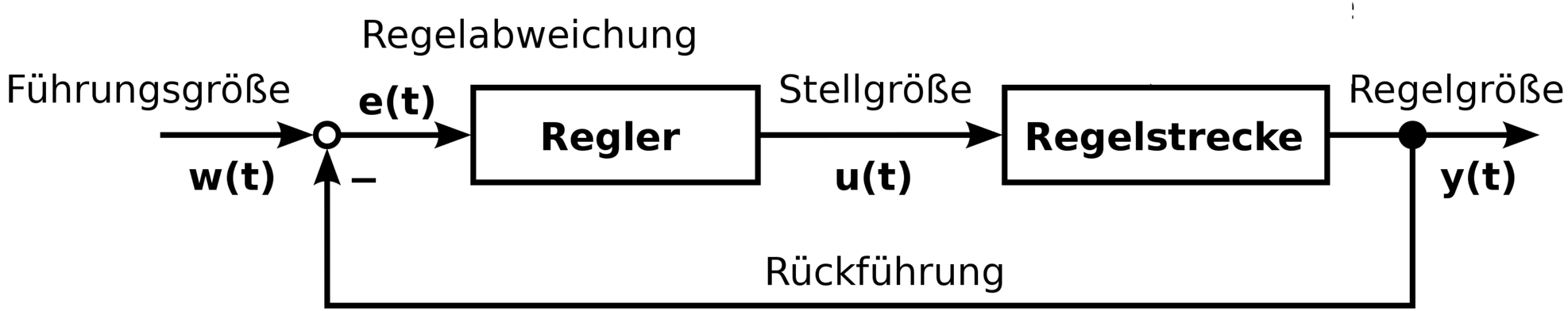
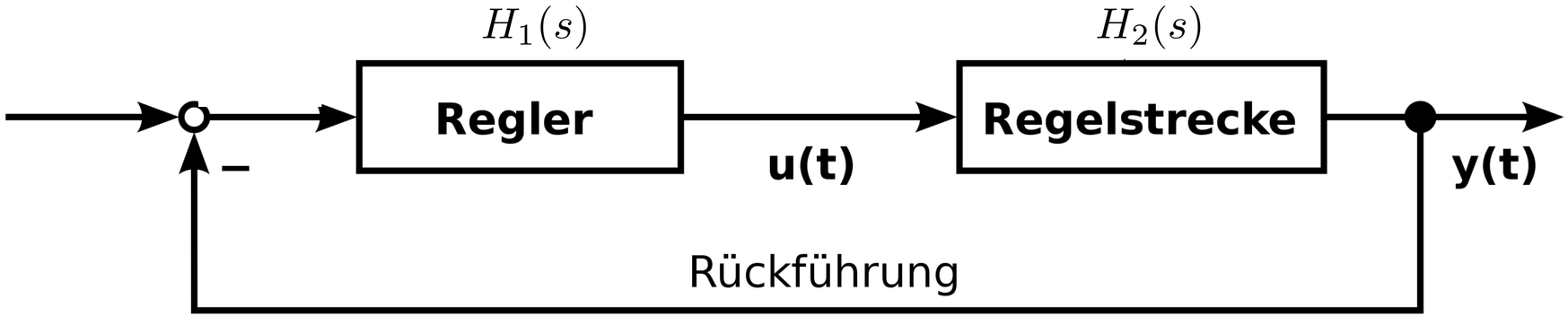
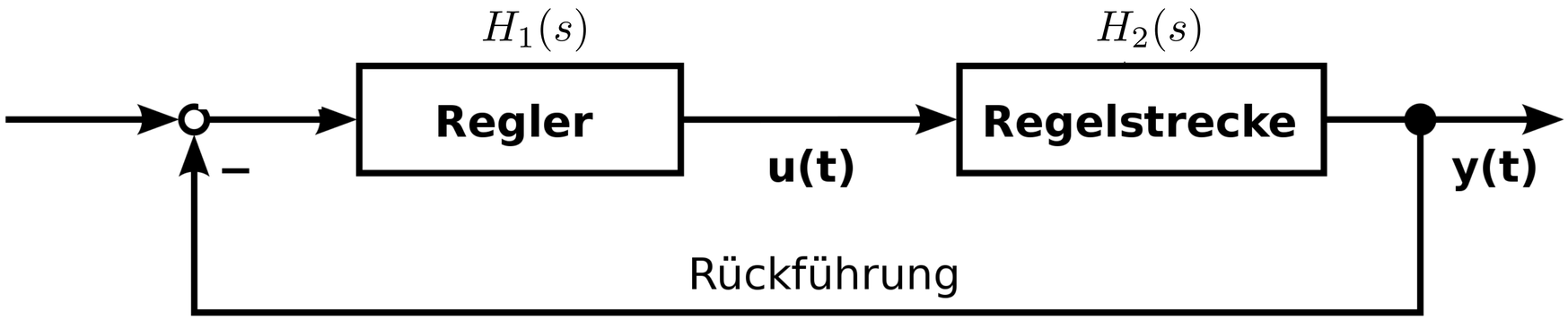
