

PHOTOSTAT AND BOOK CENTER ADDRESS

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(PHOTOSTAT, BOOK CENTER)

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HIND PHOTOSTAT AND HIND BOOK CENTER

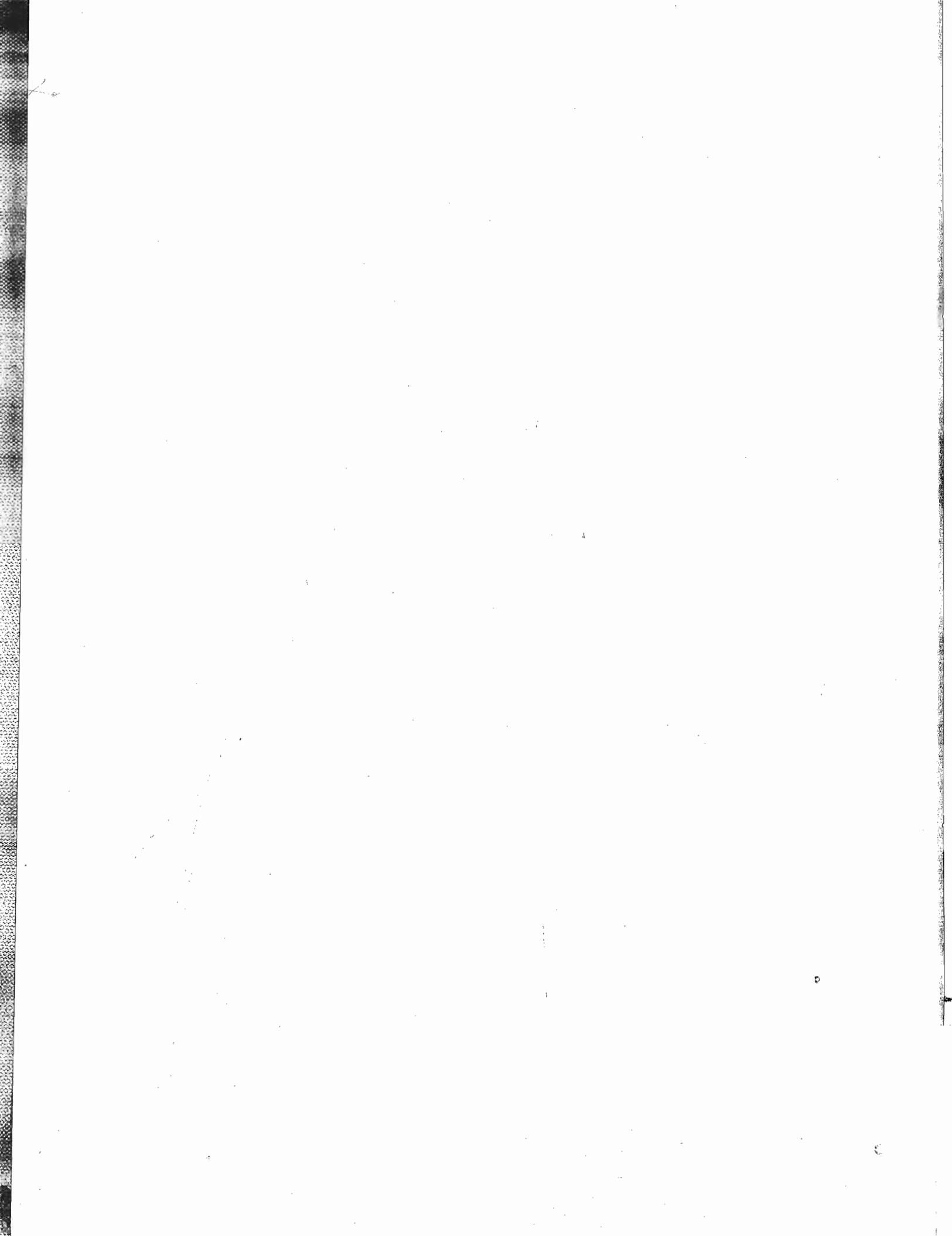
NAME:-.....

SUBJECT:-..... [Control System] NEW.....

INSTITUTE:-..... By Gopal Sir.....

PLEASE CONTACT FOR:-

- **PHOTOSTAT (LASER DIGITAL)**
- **PRINT OUT FROM COMPUTER**
- **SPIRAL BINDING, HARD BINDING**
- **TEST PAPER FOR PSU, GATE, IES**
- **ALL NOTES AVAILABLE**
- **ALL BOOK AVAILABLE**



BASICS OF CONTROL SYSTEMS

* Open Loop system:

- In case of Open Loop system, its final point is undefined. We give some input and corresponding to that input, output is coming which is not pre-defined, it is behaviour of open loop system.

* Closed Loop system:

- Here, final point is defined and system will try to achieve that final point.

* In case of open loop systems, its location of Pole is independent of any parameter while in case of closed loop systems, its location of pole is parameter-dependent and under specific condition, There is possibility that pole can lie on Right-Half of Imaginary-axis.

So, Open Loop system is more stable than Closed Loop System.

* Zero in any system only changes the output response. Zero won't affect the stability of the system.

* Due to Pole, exponential terms exist in the output response and if after settling time, exponential terms are 0, then that system will be Stable System otherwise Unstable System.

• If exponential terms do not exist in output Response, only Sinusoidal terms exist, then system is Marginally Stable System.

