Computer Exercise 2
EL2520 Control Theory and Practice

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Minimum phase case
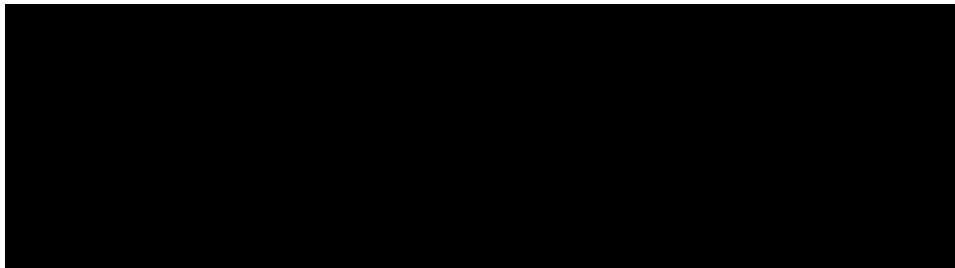
The controller is given by

$$F(s) = \dots$$

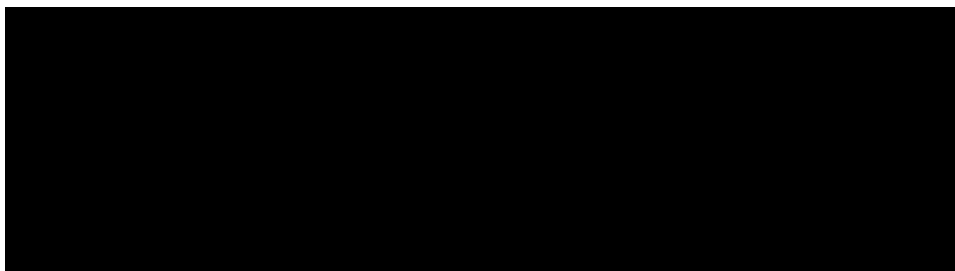Figure 1: Simulink plots from exercise 3.2.3

Figure 2: Bode diagram of the loop gain $L(s)$ from exercise 3.2.1

Is the controller good?

. . . .
. . . .

Are the output signals coupled?

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Non-minimum phase case
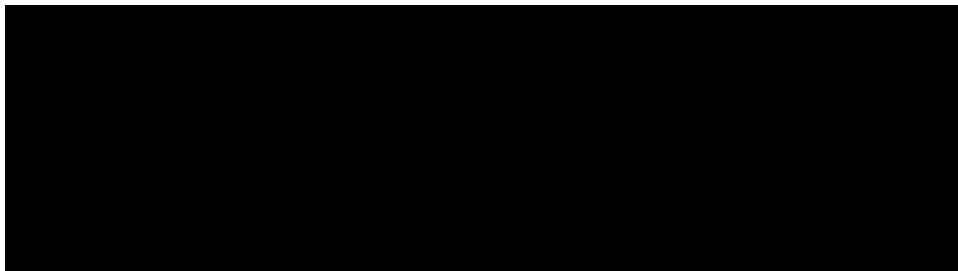
The controller is given by

$$F(s) = \ldots$$
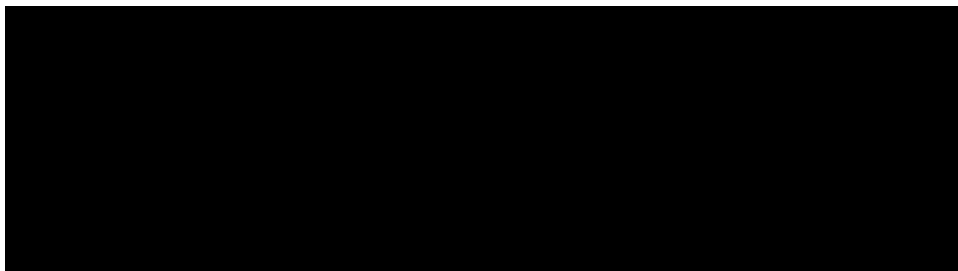

Figure 3: Simulink plots from exercise 3.2.3

Figure 4: Bode diagram of the loop gain $L(s)$ from exercise 3.2.1

Is the controller good?

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Are the output signals coupled?

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