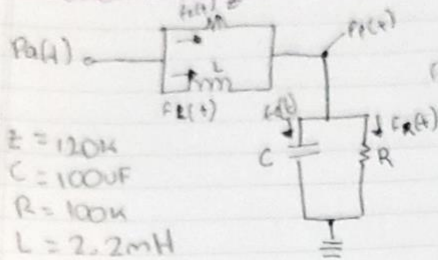


Problema 5.4 sistema de control

(Ejercicio Principal)

10/oct/25



$$F_a(t) = F_z(t) + F_L(t) = F_C(t) + F_R(t)$$

$$F_z(t) = \frac{P_a(t) - P_R(t)}{Z}$$

$$F_L(t) = \frac{C d P_R(t)}{dt}$$

$$F_L(t) = \frac{1}{L} \int [P_a(t) - P_R(t)] dt$$

$$F_R(t) = \frac{P_R(t)}{R}$$

Procedimiento algebraico

$$\frac{P_a(t)}{Z} - \frac{P_R(t)}{Z} + \frac{1}{L} \int P_a(t) - P_R(t) dt = \frac{C d P_R(t)}{dt} + \frac{P_R(t)}{R}$$

$$\frac{P_a(s)}{Z} - \frac{P_R(s)}{Z} + \frac{P_a(s) - P_R(s)}{Ls} = \frac{Cs P_R(s)}{dt} + \frac{P_R(s)}{R}$$

$$\left(\frac{1}{Z} + \frac{1}{Ls}\right) P_a(s) = \left(Cs + \frac{1}{R} + \frac{1}{Z} + \frac{1}{Ls}\right) P_R(s)$$

$$\frac{Ls + Z}{LZs} P_a(s) = \frac{(L^2 + LZs + RLs + RZ)}{RLZs} P_R(s)$$

$$\frac{P_R(s)}{P_a(s)} = \frac{Ls + Z}{LZs}$$

$$CLs^2 + (LZ + R)s + RZ$$

$$= \frac{(Ls + Z)(RLZs)}{(LZs)(CLs^2 + (LZ + R)s + RZ)}$$

record pause stop

jump

bookmark

0% jump to position 100%

playback speed

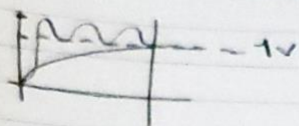
Práctica 5.4 sistema controlado br

10/10/25

- Error en estado estacionario

$$e(s) = \lim_{s \rightarrow 0} s P_o(s) \left[\frac{1 - P_r(s)}{P_o(s)} \right]$$

$$= \lim_{s \rightarrow 0} s + \frac{1}{s} \left[\frac{1 - R_L s + R_L}{CLR s^2 + (Lz + RL)s + R_L} \right] = 1 - R_L / R_L = 0 //$$



- Estabilidad en lazo abierto

$$z_{1,2} = \frac{-b \pm \sqrt{b^2 - 4ac}}{2a} \quad a = CLRz, \quad b = Lz + RL, \quad c = R_L$$

$$z_{1,2} = \frac{-(Lz + RL) \pm \sqrt{(Lz + RL)^2 - 4((CLRz)(R_L))}}{2} = \frac{(-) \pm (-)}{+}$$

El sistema tiene una respuesta estable porque $\text{Re}(z_{1,2}) < 0$

- Modelo de ecuaciones integro diferenciales de (t)

$$P_p(t) \left(\frac{1}{L} + \frac{1}{R} \right) = \frac{P_o(t)}{L} + \frac{1}{L} \int [P_o(t) - P_p(t)] dt - C_d \frac{dP_p(t)}{dt}$$

$$\therefore P_p(t) = \left(\frac{P_o(t)}{L} + \frac{1}{L} \int [P_o(t) - P_p(t)] dt - C_d \frac{dP_p(t)}{dt} \right) \cdot \frac{zR}{z+R}$$