

MISR UNIVERSITY FOR SCIENCE AND TECHNOLOGY  
COLLEGE OF ENGINEERING  
MECHATRONICS DEPARTMENT



# MTE 506 DIGITAL CONTROL

LAB 5 – SPRING 2019

Lab 5

# Goals of The Lab



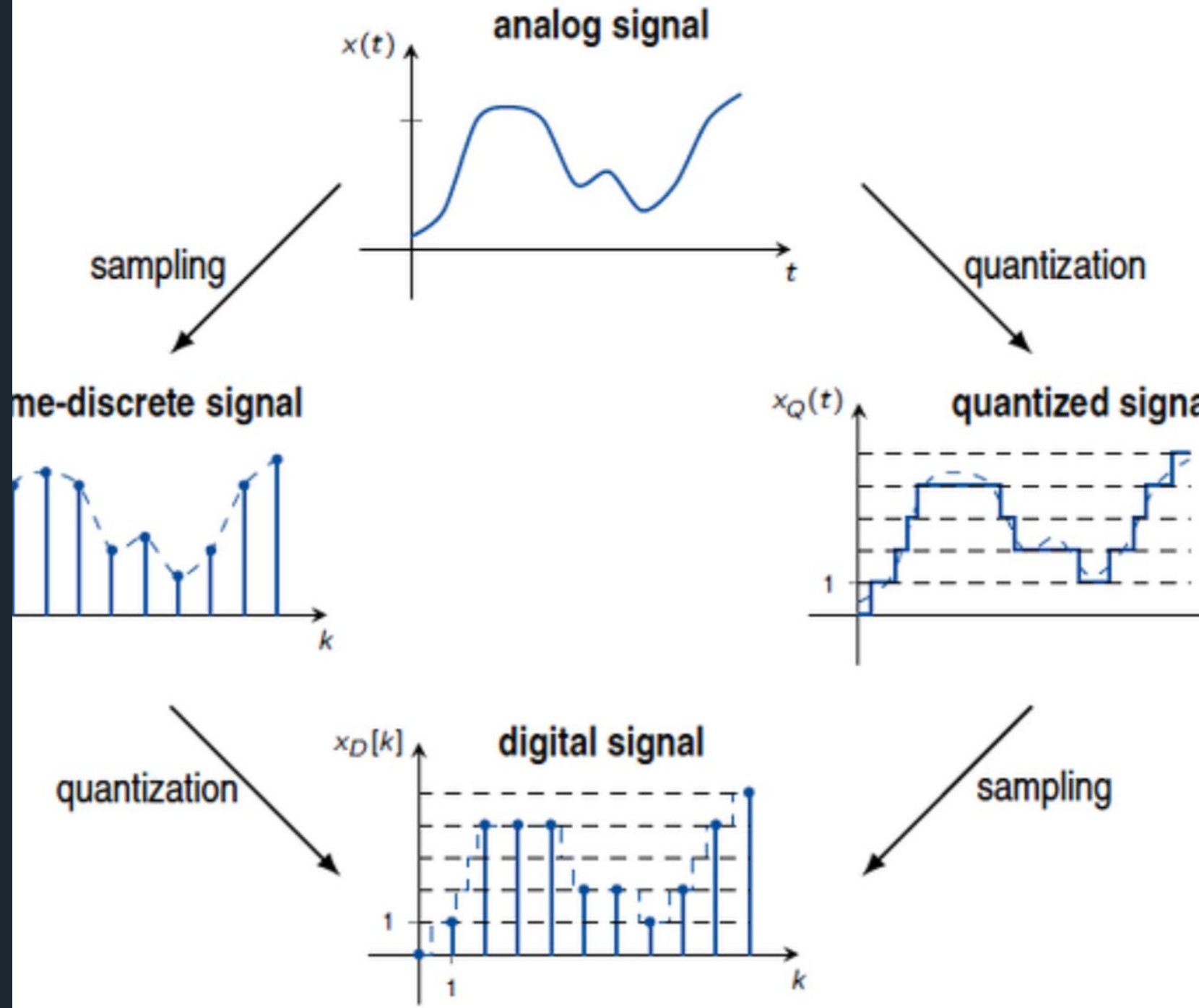
Discrete Systems Nomenclature



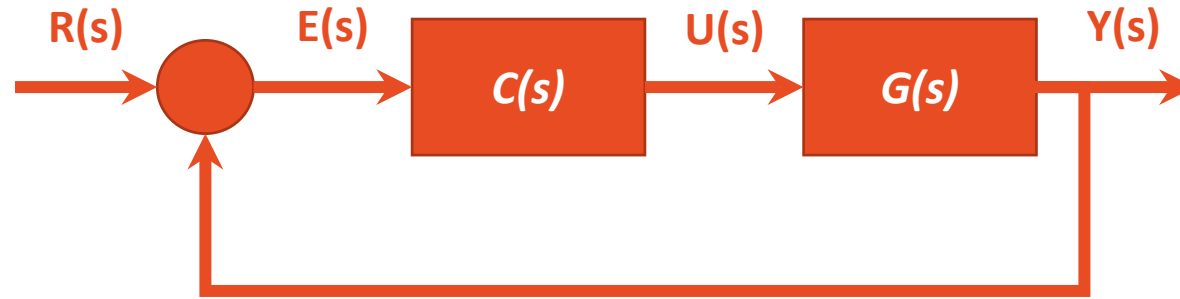
Practicing on Difference Equation

## Lab 5

# Continuous vs. Discrete Systems



# Continuous System vs. Discrete System



$R(s)$  ... *Stimulation signal*