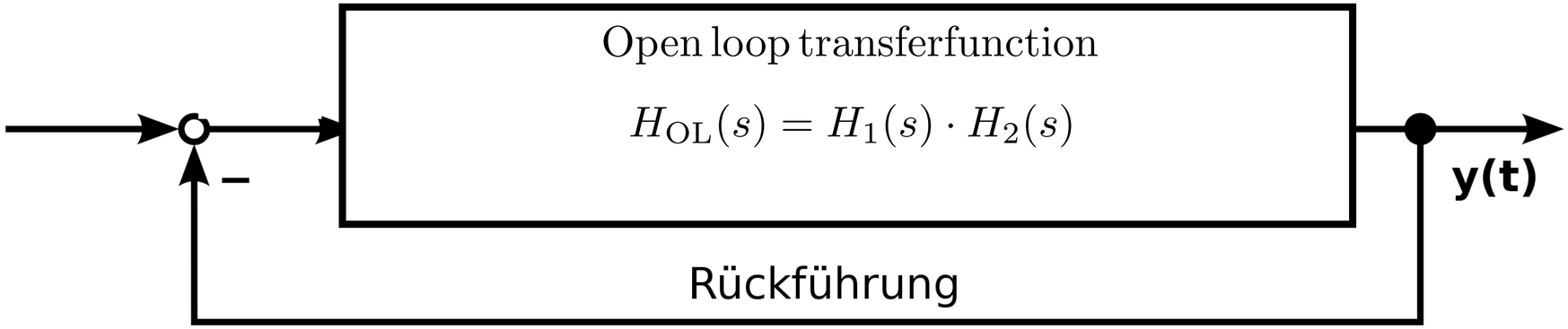
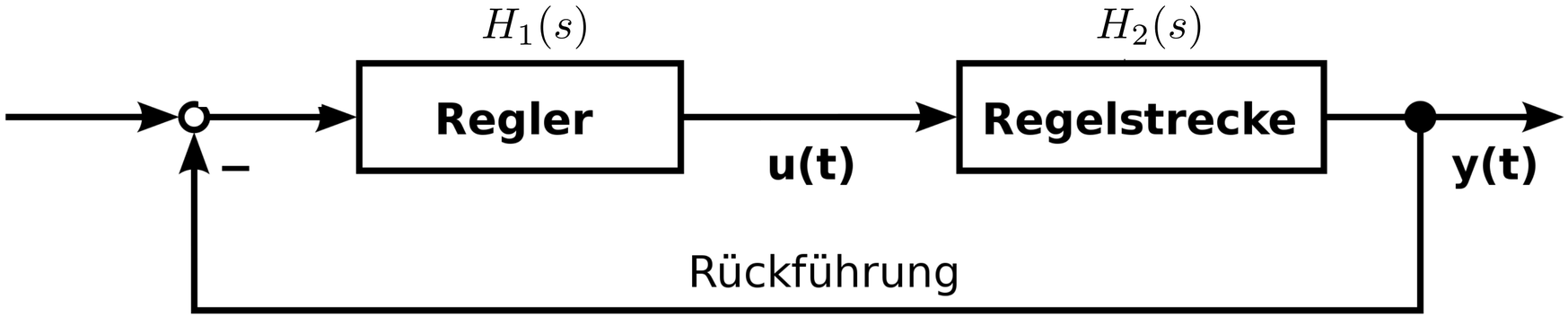
A Closed Loop Control System

