Hem,

$$A = \begin{bmatrix} 0 & 1 \\ -t/m & -b/m \end{bmatrix} ,$$

So,
$$C_{A,B} = \begin{bmatrix} B & AB \end{bmatrix} = \begin{bmatrix} O & V_{am} \\ V_{m} & -b/_{m^2} \end{bmatrix} \left\{ dut(c_{A,B}) \neq 0 \right\}.$$

implies the system is controllable.

open loop characterésties polynomial = det (SI-A)

= det
$$\left[\begin{array}{cc} S & -1 \\ k/m & S + \frac{b}{m} \end{array} \right]$$

$$= S\left(\varsigma + \frac{b}{m}\right) + \frac{k}{m}$$

$$= 3 a_{A} = \left(\frac{b}{m} \frac{k}{m}\right)$$

$$= 5^{2} + \frac{b}{m}s + \frac{k}{m}.$$

$$A_{A} = \left(1 + \frac{b}{m}\right)$$

$$A_{n} = \begin{pmatrix} 1 & 5/m \\ 0 & 1 \end{pmatrix}$$

Now, desired closed loop polynomial: 52+24, wis + won2

(when wn = 1.1 & Hs = 0.7)

from the augmented system.
$$A_{1} = \begin{pmatrix} 0 & 1 & 0 \\ -k_{1}m & -b_{1}m & 0 \\ -1 & 0 & 0 \end{pmatrix}$$

$$\theta_1 = \begin{pmatrix} \theta \\ 0 \end{pmatrix} = \begin{pmatrix} 0 \\ \frac{1}{m} \end{pmatrix}$$

$$A_{1}^{2}B_{1} = \begin{cases} 0 & \frac{1}{m} & -\frac{b}{m^{2}} \\ \frac{1}{m} & \frac{b^{2}-k}{m^{2}} \\ 0 & 0 & -\frac{1}{m} \end{cases}$$

open loop charactéristics polynomial = det (SI - AI).

$$\frac{1}{2} \det \begin{pmatrix} s & -1 & 0 \\ \frac{1}{2} & s + \frac{b}{m} & 0 \\ 0 & s \end{pmatrix} = s^{3} + \frac{b}{m} s^{2} + \frac{ks}{m}.$$

$$\Rightarrow a_m = \left(\frac{b}{m} + \frac{k}{m}\right)$$

$$\Rightarrow a_{m} = \left(\frac{b}{m} + \frac{k}{m} + 0\right) \qquad A_{A_{1}} = \left(\frac{1}{0} + \frac{b}{m} + \frac{k}{m}\right)$$

$$= 5^{3} + (P, +2 2 s w n) s^{2} + (w n^{2} + 2 2 s w n P,) s$$

$$+ w n^{2} P,$$

$$\Rightarrow x = (P_1 + 2\xi_5 \omega_n), (w_n^2 + 2\xi_5 \omega_n P_1), \omega_n^2 P_1).$$

Hence,
$$R_1 = \left(\alpha - \alpha_{A_1}\right)\left(\frac{1}{A_{A_1}}\right)\left(C_{A_1B_1}\right)$$

$$K_{\bar{1}} = K_{1}(3)$$
 $K = K_{1}(1:2)$