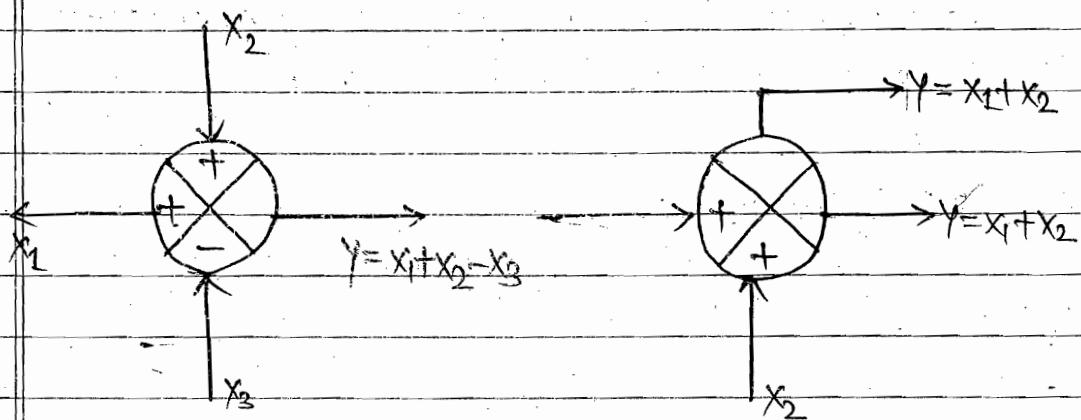
* If pole locates on Left-half of s-plane, then exponential terms will settle after t_s and that system will be Stable.

* If pole locate itself in Right-half side, exponential terms will not settle after t_s and so, system will be Unstable.

BLOCK DIAGRAM AND SIGNAL FLOW GRAPH

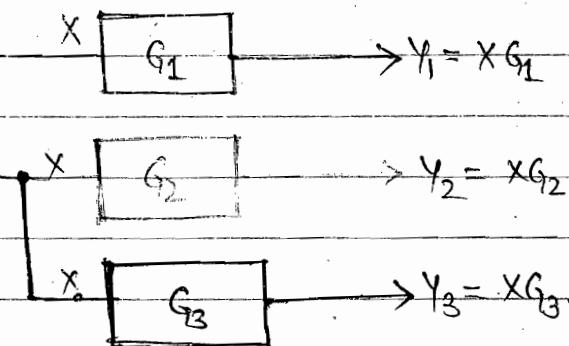
* BLOCK DIAGRAM:

* Summation Point:



* Take-off Point:

- When two different systems require common input, in that case, we will use Take-off point and from equipotential line, we can take infinite number of Take-off points.



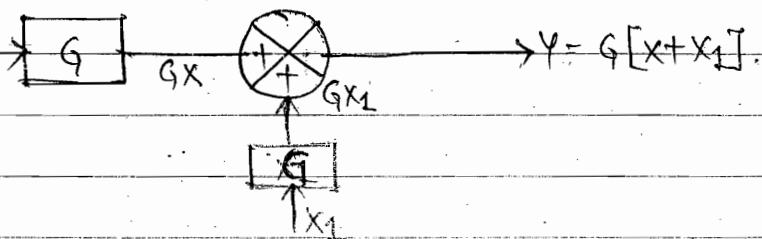
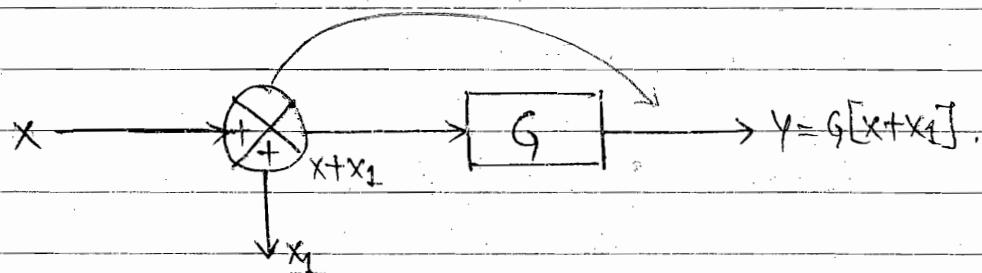
* Forward Gain:

- In case of Forward Gain, direction of flow is from input towards output and Transfer function is Ratio of output with respect to input.

Under specific condition, a Closed Loop system can act as Forward Gain but it will never act like feedback gain.

Case-I

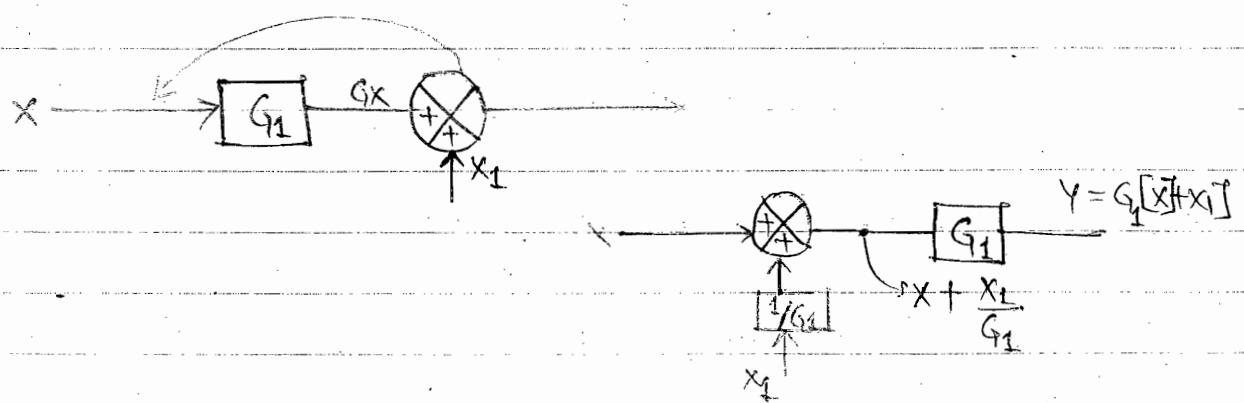
- To move summation on other side of Take-off point in direction of flow.



