determined by using a rotary encoder as the closed-loop feedback

Since 1940, the PID controller has been used for several decades in industries to process control system applications (Hassan et al., 2017). Traditionally, Proportional Integral Derivative (PID) algorithm controller is the most preferable controller because of