Computer Exercise 4  
EL2520 Control Theory and Practice

|  |  |
| --- | --- |
| Osqulda Osquldasdotter | Oscar Oscarsson |
| [x@kth.se](mailto:x@kth.se) | [y@kth.se](mailto:y@kth.se) |
| YYMMDD-NNNN | YYMMDD-NNNN |

# Minimum phase case

## Dynamic decoupling

The dynamic decoupling in exercise 3.2.1 is

Figure : Bode diagram of G(s) derived in exercise 3.2.1

Figure 2: Simulink plots from exercise 3.2.4

Is the controller good?

Are the output signals coupled?

## Glover-MacFarlane robust loop-shaping

Figure : Simulink plots from exercise 3.3.4

What are the similarities and differences compared to the nominal design?

# Non-minimum phase case

## Dynamic decoupling

The dynamic decoupling in exercise 3.2.1 is

Figure : Bode diagram of G(s) derived in exercise 3.2.1

Figure : Simulink plots from exercise 3.2.4

Is the controller good?

Are the output signals coupled?

## Glover-MacFarlane robust loop-shaping

Figure : Simulink plots from exercise 3.3.4

What are the similarities and differences compared to the nominal design?