- To do this, Gain term (G) will be introduced at its second input.

Case-II

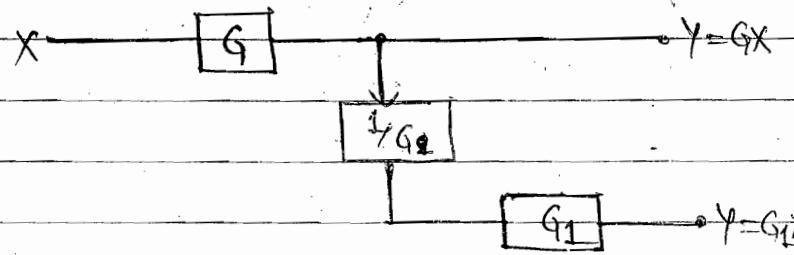
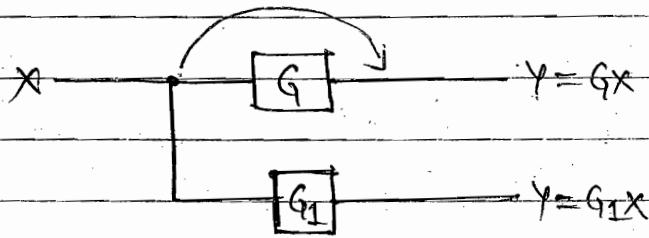
- To move summation on other side of Take-off point in direction opposite to that of flow.



- Inverse of Gain term ($\frac{1}{G}$) will be introduced at its second input.

Case-III

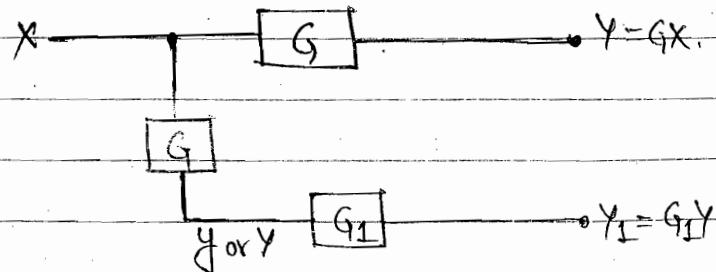
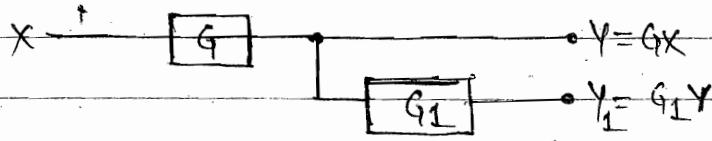
- ** To move take-off point on other side of Gain in the direction of flow:



- Inverse of Gain term will be introduced at take-off point.

Case-IV

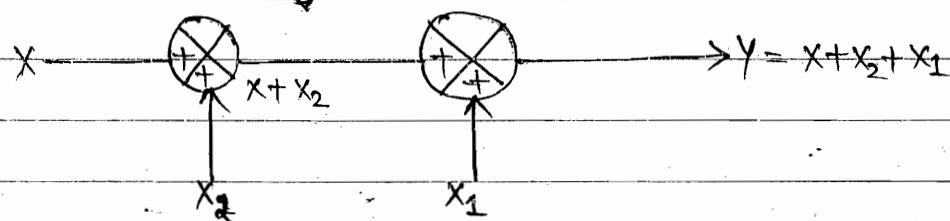
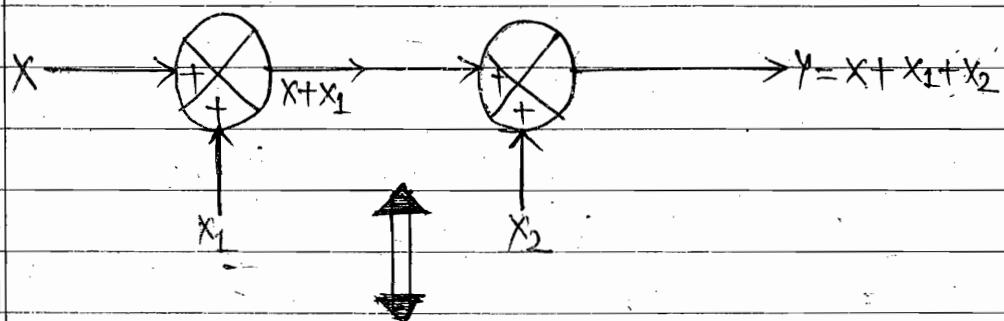
- ** To move take-off point on other side of Gain in the direction opposite to that of flow:



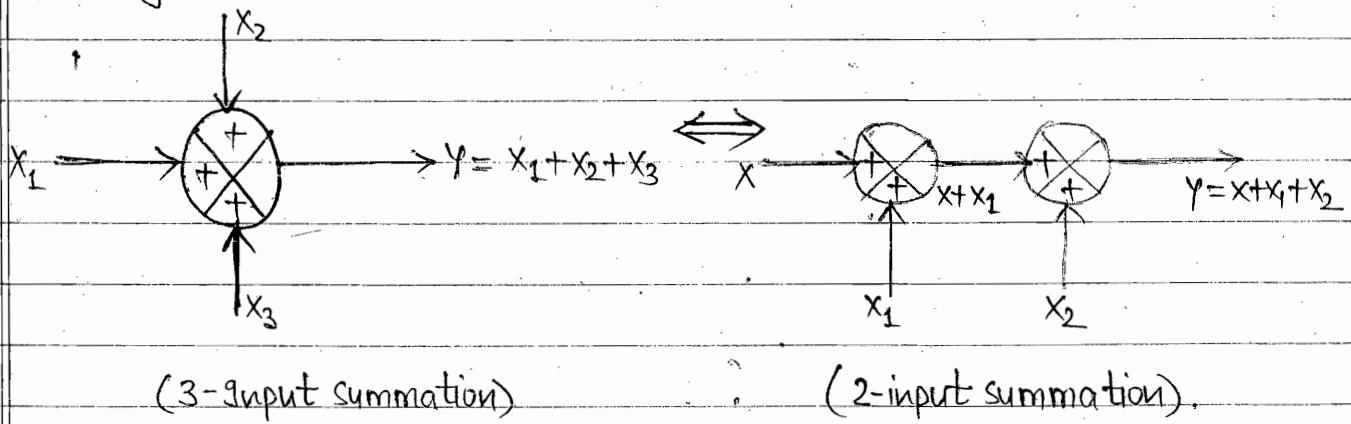
- Gain term (G) will be introduced at Take-off point.

