

5

⑤ Polar plot of $\left[1 + 2\zeta\left(\frac{j\omega}{\omega_n}\right) + \left(\frac{j\omega}{\omega_n}\right)^2\right]^{-1}$

$$\rightarrow a(j\omega) = \frac{1}{1 + 2\zeta\left(\frac{j\omega}{\omega_n}\right) + \left(\frac{j\omega}{\omega_n}\right)^2}$$

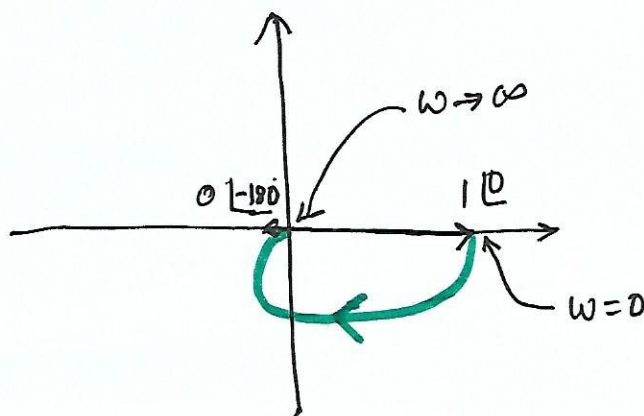
→ When $\omega = 0$, $1 \angle 0$

→ When $\omega \rightarrow \infty$, $0 \angle -180^\circ$

→ Thus the polar plot starts at $1 \angle 0$ and ends at $0 \angle -180^\circ$ as ω increases from 0 to ∞ .

→ The negative real axis is tangent to the high frequency portion of $a(j\omega)$.

→ The values of $a(j\omega)$ in the frequency range of interest can be calculated directly at different values of ω .

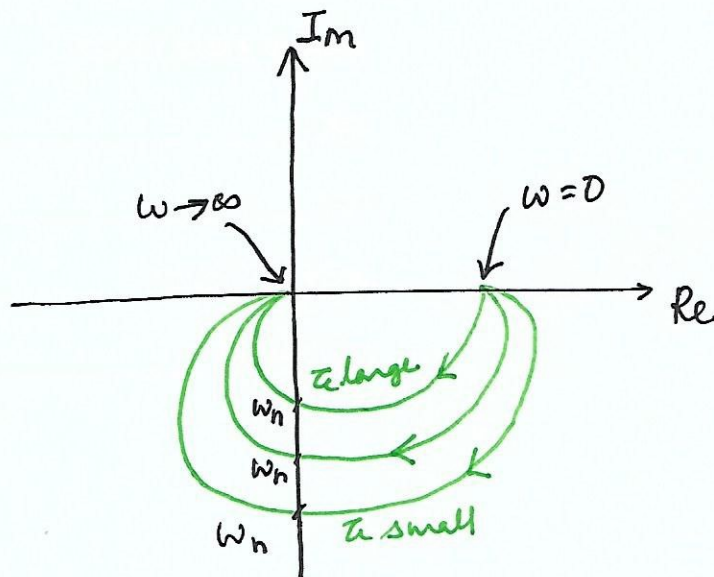


→ The exact shape of the polar plot depends on the value of ζ .

→ For the underdamped case at $\omega = \omega_n$,

$$G(j\omega_n) = \frac{1}{j2\zeta} \quad \text{ie} \quad \frac{1}{2\zeta} \angle -90^\circ$$

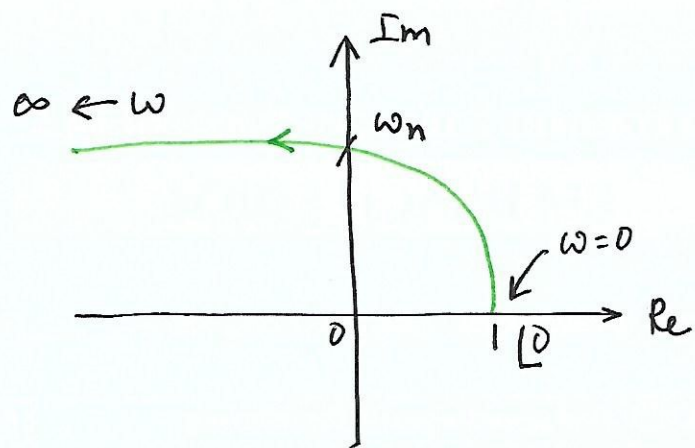
→ Thus the frequency at which the plot intersects the imaginary axis is the undamped natural frequency, ω_n .