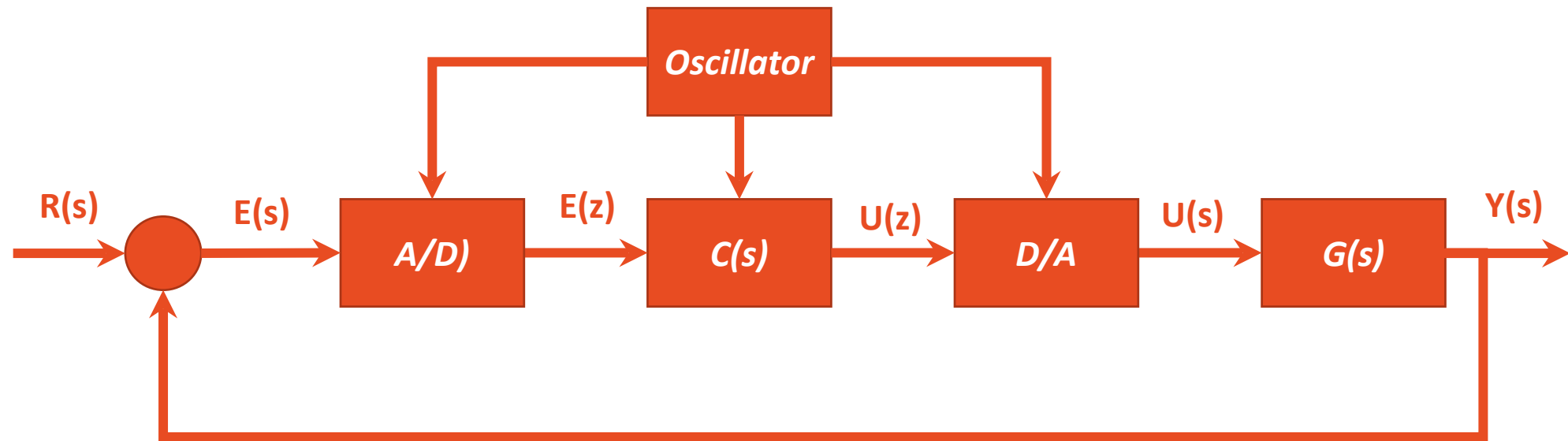
$E(s)$  ... *Error signal*

$C(s)$  ... *Controller*

$U(s)$  ... *Control Action*

$Y(s)$  ... *Sensor Output*

# Continuous System vs. **Discrete System**



$R(s)$  ... *Stimulation signal*

$E(s)$  ... *Error signal*

$C(s)$  ... *Controller*

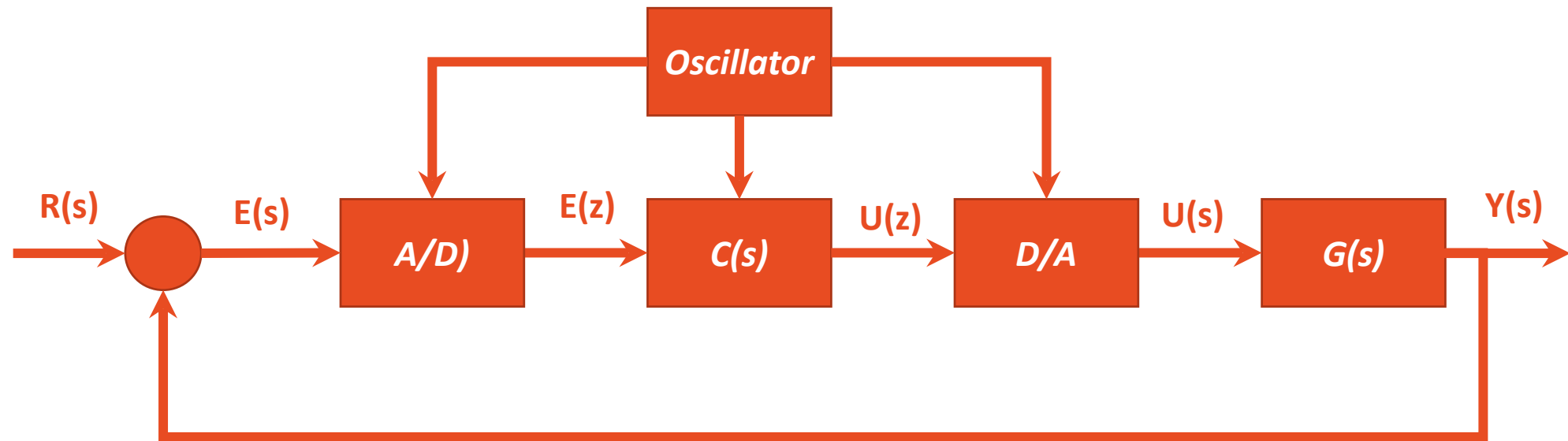
$U(s)$  ... *Control Action*

$Y(s)$  ... *Sensor Output*

$E(z)$  ... *Discretized error signal*

$U(z)$  ... *Discretized Control Action*