* → Key Factors in Solving Block Diagrams ↴

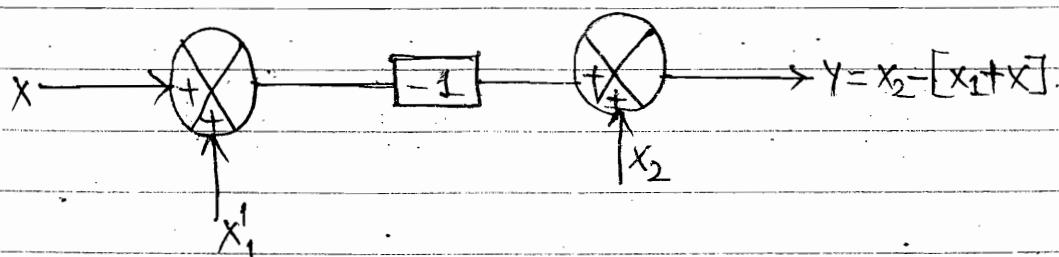
- (i) Always try to bring two summation side by side and if required, interchange their respective inputs.



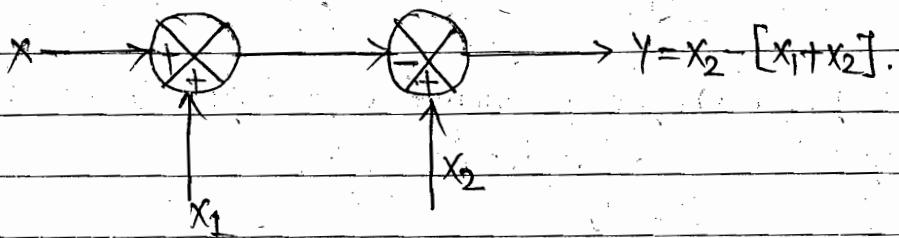
- (ii) Always convert single three-input summation into two 2-input summation side by side.



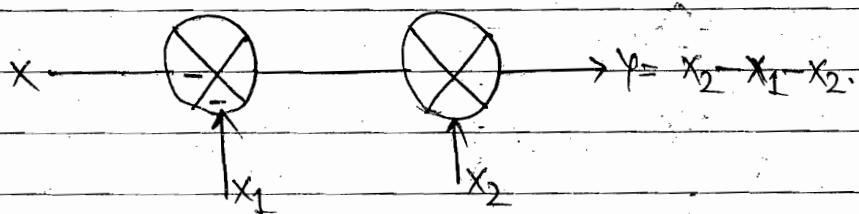
• Further :→



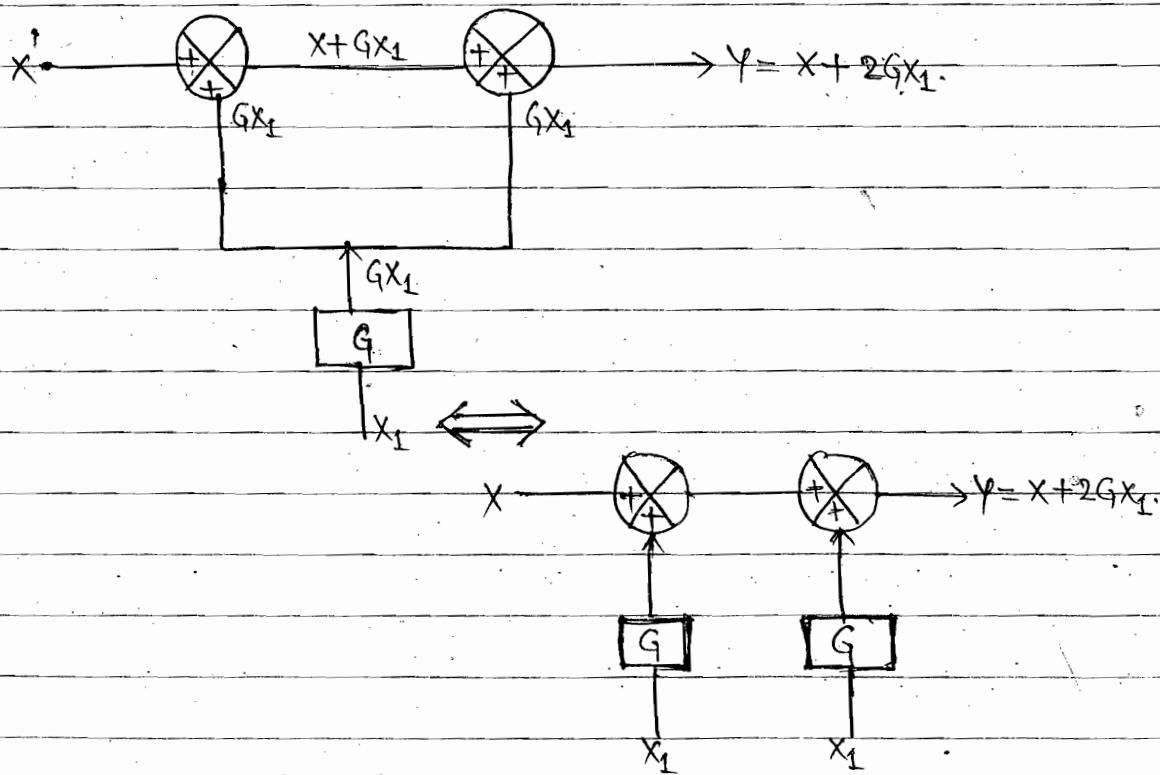
so, it is equivalent to:



