#### 1

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Abstract—This manual is an introduction to control systems based on GATE problems.Links to sample Python codes are available in the text.

Download python codes using svn co https://github.com/gadepall/school/trunk/control/codes

### 1 STABILITY

# 1.1 Second order System

### 2 ROUTH HURWITZ CRITERION

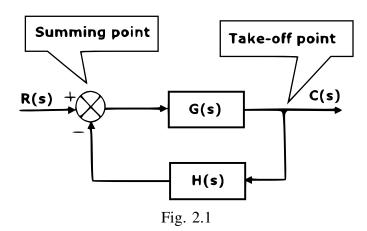
2.1. consider a standard negative feedback transfer function configuration with

$$G(s) = \frac{1}{(s+1)(s+2)}$$
 (2.1.1)

and

$$H(s) = \frac{s + \alpha}{s} \tag{2.1.2}$$

the closed loop system to have poles on the imaginary axis, the value of  $\alpha$  should be equal to **Solution:** The transfer function for negative



feedback is given by

$$\frac{Y(s)}{X(s)} = \frac{G(s)}{1 + G(s)H(s)}$$
(2.1.3)

where

$$G(s) = \frac{1}{(s+1)(s+2)}, H(s) = \frac{s+\alpha}{s} \quad (2.1.4)$$

Characteristic equation is..,

$$1 + G(s)H(s) = 0$$
 (2.1.5)

$$=> 1 + \left[\frac{1}{(s+1)(s+2)}\right] \left[\frac{s+\alpha}{s}\right] = 0 \quad (2.1.6)$$

$$=> s^3 + 3s^2 + 3s + \alpha = 0$$
 (2.1.7)

For poles to lie on imaginary axis any one entire row of hurwitz matrix should be zero. Constructing the routh array for the characteristic equation obtained in equation

$$s^3 + 3s^2 + 3s + \alpha = 0 \tag{2.1.8}$$

$$\begin{vmatrix} s^3 \\ s^2 \end{vmatrix} \begin{vmatrix} 1 & 3 \\ 3 & \alpha \end{vmatrix} \tag{2.1.9}$$

$$\begin{vmatrix} s^{3} \\ s^{2} \\ s^{1} \end{vmatrix} \begin{vmatrix} 1 & 3 \\ 3 & \alpha \\ \frac{9-\alpha}{3} & 0 \end{vmatrix}$$
 (2.1.10)

$$\begin{vmatrix} s^{3} \\ s^{2} \\ s^{1} \\ s^{0} \end{vmatrix} \begin{vmatrix} 1 & 3 \\ 3 & \alpha \\ \frac{9-\alpha}{3} & 0 \\ \alpha & 0 \end{vmatrix}$$
 (2.1.11)

For poles on  $j\omega$  axis any one of the row should be zero.

$$\frac{9 - \alpha}{3} = 0 \ or \ \alpha = 0 \tag{2.1.12}$$

But when  $\alpha = 0$  poles does not lie on the imaginary axis

$$9 - \alpha = 0 \tag{2.1.13}$$

$$\alpha = 9 \tag{2.1.14}$$

put  $\alpha$  in the characteristic equation we get

$$s^3 + 3s^2 + 3s + 9 = 0 (2.1.15)$$

poles are

$$s = -3, -j\sqrt{3}, j\sqrt{3}$$
 (2.1.16)

3 Compensators

4 NYQUIST PLOT