⑥ POLAR PLOT OF $\left[1 + 2\zeta \left(\frac{j\omega}{\omega_n} \right) + \left(\frac{j\omega}{\omega_n} \right)^2 \right] + 1$

→ When $\omega = 0$, $\angle 0^\circ$

→ When $\omega \rightarrow \infty$, $\angle 180^\circ$

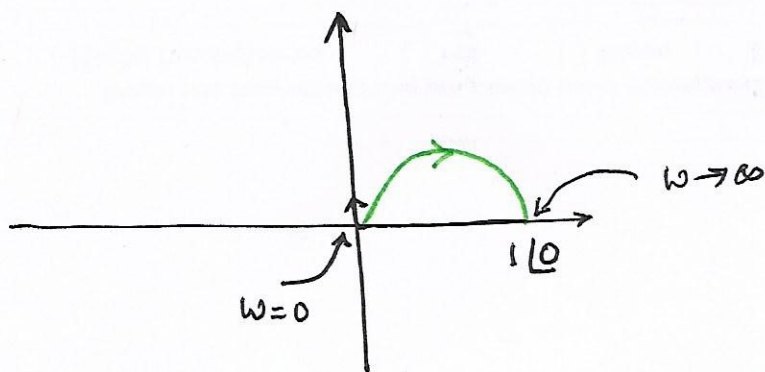


Pb (37) sketch the polar plot of $\frac{j\omega T}{1+j\omega T}$

①

Solution ① When $\omega = 0$, $0 \angle 90$

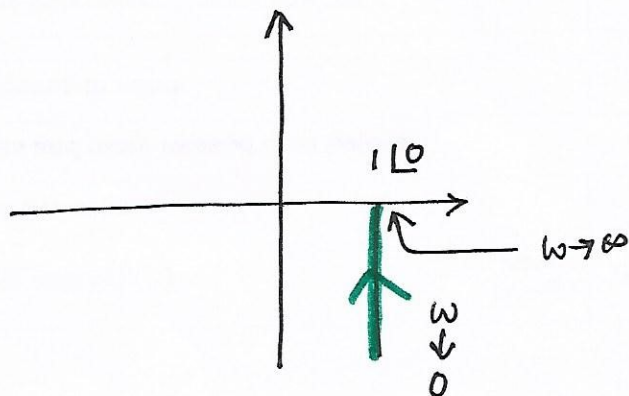
② When $\omega \rightarrow \infty$, $1 \angle 0$



Pb (38) sketch the polar plot of $\frac{1+j\omega T}{j\omega T}$

Solution ① When $\omega = 0$, $\infty \angle -90$

② When $\omega \rightarrow \infty$, $1 \angle 0$



Pb 39

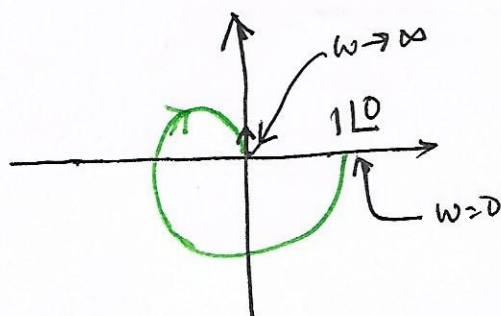
Sketch the polar plot of

$$\frac{1}{(1+j\omega T_1)(1+j\omega T_2)(1+j\omega T_3)}$$

Solution

① When $\omega=0$, $1 \angle 0$

② When $\omega \rightarrow \infty$, $0 \angle -270$



Pb 40

Given the transfer function

$$G(s)H(s) = \frac{10}{s(s+1)(s+2)}$$

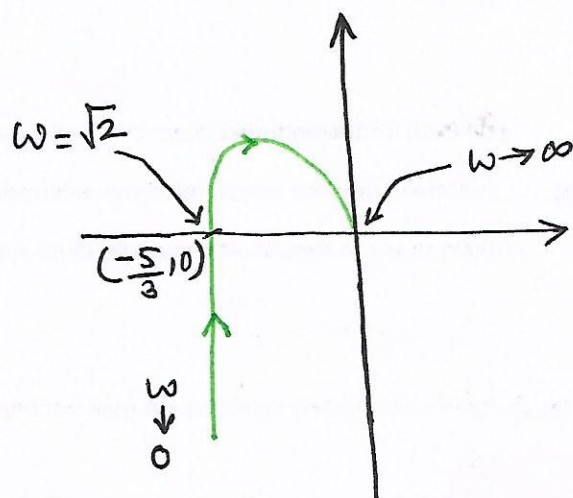
make a rough sketch of the polar plot of $G(j\omega)H(j\omega)$. Does the plot intersect any of the axes? If so, what are the coordinates of the point of intersection?

