

1. (a) 試寫出 phase leading compensator 之通式, 並繪出其 Bode plot. (5分)

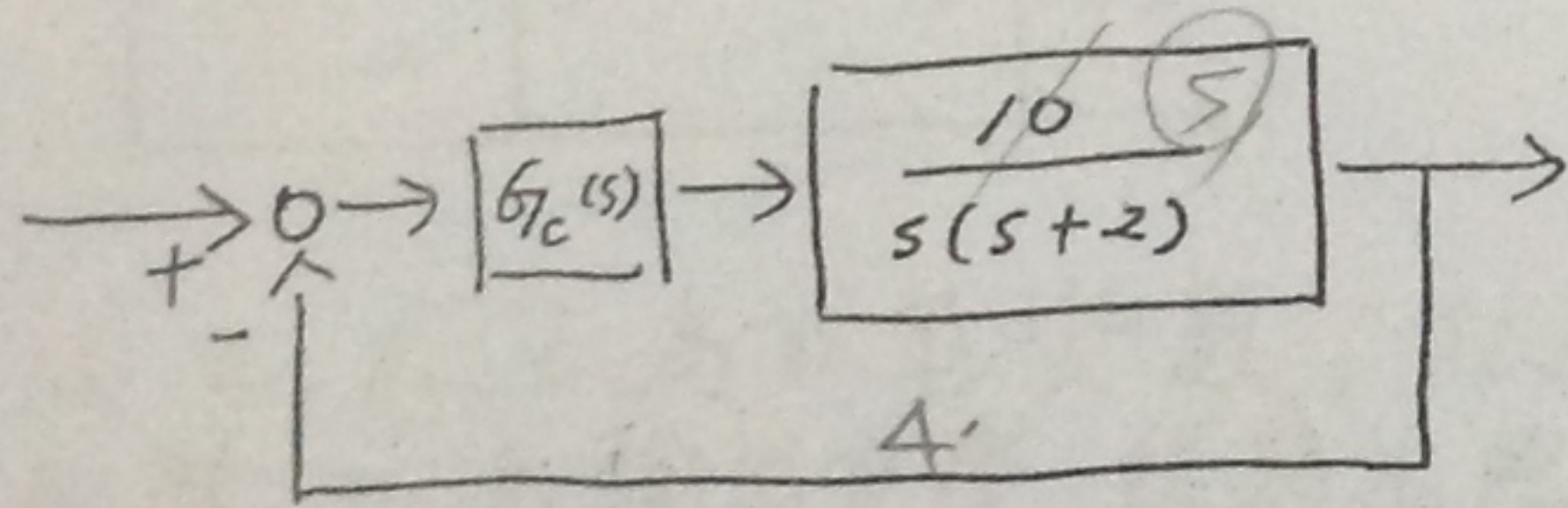
(b) 試寫出 phase lag compensator 之通式並繪出其 Bode plot. (5分)

(c) 試以頻域的觀點, 比較 phase leading compensator 與 phase lag compensator 對閉迴路控制系統暫態性能之影響。(5分)

phase lag: gain ↑, ess ↓

leading: PM ↑ ⇒ 暫態佳

2. 考慮下列回授控制系統



$$PM: |oltf(j\omega)|_{\omega=\omega_c} = 1$$

$$\frac{40}{j\omega(j\omega+2)} = \frac{40}{-10^2 + 2j4} = 1$$

$$\frac{40}{\omega(\sqrt{10^2 + 4})} = 1 \Rightarrow \omega = 6.17 \text{ rad/s}$$

$$\angle oltf(j\omega_c) = -90^\circ - \tan^{-1} \frac{\omega_c}{2} = -162.03^\circ$$

$$PM = 180^\circ - 162^\circ = 18^\circ - \text{補 } 30^\circ$$

$$\phi_m = \sin^{-1} \frac{\alpha-1}{\alpha+1}, \alpha=3$$

$$\frac{40}{j\omega_m(j\omega_m+2)} = \frac{1}{5}, \omega_m = 8.31 \text{ rad/s}$$

$$\omega_3 = \frac{\omega_m}{\sqrt{\alpha}}, \omega_4 = \omega_m \cdot \sqrt{\alpha}$$

$$\zeta = \frac{PM}{100} \Rightarrow PM = 45^\circ, \zeta \approx 0.45$$

$$\theta = \cos^{-1} \zeta = 63.4^\circ$$

$$\tan 63.4^\circ = \frac{x}{1} \Rightarrow x = 2$$

3. 同上一題, 試利用 root locus 設計 phase lag Controller. (20分)

④ 試述一線性系統與其 Adjoint system (伴隨系統) 之 stability, Controllability 及 Observability 的關係, 並證明之。(15分)

Linear system

$$\omega_d = \sqrt{1-\zeta^2} \omega_n = 7.84$$

$$\left. \frac{s}{s(s+2)} \right|_{s=-1 \pm 2j} = 1$$

$$\Rightarrow k = \frac{5}{8}$$

$$k_v = \lim_{s \rightarrow 0} s \cdot oltf(s) = \frac{5}{2} \Rightarrow ess/ramp = \frac{1}{k_v} = \frac{2}{5} = 4\%$$

$$G_c(s) = k \frac{s+2}{s+p}, oltf(s) = k \frac{s+2}{s+p} \frac{s}{s(s+2)}$$

$$\sigma_s = -1.5, \sigma_s \approx -4\%, \zeta = \frac{1}{\sqrt{2}}, \zeta = 0.45, \omega_n = 8.89$$



