CONTENTS

Abstract—This manual is an introduction to control systems based on GATE problems.Links to sample Python codes are available in the text.

Download python codes using

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

1 STABILITY

2 ROUTH HURWITZ CRITERION

- 3 Compensators
- 4 NYQUIST PLOT
- 4.1 Polar plot
- 4.1. Sketch direct and inverse polar plots for a unity feedback system with open loop transfer function

$$G(s) = \frac{1}{s(1+s)^2} \tag{4.1.1}$$

Solution: For Unity feedback system, given the open loop transfer function

$$G(s) = \frac{1}{s(1+s)^2}$$
 (4.1.2)

Now, Polar plot is defined as: The plot of points(represented as $r.e^{j\phi}$) obtained by varying w from 0 to ∞ where

$$r = |H(1\omega)||G(1\omega)| \tag{4.1.3}$$

$$\phi = \angle H(j\omega)G(j\omega) \tag{4.1.4}$$

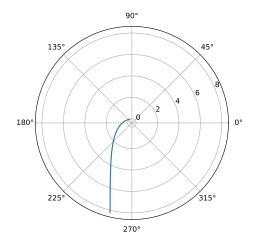
Inverse Polar plot is similar, in this we have;

$$r = \frac{1}{|H(j\omega)||G(j\omega)|}$$
(4.1.5)

$$\phi = -\angle H(j\omega)G(j\omega) \tag{4.1.6}$$

The system we're analysing is unity feedback which means $H(j\omega) = 1$ Therefore;

$$|H(j\omega)||G(j\omega)| = \frac{1}{\omega(1+\omega^2)}$$
 (4.1.7)



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Fig. 4.1: Polar Plot

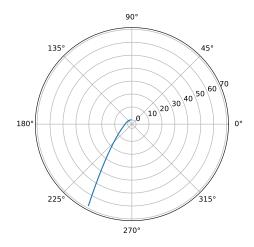


Fig. 4.1: Inverse Polar Plot

and Phase;

$$\angle H(j\omega)G(j\omega) = \frac{-\pi}{2} - 2tan^{-1}(\omega) \qquad (4.1.8)$$

The following code plots the polar and inverse polar plots

codes/ee18btech11002/polarplot.py

4.2. Find the frequency at which $|G(j\omega)| = 1$ and corresponding phase angle $\angle G(j\omega)$

Solution: For $|G(1\omega)| = 1$

$$\frac{1}{\omega(1+\omega^2)} = 1 \tag{4.2.1}$$

$$\omega + \omega^3 - 1 = 0 \tag{4.2.2}$$

and for the corresponding phase

$$\angle G(j\omega) = \frac{-\pi}{2} - 2tan^{-1}(\omega) \tag{4.2.3}$$

The following code calculates the value of w and $\angle G(\jmath\omega)$

codes/ee18btech11002/solution.py

and we get

$$\omega = 0.682$$
 (4.2.4)

$$\angle G(j\omega) = -\frac{52}{59}\pi\tag{4.2.5}$$