Control Systems

G V V Sharma*

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

1 Stability

1.1 Second order System

1.1. State the general model of a state space system specifying the dimensions of the matrices and vectors.
Solution:

$$\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t) \tag{1.1.1}$$

$$\mathbf{y}(t) = \mathbf{C}\mathbf{x}(t) + Du(t) \tag{1.1.2}$$

x(.) is called the "state vector"
y(.) is called the "output vector"
u(.) is called the "input(control) vector"
A(.) is the "state or system matrix", dim[A(.)]=nxn
B(.) is the "input matrix",dim[B(.)]=nxp
C(.) is the "output matrix",dim[C(.)]=qxn
D(.) is the "feedthrough matrix",dim[A(.)]=qxp
$\dot{x}(t) = \frac{d}{dt}x(t)$

1.2. Find the transfer function $\mathbf{H}(s)$ for the general system.
Solution:
FINDING TRANSFER FUNCTION

$$\dot{X}(t) = AX(t) + BU(t) \tag{1.2.1}$$

$$Y(t) = CX(t) + DU(t) \tag{1.2.2}$$

by applying laplace transforms on both sides of equation 1 we get
s.X(s)-X(0)=A.X(s)+B.U(s)
s.X(s)-A.X(s)=B.U(s)+X(0)
(sI-A)X(s)=X(0)+B.U(s)
$X(s) = X(0)([sI-A])^{-1} + (([sI-A])^{-1}B)U(s)$

Laplace transform of equation 2 and sub X(s)
Y(s)=C.X(s)+D.U(s)
$Y(s) = C.[X(0)([sI-A])^{-1} + (([sI-A])^{-1}B)U(s)] + DU(s)$
If X(0)=0
then $Y(s) = C[(([sI-A])^{-1}B)U(s)] + DU(s)$
$\frac{Y(s)}{U(s)} = C[(([sI-A])^{-1}B)] + D = H(s)$

1.3. Given

$$H(s) = \frac{1}{s^3 + 3s^2 + 2s + 1} \tag{1.3.1}$$

$$b1 = \begin{vmatrix} 0 & 0 & 1 \end{vmatrix} \tag{1.3.2}$$

$$b1^T = B \tag{1.3.3}$$

and D=0, find A and C.
Solution:
In the generic form D is feedforward matrix of dimension qxp
where q is number of outputs and p is number of inputs
from given question as D is given 0(scalar), so q=p=1
therefore it is single input and single output system
Hence U is the input and Y is the output which are scalar
Given that B is 3x1 so, n=3
so, A is 3x3,C is 1x3
As we know that
$Y(s) = H(s) \times U(s) = (\frac{1}{s^3+3s^2+2s+1}) \times U(s)$

$H(s) = \frac{Y(s)}{U(s)} = (\frac{(\frac{Y(s)}{x_1(s)})}{\frac{U(s)}{x_1(s)}}) = \frac{1}{s^3+3s^2+2s+1}$

let $x_1(s) = \frac{U(s)}{s^3+3s^2+2s+1}$

$Y(s) = x_1(s) \times 1$

$$s^3x_1(s) + 3s^2x_1(s) + 2sx_1(s) + x_1(s) = U(s) \tag{1.3.4}$$

Taking inverse laplace transform we get
$\dddot{x_1}(t) + \ddot{x_1}(t) + \dot{x_1}(t) + x_1(t) = U(t)$
$\dot{x_1} = x_2$
$\ddot{x_1} = \dot{x_2} = x_3$
$\dddot{x_1} = \ddot{x_2} = \dot{x_3}$
so equation 1.1.4 can be written as

$$\begin{bmatrix} sx_1(s) \\ s^2x_1(s) \\ s^3x_1(s) \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -1 & -2 & -3 \end{bmatrix} \times \begin{bmatrix} x_1(s) \\ sx_1(s) \\ s^2x1(s) \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} \times U \tag{1.3.5}$$

*The author is with the Department of Electrical Engineering, Indian Institute of Technology, Hyderabad 502285 India e-mail: gadepall@iith.ac.in.

taking inverse laplace transform

$$\begin{bmatrix} \dot{x_1} \\ \dot{x_2} \\ \dot{x_3} \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -1 & -2 & -3 \end{bmatrix} \times \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} \times U \tag{1.3.6}$$

therfore

$$A = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -1 & -2 & -3 \end{bmatrix} \tag{1.3.7}$$

Since $Y(s) = x_1(s) \times numerator$
therefore $Y(s) = x_1(s)$

$$\tag{1.3.8}$$

$$Y = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix} \times \begin{bmatrix} x_1(s) \\ sx_1(s) \\ s^2 x_1(s) \end{bmatrix} \tag{1.3.9}$$

taking inverse laplace transform

$$\tag{1.3.10}$$

$$Y = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix} \times \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} \tag{1.3.11}$$

$$C = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix} \tag{1.3.12}$$

2 Routh Hurwitz Criterion

3 Compensators

4 Nyquist Plot