Control Systems

G V V Sharma*

Contents

***Abstract*—The objective of this manual is to introduce control system design at an elementary level.**

Download python codes using

```
svn co https://github.com/gadepall/school/trunk/
    control/ketan/codes
```

*The author is with the Department of Electrical Engineering, Indian Institute of Technology, Hyderabad 502285 India e-mail: gadepall@iith.ac.in.

1 Polar Plot

1.1 Introduction

1.2 Example

1.3 Example

1.4 Example

1.5 Example

1.6 Example

1.7 Example

2 Bode Plot

2.1 Gain and Phase Margin

2.2 Example

2.3 Example

3 PID Controller

3.1 Introduction

4 Nyquist Plot

4.1. Using Nyquist criterion find the range of K for which closed loop system is stable.

$$G(s) = \frac{K}{s(s+6)}. \tag{4.1.1}$$

And,

$$H(s) = \frac{1}{s+9} \tag{4.1.2}$$

Solution: The system flow can be described as,

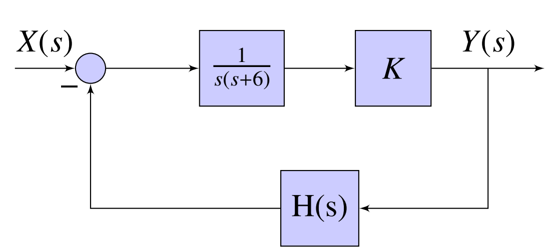

Fig. 4.1

$$G_1(s) = \frac{1}{s(s+6)}. \tag{4.1.3}$$

Nyquist Stability Criterion:

$$N = Z - P \tag{4.1.4}$$

where Z is # unstable poles of closed loop transfer function, P is # unstable poles of open loop transfer function and N is # clockwise encirclement of $(-1/K, 0)$.
For stable system,

$$Z = 0 \tag{4.1.5}$$

From 4.1.2 and 4.1.3,

$$P = 0 \tag{4.1.6}$$

$$\implies N = 0 \tag{4.1.7}$$

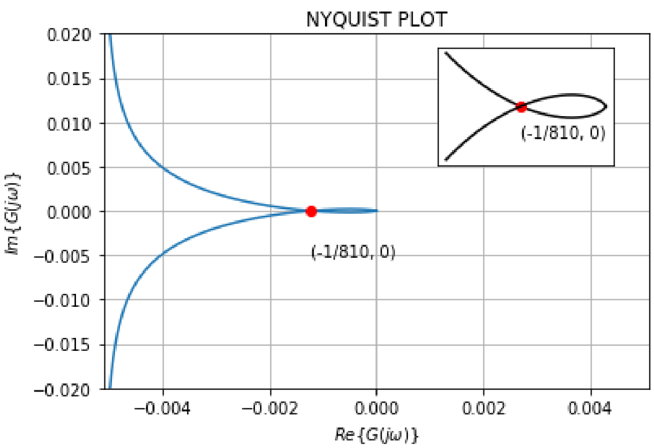

Fig. 4.1: Nyquist plot for $G_1(s)H(s)$

Since, there is a zero at origin, an infinite radius half circle will enclose the right hand side of end points of the Nyquist plot.

$$\implies \frac{-1}{K} < \frac{-1}{810} \tag{4.1.8}$$

$$\implies K < 810 \tag{4.1.9}$$

And also,

$$K > 0 \tag{4.1.10}$$

$$\implies 0 < K < 810 \tag{4.1.11}$$

The following python code generates Fig. 4.1

```
codes/ee18btech11028_1.py
```