

Subject

Year:

Month:

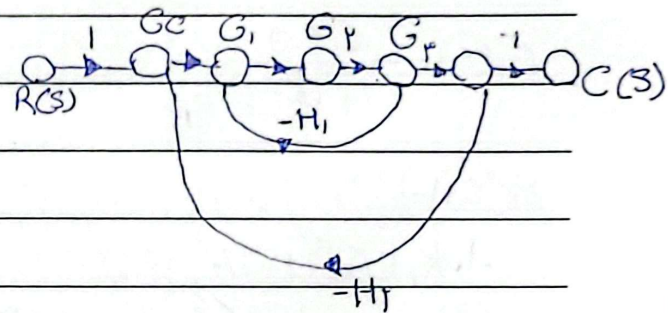
Day:

- بنام خدا  
- تازش عطریا  
- تمرین سری اول

$$(1) \frac{C(s)}{R(s)} = \frac{P}{D(s)}$$

$$P_i = G_c G_1 G_2 G_c \quad L_{1-1} = -G_c G_1 G_2 G_c H_1$$

$$\Delta_1 = 1 \quad L_{1-2} = -G_1 G_2 H_1$$

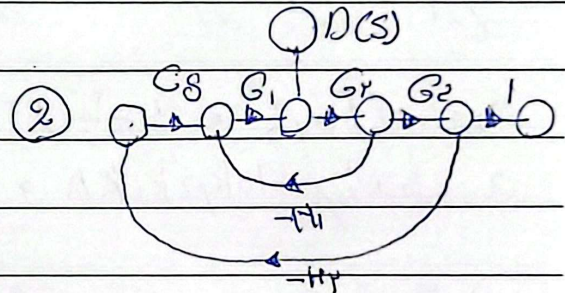


$$\frac{C(s)}{R(s)} = \frac{G_c G_1 G_2 G_c}{1 + G_1 G_2 H_1 + G_c G_1 G_2 G_c H_1}$$

$$(2) P_i = G_2 G_3 \quad L_{1-1} = -G_c G_1 G_2 G_c H_1$$

$$\Delta_1 = 1 \quad L_{1-2} = -G_1 G_2 H_1$$

$$\frac{C(s)}{D(s)} = \frac{G_2 G_c}{G_c G_1 G_2 G_c H_1 + G_1 G_2 H_1 + 1}$$



$$2. \dot{X} = AX + BU \quad Y = CX + DU$$

$$\begin{bmatrix} \dot{x} \\ \dot{w} \\ \dot{q} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} -\omega & \omega & \omega & 0 \\ \omega & -\omega & \omega & 0 \\ \omega & \omega & -\omega & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} u \\ w \\ q \\ \theta \end{bmatrix} + \begin{bmatrix} 0 \\ \omega \\ \omega \\ 0 \end{bmatrix} \delta$$

$\underbrace{\begin{bmatrix} \dot{x} \\ \dot{w} \\ \dot{q} \\ \dot{\theta} \end{bmatrix}}_{\dot{X}} = \underbrace{\begin{bmatrix} -\omega & \omega & \omega & 0 \\ \omega & -\omega & \omega & 0 \\ \omega & \omega & -\omega & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix}}_A \underbrace{\begin{bmatrix} u \\ w \\ q \\ \theta \end{bmatrix}}_X + \underbrace{\begin{bmatrix} 0 \\ \omega \\ \omega \\ 0 \end{bmatrix}}_B \delta$

$$Y = \begin{bmatrix} 1 & 1 & 0 & 0 \\ 0 & 0 & 1 & -1 \end{bmatrix} \begin{bmatrix} u \\ w \\ q \\ \theta \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \end{bmatrix} \delta$$



$$(3) G(s) = G_1(s) G_2(s) G_c(s) \quad G_1(s) = \frac{k_1}{s} \text{ and } G_2(s) = \frac{1}{s+1}$$

$$G_c(s) = \frac{-k_A(1+STA)}{(s^2 + 2\zeta\omega_{sp}s + \omega_{sp}^2)}$$

$$G(s) = \left(\frac{k_1}{s}\right) \left(\frac{1}{s+1}\right) \left(\frac{-k_A(1+STA)}{(s^2 + 2\zeta\omega_{sp}s + \omega_{sp}^2)}\right)$$

$$G(s) = \frac{G(s)}{1 + G(s)k_p}$$

$$s(s+1)(s^2 + 2\zeta\omega_{sp}s + \omega_{sp}^2)q(s) + 1 \cdot k_p k_1 k_A (1+STA)q(s) = -1 \cdot k_1 k_A (1+STA)q(s)$$

$$\frac{d^3 q}{dt^3} + a_2 \frac{d^2 q}{dt^2} + a_1 \frac{dq}{dt} + a_0 q = b_1 \frac{d^2 q}{dt^2} + b_0 q$$

$$a_1 = 1 + 2\zeta\omega_{sp} \text{ and } a_2 = 1 + (2\zeta\omega_{sp}) + \omega_{sp}^2 + 1 \cdot k_p k_1 k_A T_A$$

$$a_0 = 1 \cdot \omega_{sp}^2 + 1 \cdot k_p k_1 k_A \text{ and } b_0 = -1 \cdot k_1 k_A \text{ and } b_1 = -1 \cdot k_1 k_A T_A$$

$$(4) \ddot{y} - \ddot{y} + 3\dot{y} + 4y = 2\ddot{u} + 5\dot{u} - \dot{u} + 3u$$

$$\ddot{y} + a_1 \dot{y} + a_2 y = b_0 \ddot{u} + b_1 \dot{u} + b_2 u$$

$$a_1 = -1 \quad b_1 = 5$$

$$a_2 = 3 \quad b_2 = -1$$

$$a_3 = 4 \quad b_3 = 3$$

$$\left. \begin{matrix} y_1 = y \\ y_2 = \dot{y} \\ y_3 = \ddot{y} \end{matrix} \right\} \Rightarrow \left. \begin{matrix} \dot{y}_1 = \dot{y} \\ \dot{y}_2 = \ddot{y} \\ \dot{y}_3 = \ddot{\ddot{y}} \end{matrix} \right\} \Rightarrow \left. \begin{matrix} \dot{y}_1 = y_2 \\ \dot{y}_2 = y_3 \\ \dot{y}_3 = -4y_1 - 3y_2 + y_3 + 2\ddot{u} + 5\dot{u} - \dot{u} + 3u \end{matrix} \right\}$$

$$\begin{bmatrix} \dot{y}_1 \\ \dot{y}_2 \\ \dot{y}_3 \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -4 & -3 & 1 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \\ y_3 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 2 \end{bmatrix} \ddot{u} + \begin{bmatrix} 0 \\ 5 \\ 5 \end{bmatrix} \dot{u} + \begin{bmatrix} 0 \\ 0 \\ 3 \end{bmatrix} u$$

$$Y = [1 \ 0 \ 0] \begin{bmatrix} y_1 \\ y_2 \\ y_3 \end{bmatrix} + [0] u \quad \text{Ariyan}$$