clear clc

Controls Homework 11 Problem 1

```
Gs1 = zpk([],[0 -10 -15 -50],200);
X1 = evalfr(Gs1, -2.6 + 5.08j)
K1 = -1/X1
Gcll = minreal(Gsl*abs(K1) / (1 + Gsl*abs(K1)))
T = .05;
s1 = [roots([1 4.656 27.64])', roots([1 45.34 536.3])'];
z1 = \exp(s1*T);
Gz1p = zpk([],z1,1,T)
Gs1 = zpk([],s1,14823)
kz1 = evalfr(Gz1p, 1);
ks1 = evalfr(Gs1, 0);
k1 = ks1/kz1
Gz1 = zpk([0 \ 0], z1, k1, T);
Kz1 = zpk([0.8187 \ 0.6065],[1 \ 0.0834],34.7201,.1)
Kz1 = tf(Kz1)
step(Gcl1)
X1 =
  -0.0061 - 0.0000i
K1 =
   1.6361e+02 - 9.1505e-02i
Gc11 =
                    32721
  (s+49.52) (s+20.28) (s^2 + 5.204s + 32.58)
Continuous-time zero/pole/gain model.
Gz1p =
```

 $(z^2 - 0.6259z + 0.1036) (z^2 - 1.731z + 0.7923)$

Sample time: 0.05 seconds Discrete-time zero/pole/gain model.

Gs1 =

Continuous-time zero/pole/gain model.

k1 =

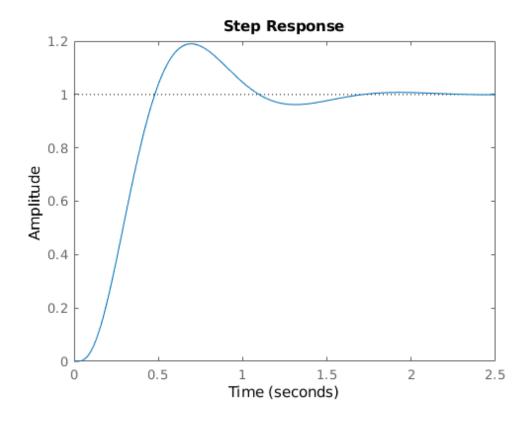
0.0293

Kz1 =

Sample time: 0.1 seconds Discrete-time zero/pole/gain model.

Kz1 =

Sample time: 0.1 seconds Discrete-time transfer function.



Controls Homework 11 Problem 2

```
T2 = .250;
s2 = [roots([1 4.656 27.64])', roots([1 45.34 536.3])'];
z2 = exp(s2*T2);

Gz2p = zpk([],z2,1,T2);
Gs2 = zpk([],s2,14823);
kz2 = evalfr(Gz2p, 1);
ks2 = evalfr(Gs2, 0);
k2 = ks2/kz2
Gz2 = zpk([0 0],z2,k2,T2)

Kz2 = zpk([0.2865 0.6065],[1 -0.7287],31.5021,.25)
Kz2 = tf(Kz2)

figure;
step(Gs2)
k2 =
```

Gz2 =

 $(z^2 - 0.002618z + 1.195e-05)$ $(z^2 - 0.4273z + 0.3122)$

Sample time: 0.25 seconds

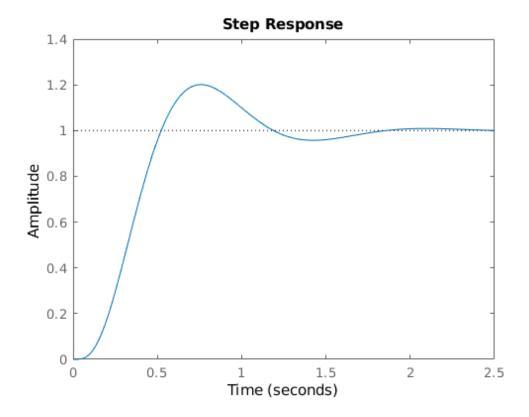
Discrete-time zero/pole/gain model.

Kz2 =

Sample time: 0.25 seconds Discrete-time zero/pole/gain model.

Kz2 =

Sample time: 0.25 seconds Discrete-time transfer function.



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