# Continuous System vs. **Discrete System**



$R(s)$  ... *Stimulation signal*

$E(s)$  ... *Error signal*

$C(s)$  ... *Controller*

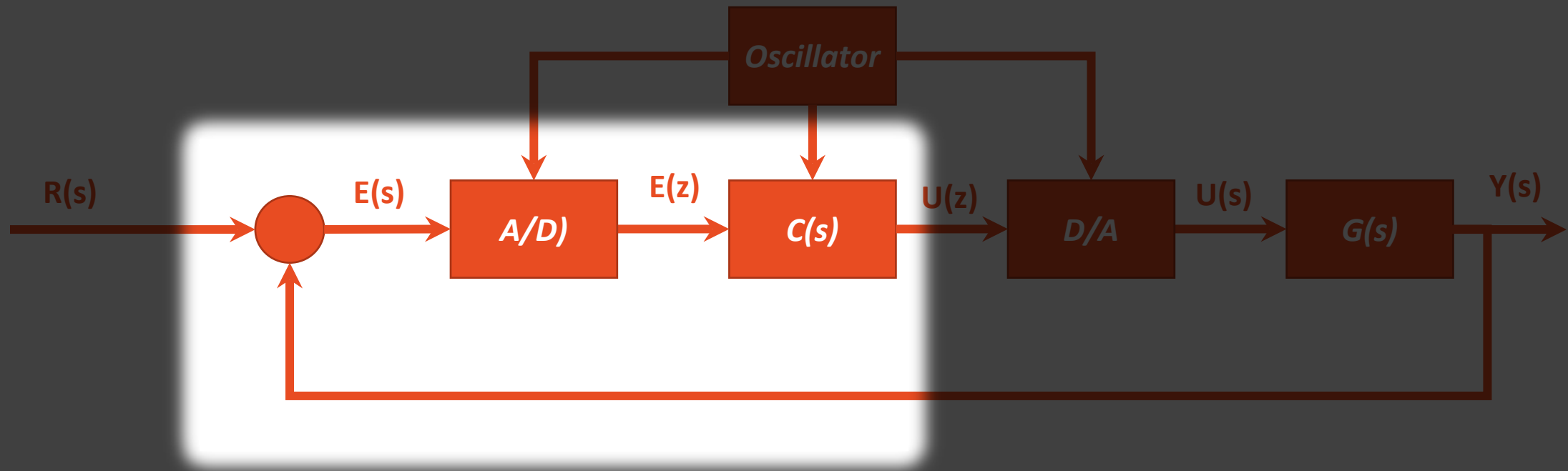
$U(s)$  ... *Control Action*

$Y(s)$  ... *Sensor Output*

$E(z)$  ... *Discretized error signal*

$U(z)$  ... *Discretized Control Action*

## Continuous System vs. **Discrete System**



# Modern Controllers

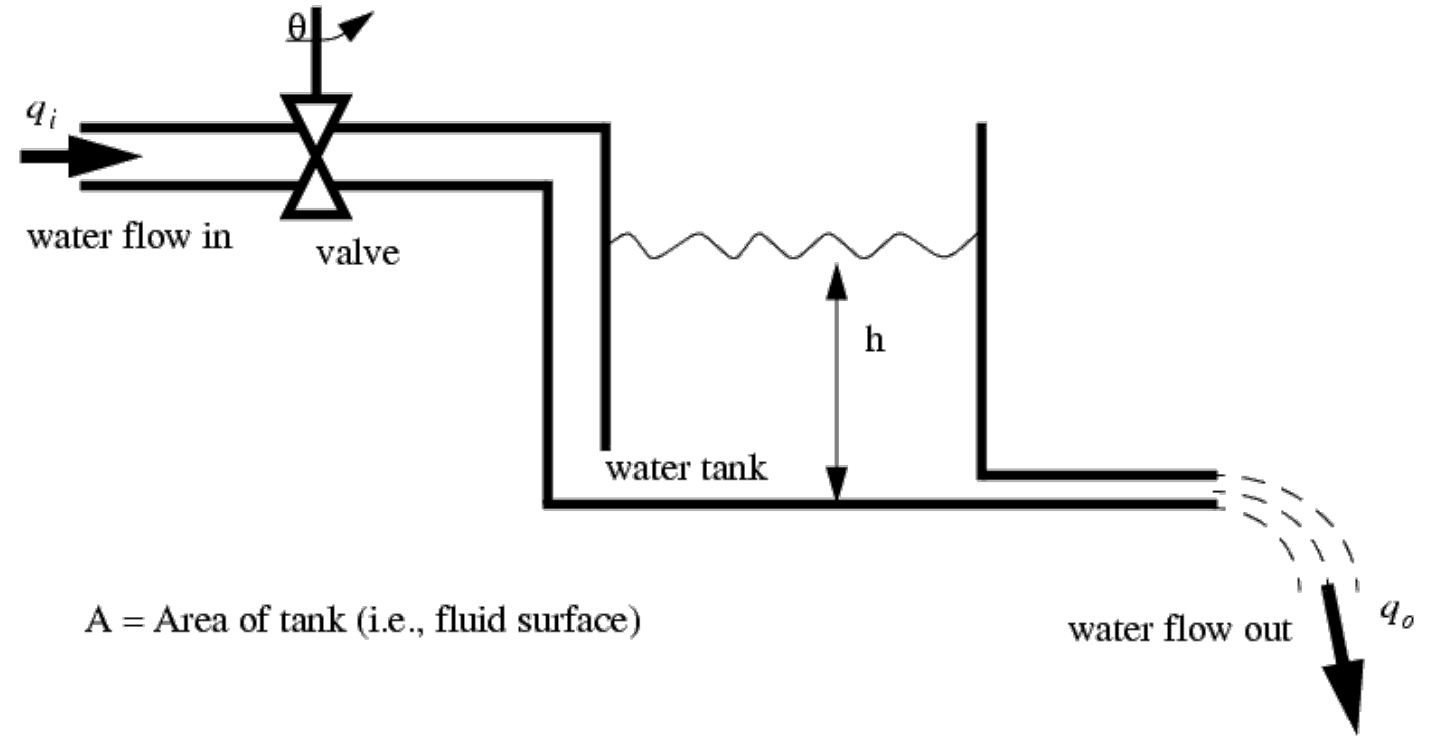
## Lab 5

# Simulating Water Tank

Revisited

