# Computing controllers that ensure a phase margin of 60 degrees

### Compute and declare my transfer function

The transfer function has the following form:

$$H_f(s) = \frac{K_f}{s(T_f s + 1)}$$

Knowing that my values are Kf = 4 and Tf = 8, the function becomes:

$$H_f(s) = \frac{4}{s(8s+1)}$$

I declare my transfer function in code:

```
Kf = 4;
Tf = 8;
Hf = tf(Kf,[Tf 1 0])
```

Hf =

4
----8 s^2 + s

Continuous-time transfer function.

Declare the phase margin's value

$$gammaK = 60;$$

## **Computing a PD**

$$\angle H_{ol}(j\omega_c) = -180^\circ + \gamma_k$$

We choose  $\beta$  between 0.1 and 0.125

$$\angle H_c(j\omega_c) = atan \frac{1-\beta}{2\sqrt{\beta}}$$

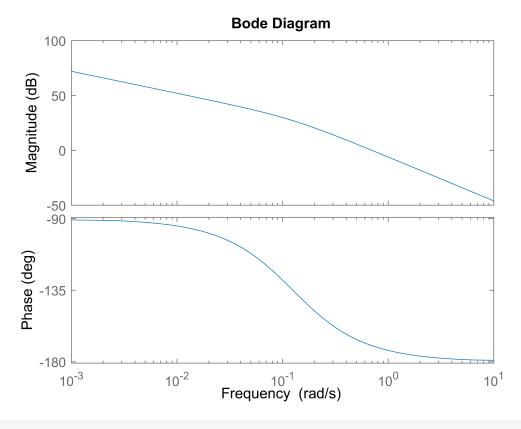
phaseHc = atand((1-beta)/2/sqrt(beta));

$$\angle H_{ol}(j\omega_c) = \angle \left( H_p(j\omega_c) H_c(j\omega_c) \right) = \angle H_p(j\omega_c) + \angle H_c(j\omega_c)$$

phaseHp = phaseHol - phaseHc;

I get the value of  $w_c$  from bode:

bode(Hf)



$$Wc = 1.4;$$

$$au_d = rac{1}{\omega_c \sqrt{eta}}$$

I read the value of  $|H_p(jw_c)|$  from Bode

$$magHp = 10^{(-12)/20};$$

$$k_p = \frac{\sqrt{\beta}}{\left|H_p(j\omega_c)\right|}$$

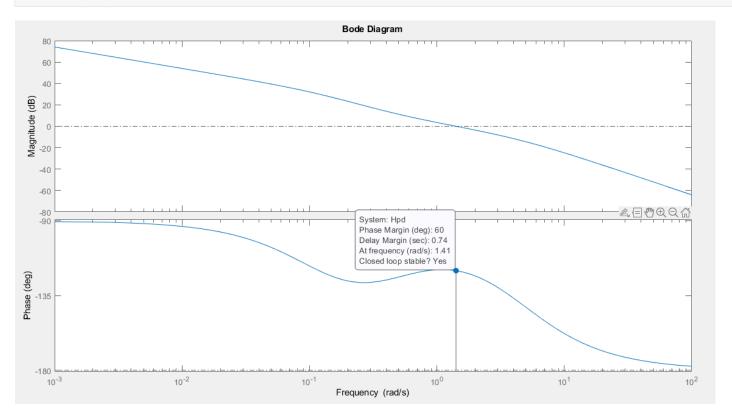
Using PD general formula, I compute the final open loop transfer function.

$$H_c(s) = k_p \frac{1 + \tau_d s}{1 + \beta \tau_d s}$$

Hpd =

Continuous-time transfer function.

#### % bode(Hpd)



# **Computing a PI**

$$\angle H_{ol}(j\omega_c) = -180^{\circ} + \gamma_k$$

assume that  $\angle H_c(j\omega_c) = -15^\circ$ 

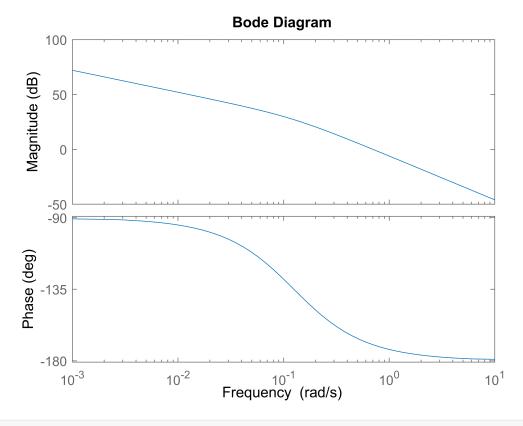
phaseHc = -15;

$$\angle H_{ol}(j\omega_c) = \angle \left( H_p(j\omega_c) H_c(j\omega_c) \right) = \angle \, H_p(j\omega_c) + \angle \, H_c(j\omega_c)$$

phaseHp = phaseHol - phaseHc;

I get the value of  $w_c$  from bode:

bode(Hf)



Wc = 0.035;

$$T_i = \frac{4}{\omega_c}$$

$$Ti = 4/Wc;$$

I read the value of  $|H_p(jw_c)|$  from Bode

$$magHp = 10^{(40/20)};$$

$$k_p = \frac{1}{|H_p(j\omega_c)|}$$

kp = 1/magHp;

Using PI general formula, I compute the final open loop transfer function.

$$H_c = k_p \left(1 + \frac{1}{\mathrm{T_i s}}\right)$$

Hpi =

Continuous-time transfer function.

### % bode(Hpi)