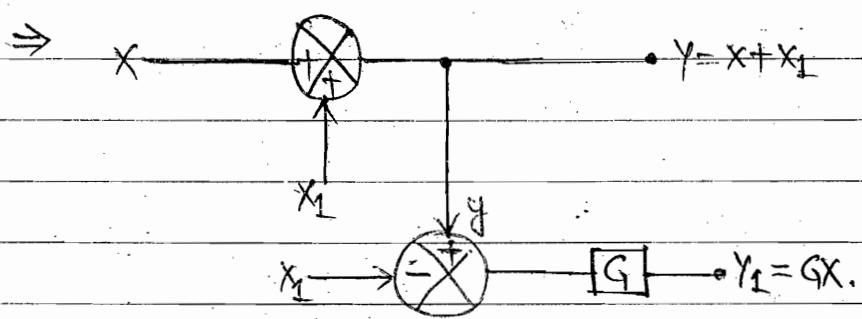
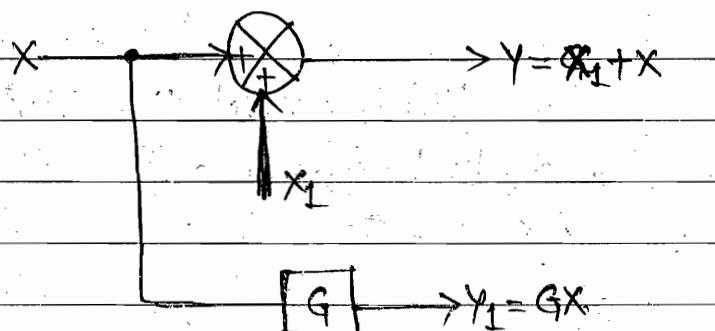
similarly,



- (ii) If any path is common between two summation, we can break that path into two parallel paths.

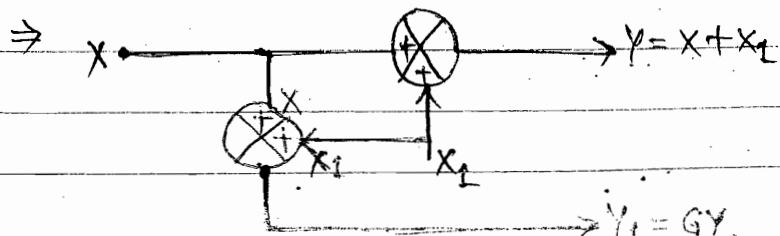
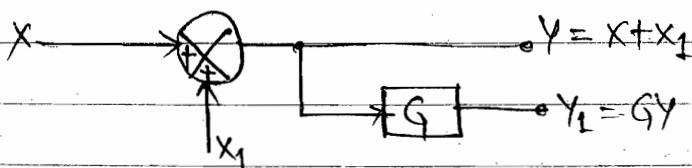


** To move Take-off point on other side of summation in the direction of flow: ↴



- Second summation will be introduced at take-off point and second input of that summation will be same as that of first summation but in Reverse Polarity.

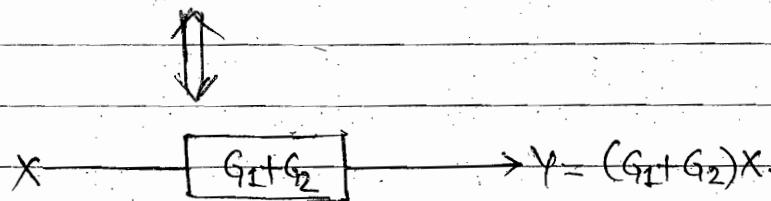
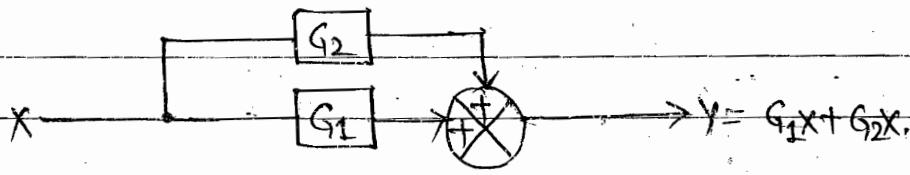
** To move Take-off point on other side of summation in opposite direction to flow: ↩



- Hence, a second summation will be introduced at take-off point whose second input will be same as second input of first summation with same polarity.

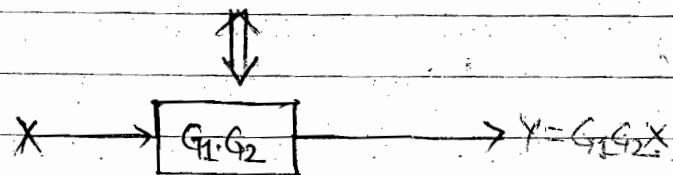
Gain connected in Parallel:

- For two gains to be connected in parallel, their input should be same, summation should be common and direction of flow should be same, then overall gain will be: Sum of two gains.