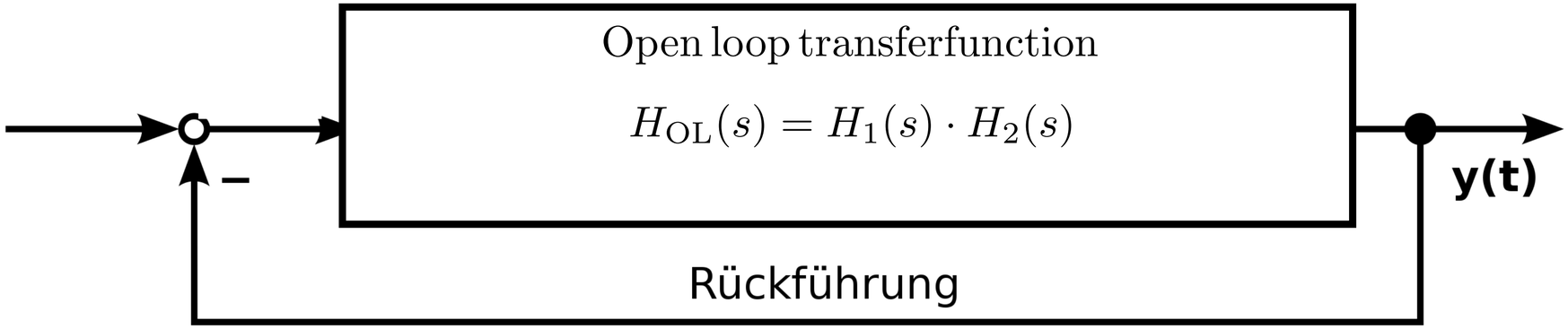


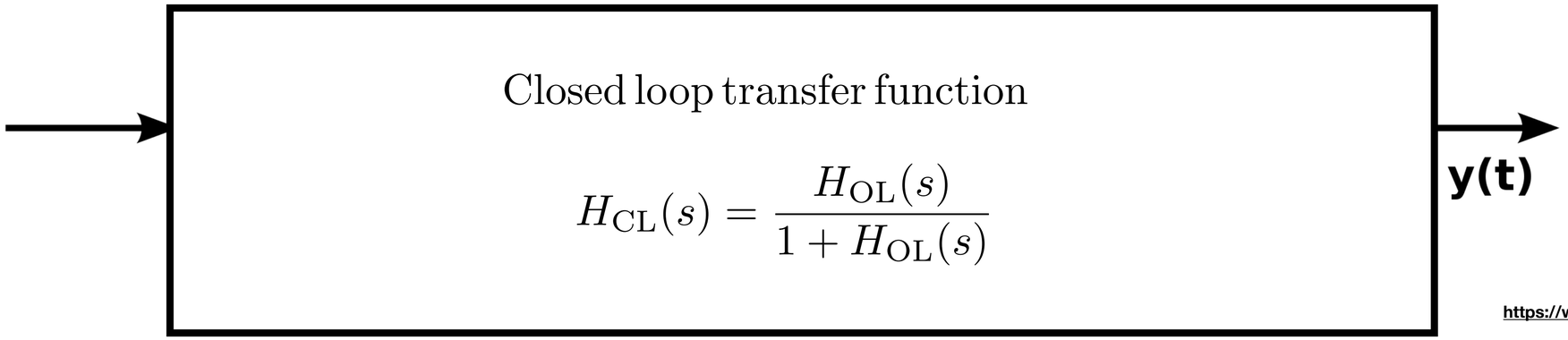

$H_1(s)$
$H_2(s)$
Regler
Regelstrecke
u(t)
y(t)
−
Rückführung


$H_1(s)$
$H_2(s)$
Regler
Regelstrecke
u(t)
y(t)
−
Rückführung

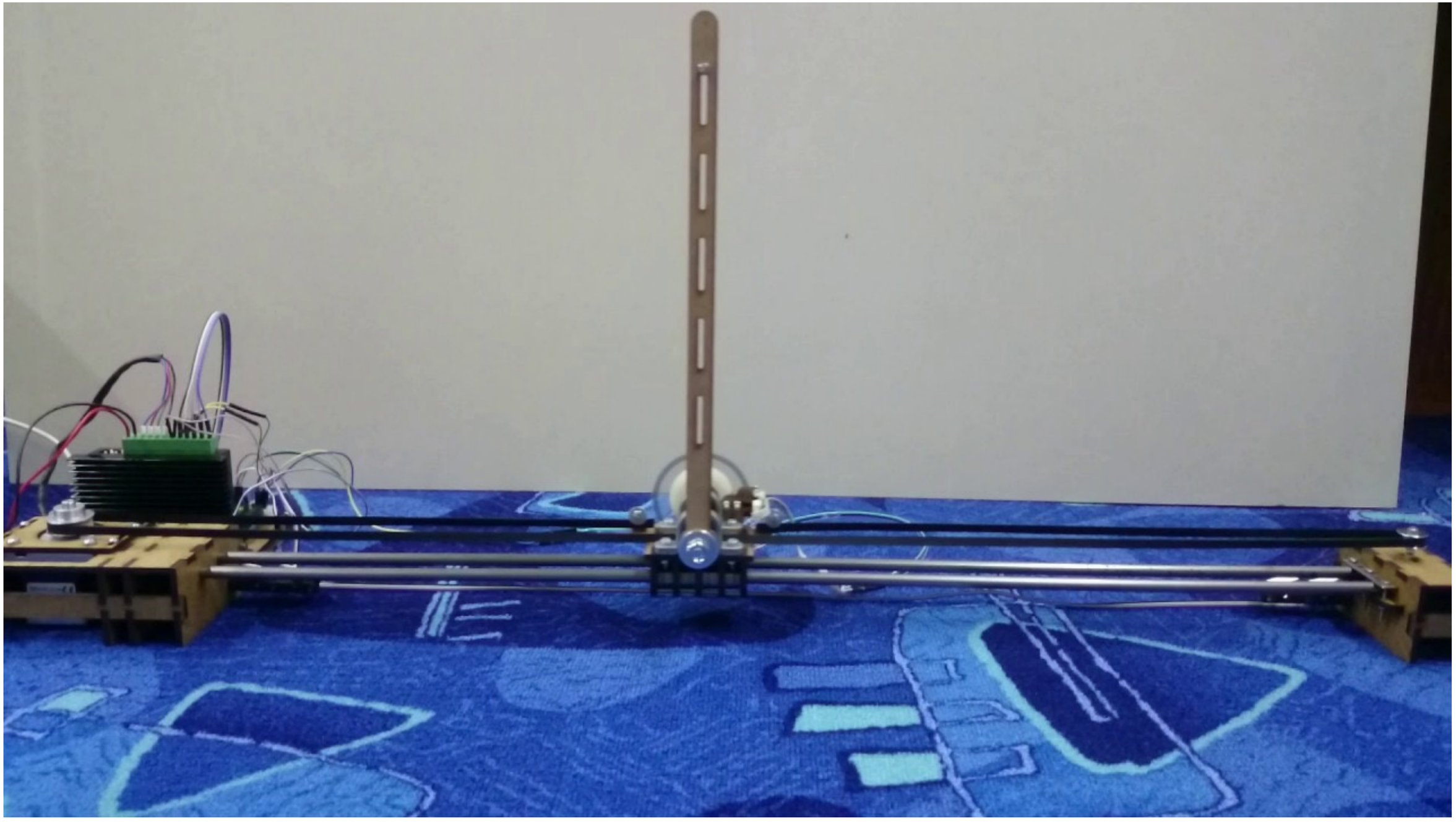

Open loop transferfunction
$H_{\mathrm{OL}}(s) = H_1(s) \cdot H_2(s)$
y(t)
−
Rückführung





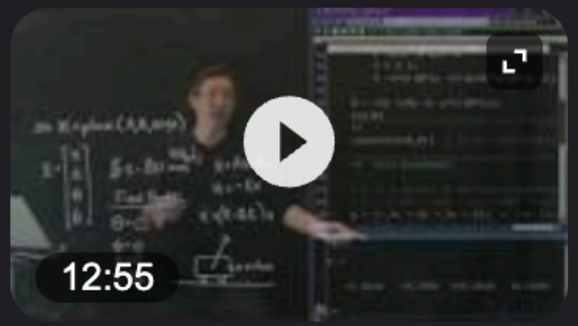


For derivation check
https://www.youtube.com/watch?v=GBv5iiKA6gw



www.youtube.com › watch

Pole Placement for the Inverted Pendulum on a Cart [Control ...



Here we use the 'place' command in Matlab to design full-state feedback gains to specify the eigenvalues of the closed-loop…

YouTube · Steve Brunton · 29.01.2017

Steve Brunton, University of Washington: https://www.youtube.com/@Eigensteve