5. 考慮下列系統

$$\dot{x} = \begin{bmatrix} 0 & 1 \\ 7 & -4 \end{bmatrix} x + \begin{bmatrix} 1 \\ 2 \end{bmatrix} u$$

$$y = [1 \quad 3] x$$

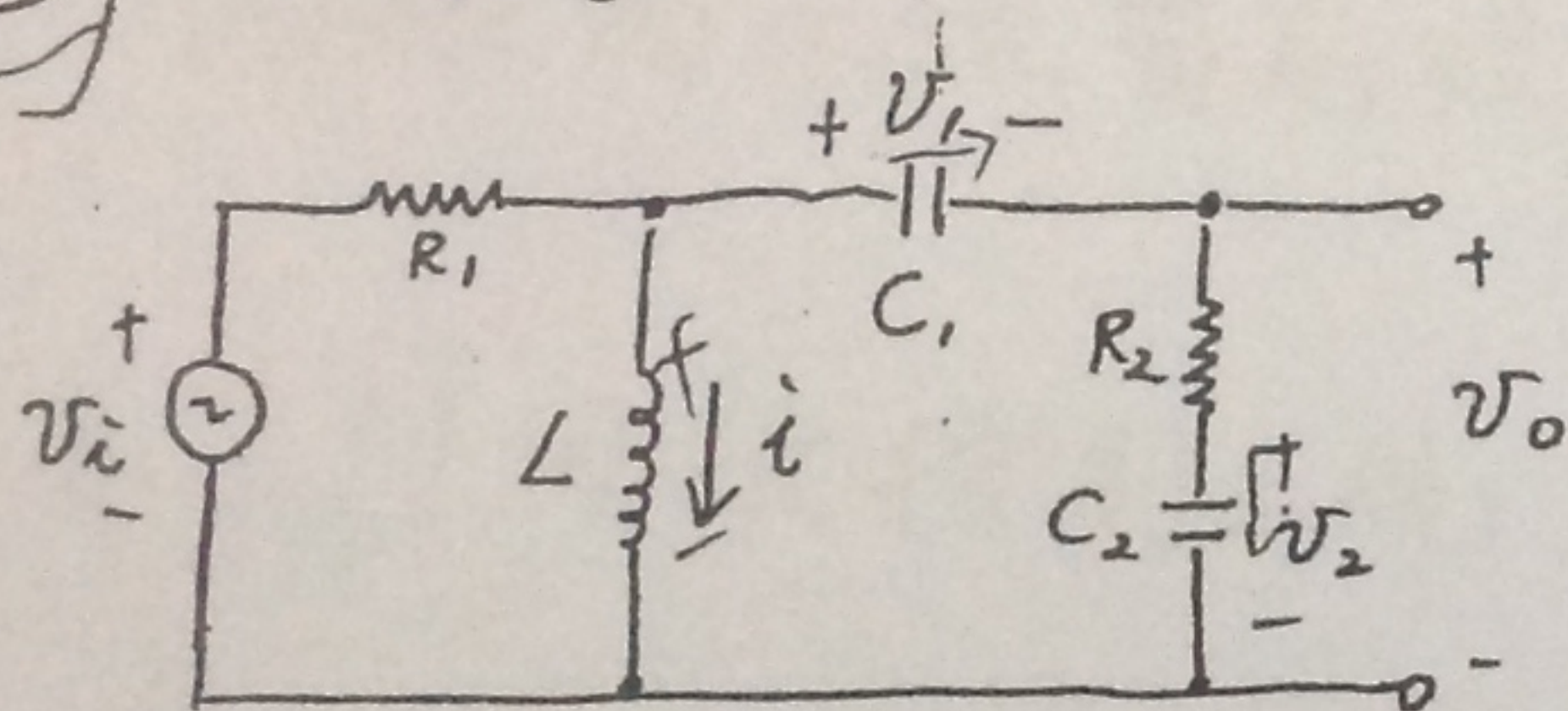
(a) 以積分器為基礎，繪出此系統的方塊圖。(5分)

(b) 令  $A = \begin{bmatrix} 0 & 1 \\ 7 & -4 \end{bmatrix}$  試求  $e^{At} = ?$  (8分)

(c) 試求轉移函數  $\frac{Y(s)}{U(s)} = ?$  (7分)

$$C(sI - A)^{-1}B + D$$

6. (a) 考慮下列電路



以  $v_1, v_2, i$  為狀態變數， $v_i$  為輸入電壓， $v_o$  為輸出電壓，試寫出此系統之狀態空間表示式。(12分)

(b) 轉移函數如下：

$$G(s) = \frac{2s^3 + 11s^2 + 19s + 11}{(s+1)^2(s+2)^2}$$

將上述系統以 Jordan form 表示之。(8分)

$$G(s) = \frac{A}{(s+1)} + \frac{B}{(s+1)^2} + \frac{C}{(s+2)} + \frac{D}{(s+2)^2}$$

$$(s+1)(s+2)^2 A + (s+2)^2 B + (s+1)^2 (s+2) C + (s+1)^2 D$$

$$= A(s^3 + 5s^2 + 8s + 4) + B(s^2 + 4s + 4) + C(s^3 + 4s^2 + 5s + 2) + D(s^2 + 2s + 1)$$

$$= (A+C)s^3 + (5A+B+4C+D)s^2 + (8A+4B+5C+2D)s + 4A+4B+4C+D$$

$$= 2s^3 + 11s^2 + 19s + 11$$

$$x = P^{-1} z$$