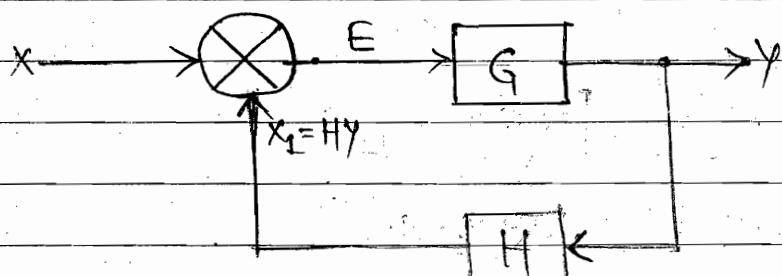
Gain connected in Cascade:

- For two gains to be connected in cascade, output of one should be input to other gain. So, overall gain will be: Product of two gains.



* * Closed Loop Systems

(i) Negative feedback Closed Loop System :



$$\text{Here, } E = X - X_f = X - HY.$$

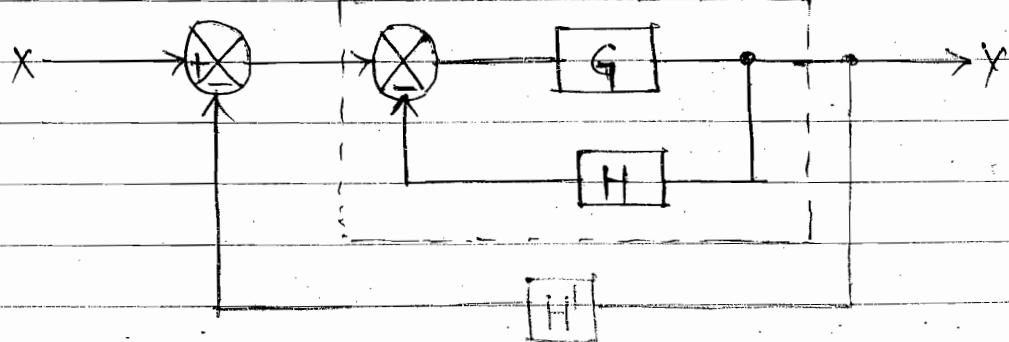
$$\therefore Y = GE = G(X - HY).$$

$$\Rightarrow Y = GX - GHY \Rightarrow Y(1 + GH) = GX.$$

$$\boxed{\frac{Y}{X} = \frac{G}{1+GH}} *$$

Or, $X \rightarrow \boxed{\frac{G}{1+GH}} \rightarrow Y = \frac{G \cdot X}{(1+GH)}$

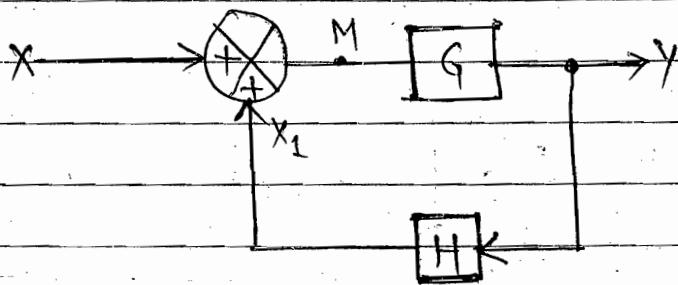
Also,



$$\boxed{\frac{Y}{X} = \frac{G}{1+G(H+H')}} *$$

(ii) Positive feedback closed loop system

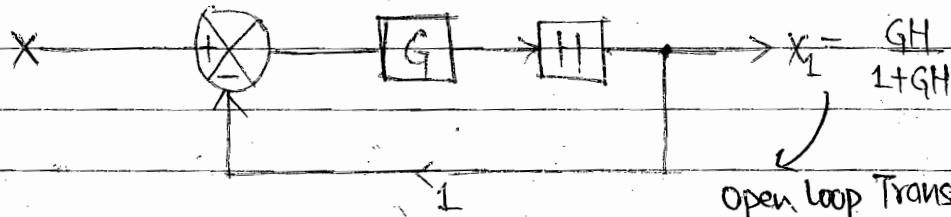
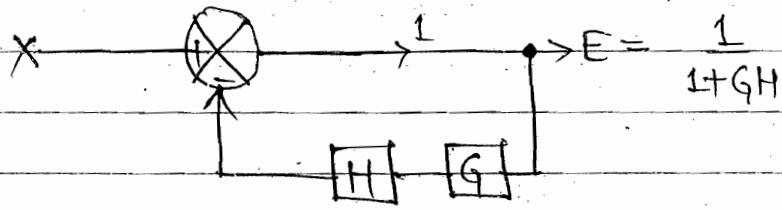
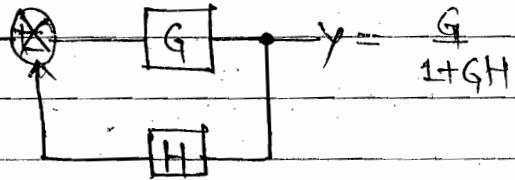
- It acts as Mixer.



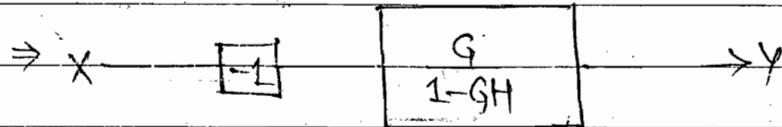
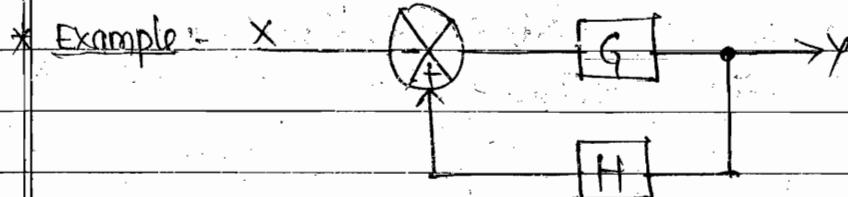
$$X_1 = HY \Rightarrow X + X_1 = M.$$

$$\therefore \boxed{\frac{Y}{X} = \frac{G}{1-GH}} *$$

*Example:-



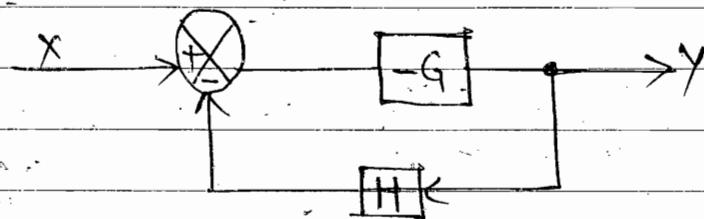
Open loop Transfer Function.