## Conversion to Discrete System

Difference Equation





## In Lab 1 ....

$$h(t) = \frac{\Delta t * (k * h(t - \Delta t) - q_i(t))}{A} + h(t - \Delta t)$$

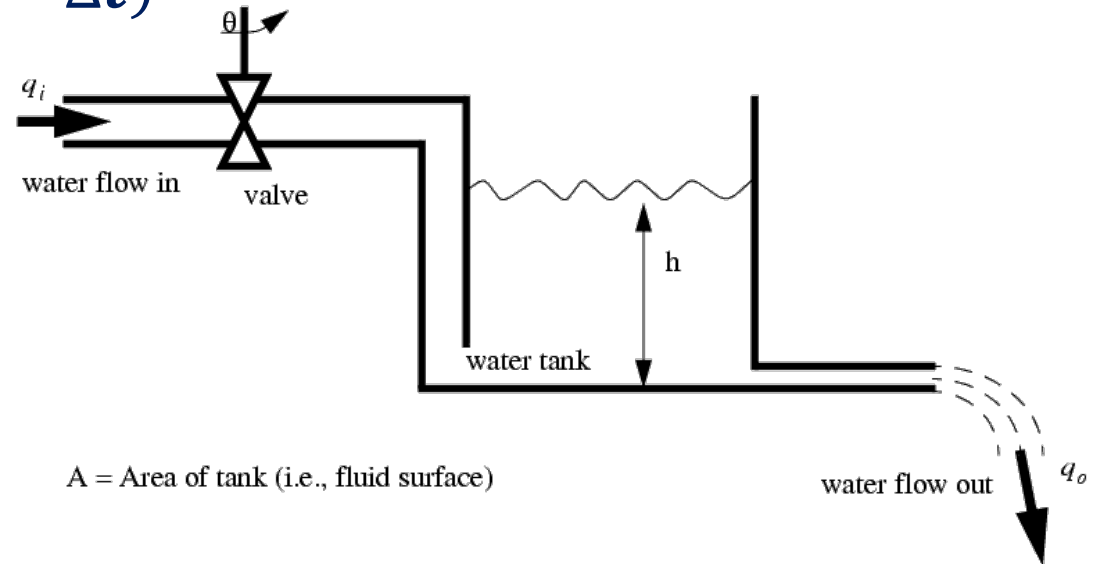
$\Delta t$  ... Sampling time     $q_i(t)$  ... Excitationsignal

Let  $\Delta t$  be  $T$  (textbook term)

Samples:

$T, 2T, 3T, \dots, kT$ ,     $k > 0$

$$h(kT) = \frac{T * (k * h(kT - 1) - q_i(kT))}{A} + h(kT - 1) \text{ [Difference Equation]}$$



