

1/1

1/1

1/2

This does not explain why we need these values and cannot let just the controller define the input

2/2

it was not necessary to calculate the values in this task

1/2

The values for the overshoot and s

0/1

The crossover frequency is not correct, if you use the open-loop system with the third controller co

Your plots for small sampling times do not make sense. The discretized controller is not getting w

1/2

Where does the 0.1 come from?What is the

1/3

If you use the controller from Task 5 it the maximum sampling time should be around 0.4. Even if you

0/1

This graph is wrong

0/2

You should design the discretized s

1/1

1/1

0/3

Where do these poles come from?

You should derive A_a and B_a . For

1/3

Where is the derivation? This is just

0/3

If you use the controller that you designed in task for, there should be two eigenvalues

Why would you use the larger poles for a faster response?

1/2

This is not the reason for the steady state error, since you have designed I_r such that there should be no error.

2/2

5/5