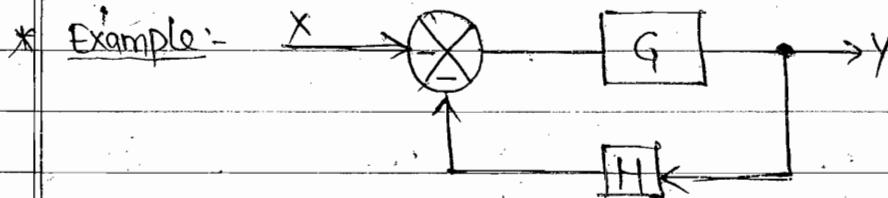
$$\therefore \frac{Y}{X} = \frac{-G}{1-GH}$$

* so, Given system uses Positive Feedback.

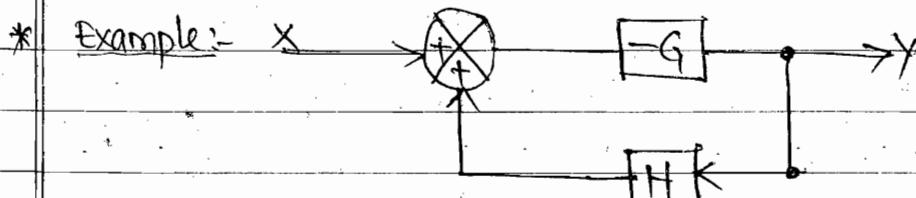
* Example:-



$$\Rightarrow \text{Here, } \frac{Y}{X} = \frac{-G}{1+(-GH)} = \frac{-G}{1+GH}, \text{ so given system uses Positive Feedback.}$$



