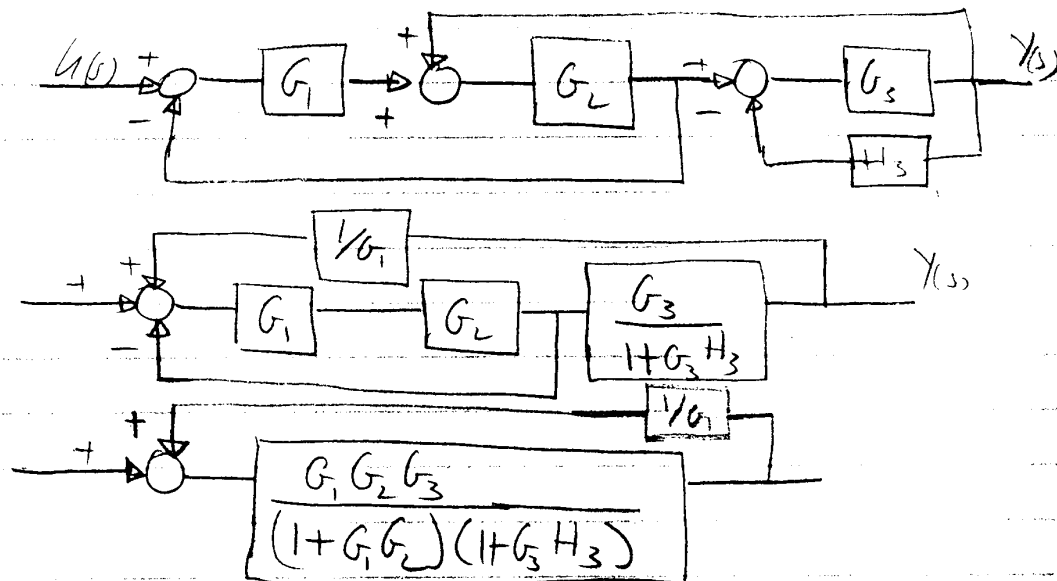
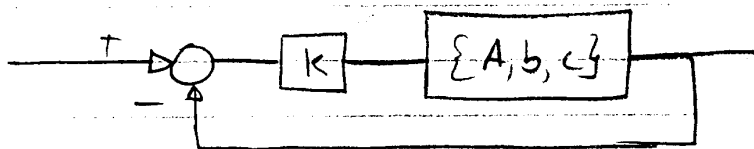


(4) 1.



$$G(s) = \frac{G_1 G_2 G_3}{(1 + G_1 G_2)(1 + G_3 H_3)} = \frac{G_1 G_2 G_3}{1 + G_1 G_2 + G_3 H_3 + G_1 G_2 G_3 H_3 - G_2 G_3}$$

(4) 2.



$$G(s) = [1 \ 2] \begin{bmatrix} s+4 & -5 \\ -1 & s \end{bmatrix}^{-1} \begin{bmatrix} 1 \\ 0 \end{bmatrix} = \frac{1}{s(s+4)-5} [1 \ 2] \begin{bmatrix} s & 5 \\ 1 & s+4 \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$= \frac{s+2}{s^2+4s-5}$$

$$G_{tot}(s) = \frac{(s+2)K}{s^2+4s-5+K(s+2)} = \frac{(s+2)K}{s^2+(4+K)s+(2K-5)}$$

necessary and sufficient $\begin{cases} 4+K > 0 \\ 2K-5 > 0 \end{cases} \Rightarrow K > 2.5$

$$(2) \quad 3. \quad G(s) = \frac{4s + 6}{s^3 + 3s^2 + 2s + 1}$$

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

$$b = \begin{bmatrix} 6 \\ 4 \\ 0 \end{bmatrix}$$

$$c = [0, 0, 1]$$

$$\beta_0 = 0, \beta_1 = 0, \beta_2 = 4$$

$$\beta_3 = b_3 - a_1\beta_2 = 6 - 3 \cdot 4 = -6$$

or

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

$$b = \begin{bmatrix} 0 \\ 4 \\ -6 \end{bmatrix}$$

$$c = [1, 0, 0]$$

$$(4) \quad 4. \quad G(s) = \frac{s+1}{s^2(s+4)}$$

$$\text{zeros: } -1 \quad \text{poles: } 0, 0, -4$$

$$\text{asymptotes: } \phi = (2k+1) \frac{180}{2} = \pm 90^\circ \quad \sigma = \frac{-4+1}{2} = -1.5$$

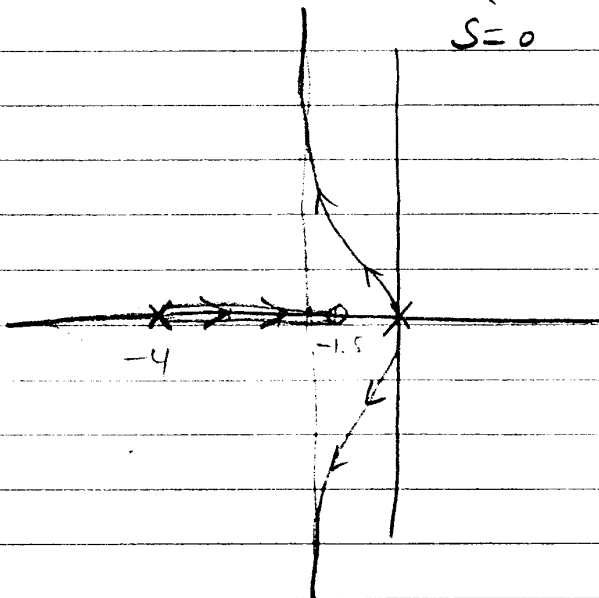
$$\text{break-away points } (3s^2 + 8s)(s+1) - (s^3 + 4s^2) = 0$$

$$s(3s^2 + 8s + 3s + 8 - s^2 - 4s) = 0$$

$$s(2s^2 + 7s + 8) = 0$$

$$s = 0 \quad s = \frac{-7 \pm \sqrt{49 - 64}}{4}$$

complex conjugate \Rightarrow not possible

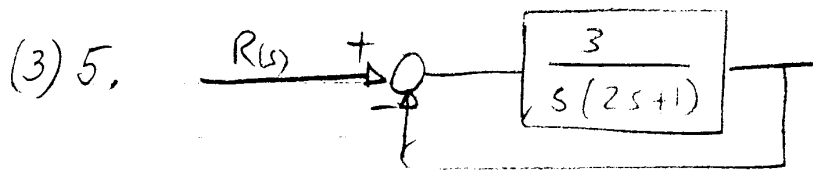


• The system has an underdamped response for all $K > 0$.

• Settling time decreases until it becomes $t_s = \frac{4}{1.5}$

• frequency of oscillations increases as $K \uparrow$.

• damping ratio from $0 \rightarrow \zeta_{max} \rightarrow 0$.



Open-loop system is type 1 $K_p = \infty$ $K_v = 3$

e_{ss} for step $e_{ss} = \frac{1}{1+K_p} = 0$

e_{ss} for ramp $e_{ss} = \frac{1}{K_v} = \frac{1}{3}$