# Difference Equation

$$h(kT) = \frac{T * (k * h(kT - 1) - q_i(kT))}{A} + h(kT - 1)$$

*if  $T = 1$  second (most problems assuming this for simplicity)*

$$h(k) = \frac{(k * h(k - 1) - q_i(t))}{A} + h(k - 1)$$

$$A[h(k) - h(k - 1)] - k * h(k - 1) = -q_i(t)$$

$$A * h(k) - A * h(k - 1) - k * h(k - 1) = -q_i(t)$$

$$A * h(k) - [A + k] * h(k - 1) = -q_i(t)$$

$$[A + k] * h(k - 1) - A * h(k) = q_i(t)$$

*[Difference Equation]*

# Difference Equation

$$[A + k] * h(k - 1) - A * h(k) = q_i(t)$$

System Output

System Input

$$\text{if } k = 0 \rightarrow h(k - 1) = h(0)$$

# Difference Equation

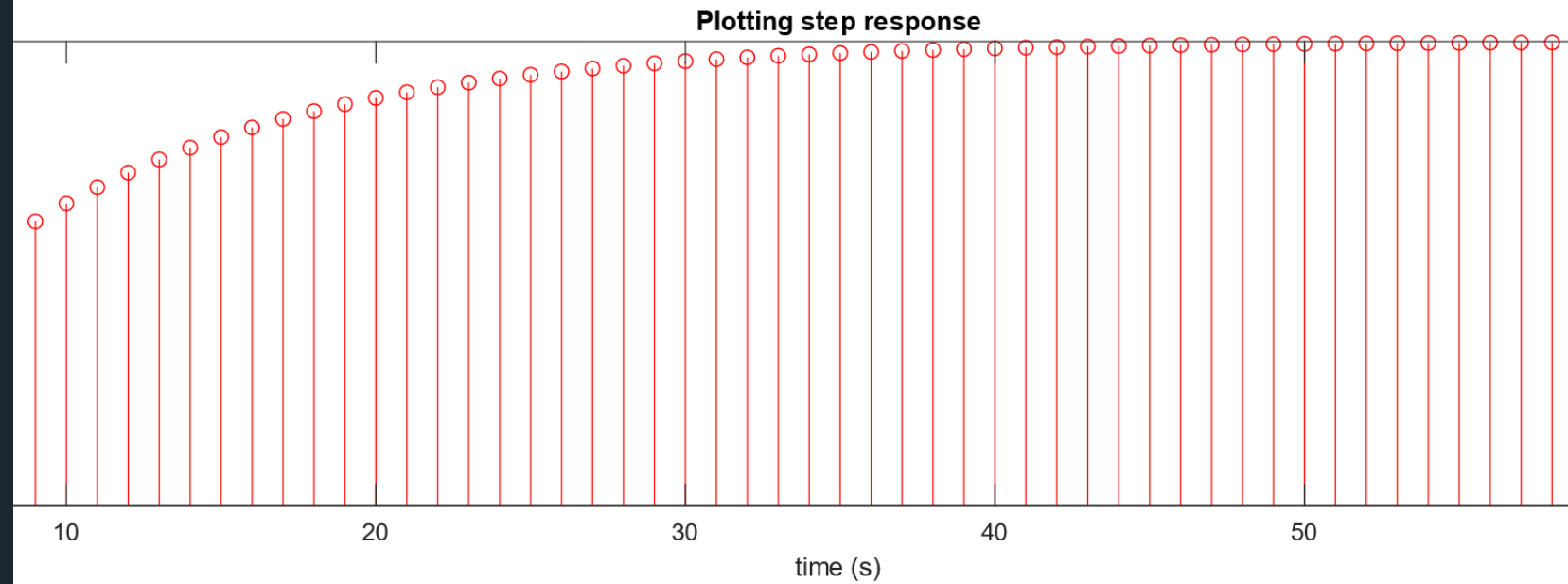
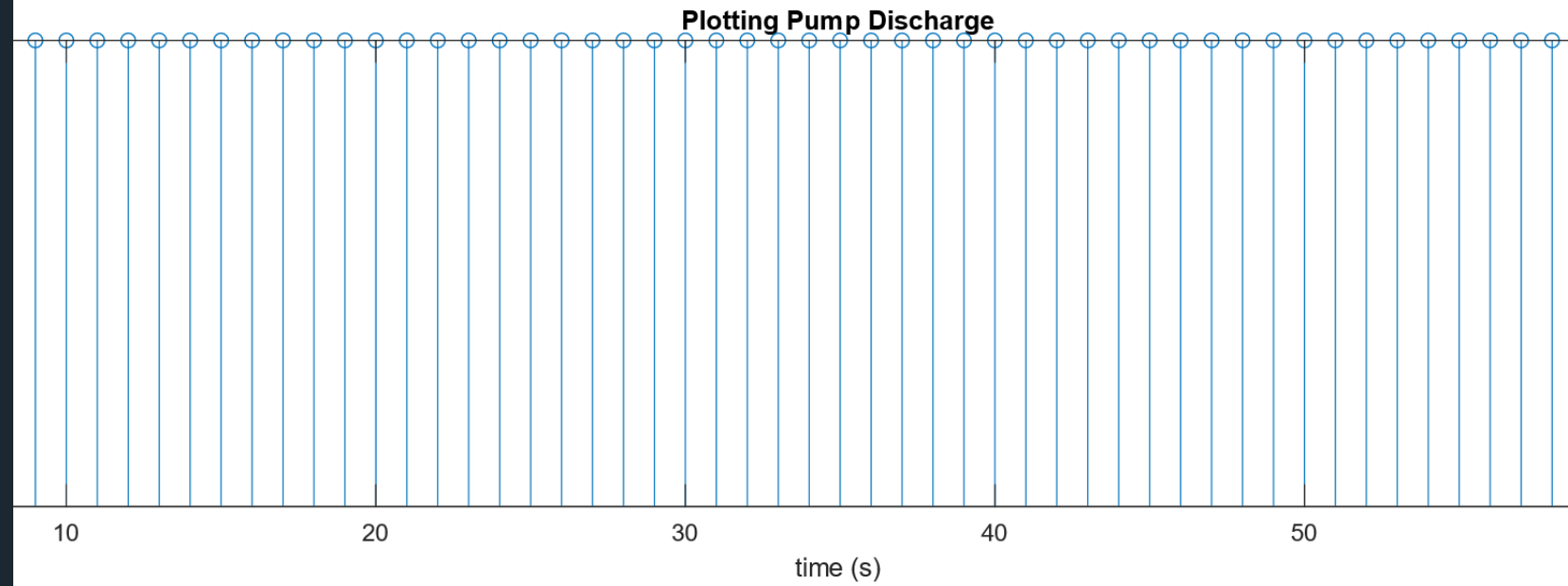
*Remember* 