Solution

$$① \quad G(j\omega)H(j\omega) = \frac{10}{j\omega(1+j\omega)(2+j\omega)}$$

② When $\omega=0$, $\infty \angle -90$

③ When $\omega \rightarrow \infty$, $0 \angle -270$



③ To find the point of intersection of the $a(j\omega)H(j\omega)$ curve on the real and imaginary axis of the $a(j\omega)H(j\omega)$ plane, it has to be rationalized.

$$④ \quad a(j\omega)H(j\omega) = \frac{10(-j\omega)(1-j\omega)(2-j\omega)}{j\omega(1+j\omega)(2+j\omega)(-j\omega)(1-j\omega)(2-j\omega)}$$

$$\begin{aligned} ⑤ \quad a(j\omega)H(j\omega) &= \frac{10(-j\omega - \omega^2)(2-j\omega)}{\omega^2(1+\omega^2)(4+\omega^2)} \\ &= \frac{10(-j2\omega - \omega^2 - 2\omega^2 + j\omega^3)}{\omega^2(1+\omega^2)(4+\omega^2)} \\ &= \frac{-30\omega^2 - j10\omega(2-\omega^2)}{\omega^2(1+\omega^2)(4+\omega^2)} \end{aligned}$$

⑥ Put Imaginary part = 0

$$\frac{-10\omega(2-\omega^2)}{\omega^2(1+\omega^2)(4+\omega^2)} = 0$$

$$\textcircled{1} \quad -10w(2-w^2) = 0$$

$$2-w^2 = 0$$

$$w = \pm\sqrt{2}$$

$\textcircled{2}$ The point of intersection with the real axis is found by substituting $w = \sqrt{2}$ in the real part.

$$\textcircled{3} \quad \frac{-30w^2}{w^2(4w^2)(4+w^2)} = 0$$

$$\frac{-30(2)}{2(3)(5)} = \frac{-5}{3}$$

$\textcircled{4}$ The plot intersects the negative real axis at $(-\frac{5}{3}, 0)$

NYQUIST STABILITY CRITERION

①

- ⑧ Nyquist analysis is a graphical procedure for determining absolute and relative stability of closed loop control systems.
- ⑧ For a system with CLTF $\frac{C(s)}{R(s)} = \frac{G(s)}{1+G(s)H(s)}$ to be stable, all the roots of the characteristic equation $1+G(s)H(s)=0$ must lie in the LHSP.
- ⑧ The Nyquist stability criterion is one which relates the open loop frequency response $G(j\omega)H(j\omega)$ to the number of zeros and poles of $1+G(s)H(s)$ that lie in the RHSP.
- ⑧ Nyquist stability criterion is based on a theorem from the theory of complex variables.
- ⑧ Consider the following:
- ① Given the OLTF, $G(s)H(s)$, Nyquist Stability Criterion helps to predict about closed loop stability.
 - ② For a closed loop system to be stable, the poles of $\frac{G(s)}{1+G(s)H(s)}$ must lie in the LHSP.
 - ③ In other words the zeros of $1+G(s)H(s)$ must lie in the LHSP.

② If $G(s)$ and $H(s)$ are known individually, we can find CLTF as $\frac{G(s)}{1+G(s)H(s)}$.

① But if $G(s)H(s)$ is given as a single transfer function, we cannot find out CLTF.

① But we can find $1+G(s)H(s)$ and get information about zeros of $1+G(s)H(s)$.

① The zeros of $1+G(s)H(s)$ are nothing but the closed loop poles.

→ ③ The poles of $G(s)H(s)$ and the poles of $1+G(s)H(s)$ are the same.

$$\text{eg } G(s)H(s) = \frac{K(s+1)}{(s+2)(s+3)(s+4)}$$

$$1+G(s)H(s) = \frac{(s+2)(s+3)(s+4) + K(s+1)}{(s+2)(s+3)(s+4)}$$