$$\frac{dh}{dT} = h(t) - h(t - \Delta t) = h(kT) - h(kT - 1)$$

## Lab 5

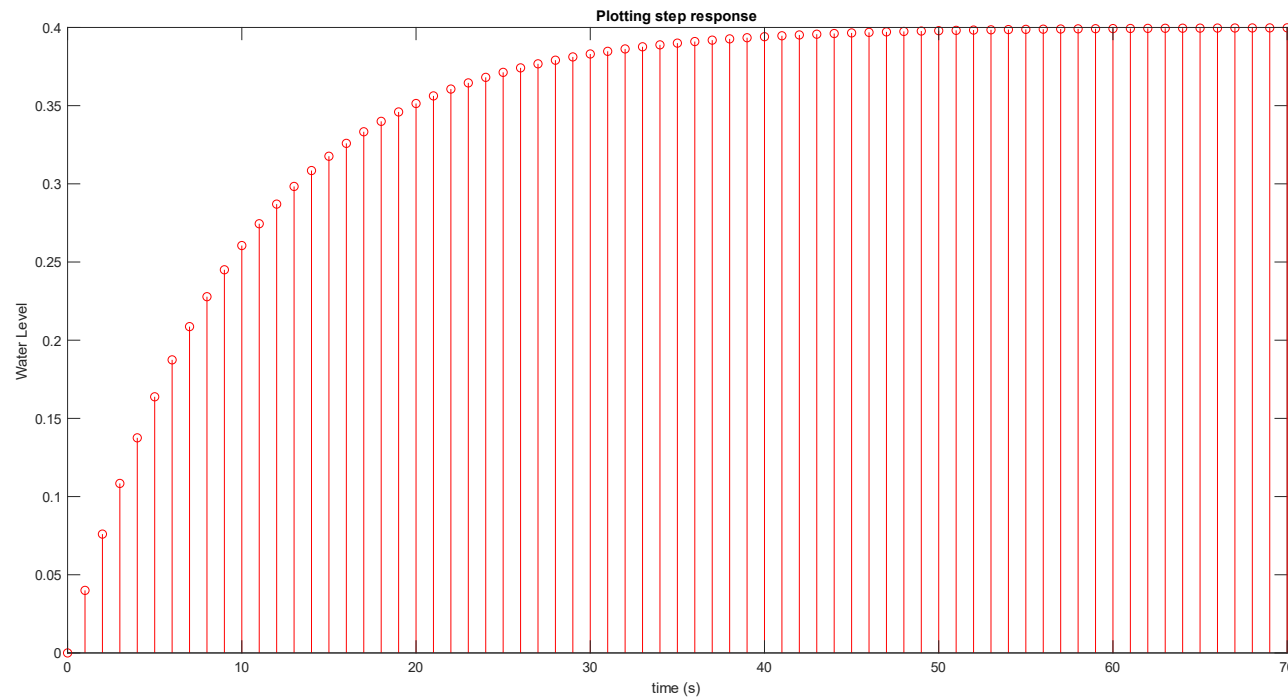
# Exercise 1

Representation of discrete response using MATLAB



## MATLAB command

***stem (t, y) ...plots discretized (SAMPLED) data***



## Solved Example

Difference Equation

ne system shown in Figure 12.7. For  $k = 0, 1, 2, \dots$ , then the system is described by the difference equation. This text studies only the class of systems that can be described by linear difference equations such as

$$y(k+2) + 2y(k+1) - y(k) = 2u(k+1)$$

$$y(k-1) - y(k-2) = 2u(k-1)$$

## Difference Equation Example

$$3y(k + 2) + 2y(k + 1) - y(k) = 2u(k + 1) - 3u(k)$$

*Find  $y$  value after 3 seconds assuming 1 s sampling interval*

### *Solution*

Rearranging equation terms by changing future term to past:

$y(k + 2) \rightarrow y(k)$  (present)  $\rightarrow$  replace  $k$  with  $k - 2$

$$\therefore 3y(k) + 2y(k - 1) - y(k - 2) = 2u(k - 1) - 3u(k - 2)$$



## Difference Equation Example

$$\therefore 3y(k) = 2u(k-1) - 3u(k-2) - 2y(k-1) + y(k-2)$$

$$\therefore y(k) = \frac{1}{3} [2u(k-1) - 3u(k-2) - 2y(k-1) + y(k-2)]$$

*Initial conditions needed*

$$y(-2) = 1, y(-1) = -2 \text{ and } u(k) = 1 \text{ [unit step]}$$

*We need to compute*  $y(0) \rightarrow y(1) \rightarrow y(2) \rightarrow y(3)$

## Difference Equation Example

$y(-2) = 1$ ,  $y(-1) = -2$  and  $u(k) = 1$  [unit step]

$$y(0) = \frac{1}{3} [2u(-1) - 3u(-2) - 2y(-1) + y(-2)]$$

$$= \frac{1}{3} [2 * (0) - 3 * (0) - 2 * (-2) + (1)] = \frac{5}{3}$$

$$y(1) = \frac{1}{3} [2u(0) - 3u(-1) - 2y(0) + y(-1)]$$

$$= \frac{1}{3} \left[ 2 * (1) - 3 * (0) - 2 * \left(\frac{5}{3}\right) + (-2) \right] = -\frac{10}{9}$$

## Difference Equation Example

$y(-2) = 1$ ,  $y(-1) = -2$  and  $u(k) = 1$  [unit step]

$$y(2) = \frac{1}{3} [2u(1) - 3u(0) - 2y(1) + y(0)]$$

$$= \frac{1}{3} \left[ 2 * (1) - 3 * (1) - 2 * \left(-\frac{10}{9}\right) + \left(\frac{5}{3}\right) \right] = \frac{26}{27}$$

$$y(3) = \frac{1}{3} [2u(2) - 3u(1) - 2y(2) + y(1)]$$

$$= \frac{1}{3} \left[ 2 * (1) - 3 * (1) - 2 * \left(\frac{26}{27}\right) + \left(-\frac{10}{9}\right) \right] = -\frac{109}{27}$$

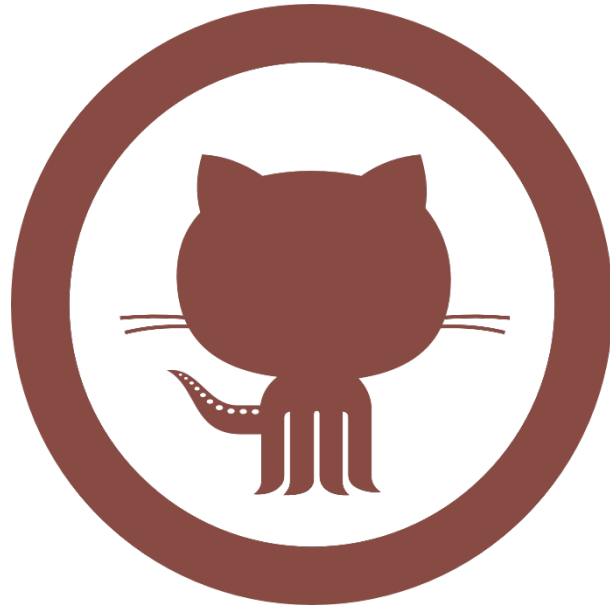
## Assignment

$$3y(k + 2) + 2y(k + 1) - y(k) = 2u(k + 1) - 3u(k)$$

*Write a MATLAB script to calculate  $y(k)$  given  $k, y(-1), y(-2)$  assuming unit step input*

***Due date (today 11:59 PM)***

***Send to : waleed.elbadry@must.edu.eg***



Don't forget to pull the lab update from.

<http://github.com/wbadry/mte506>

# END OF Lab 5