$$Y = \frac{-G}{1+GH}, \text{ Hence system uses Negative Feedback.}$$

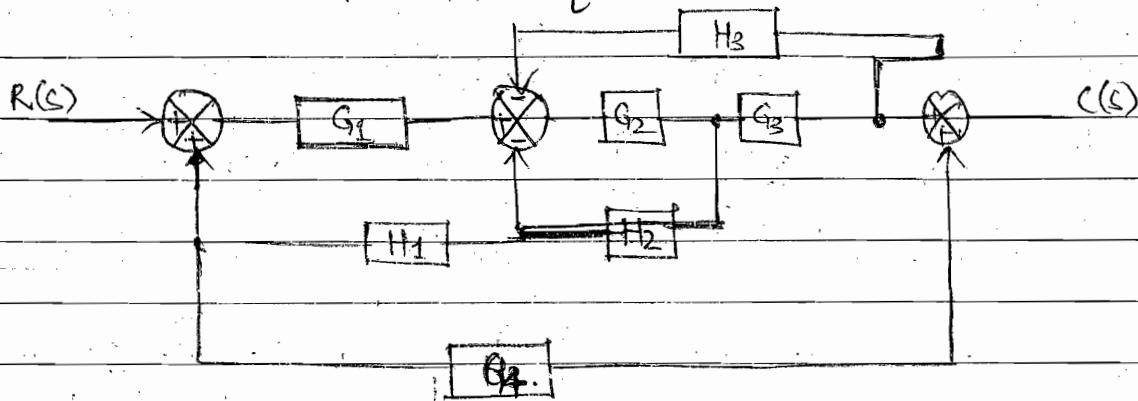


$$Y = \frac{G}{1+GH}, \text{ Hence system uses Negative Feedback.}$$

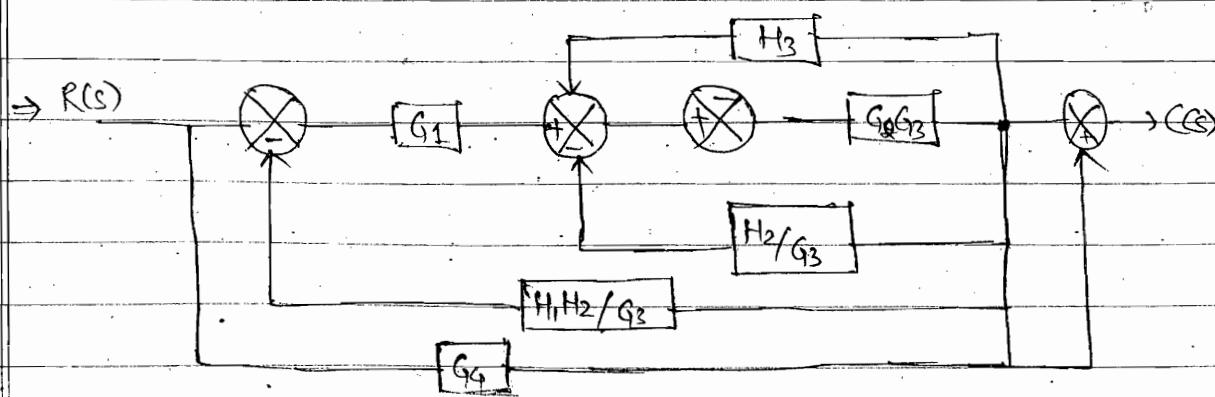
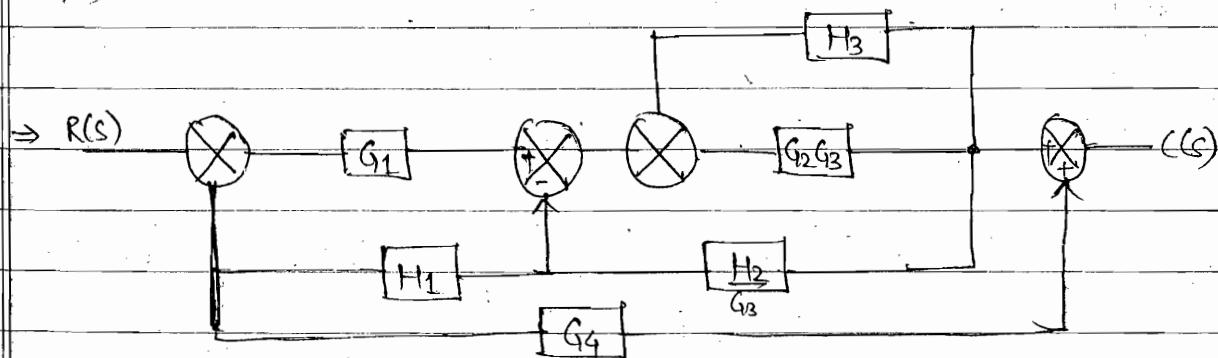
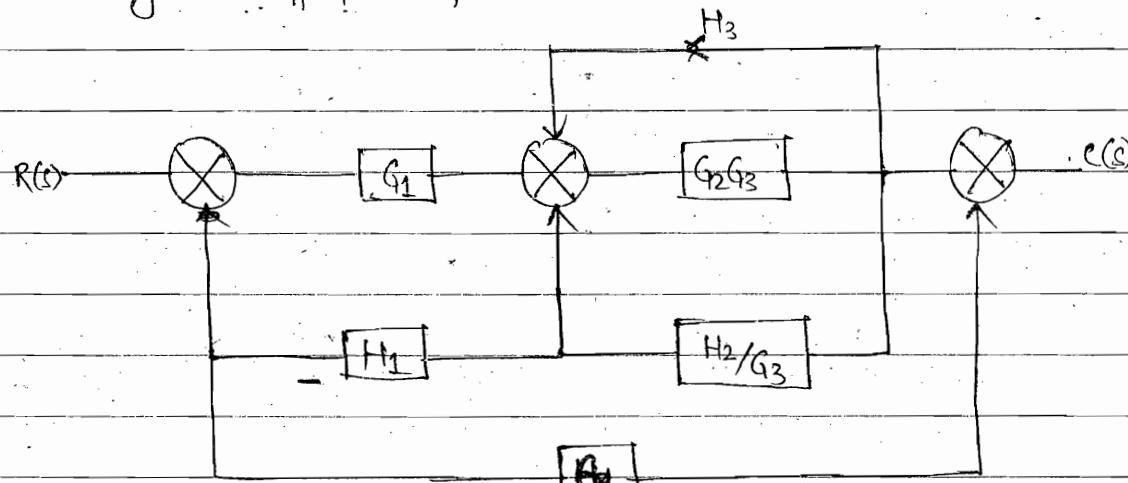
07-20-21

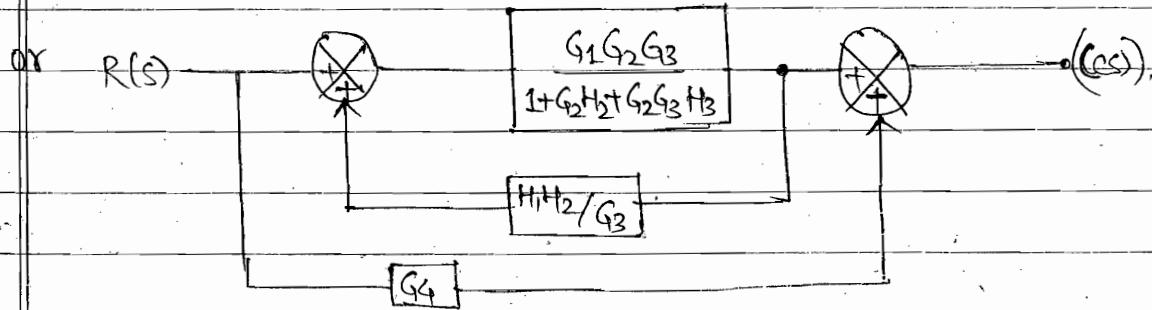
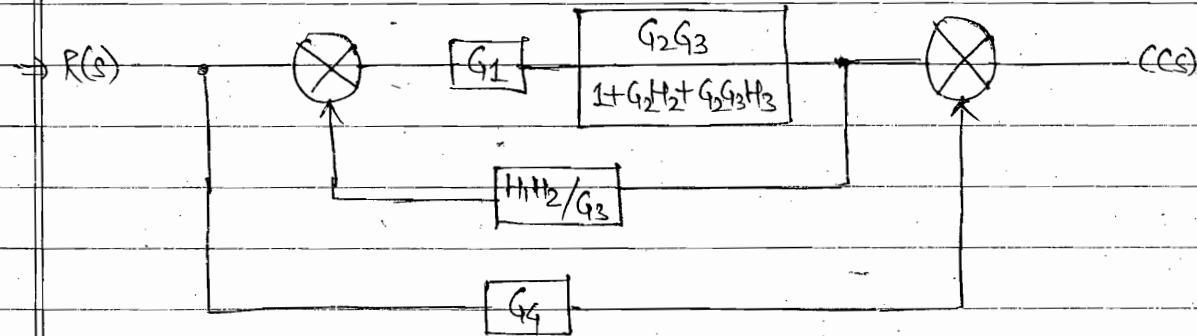
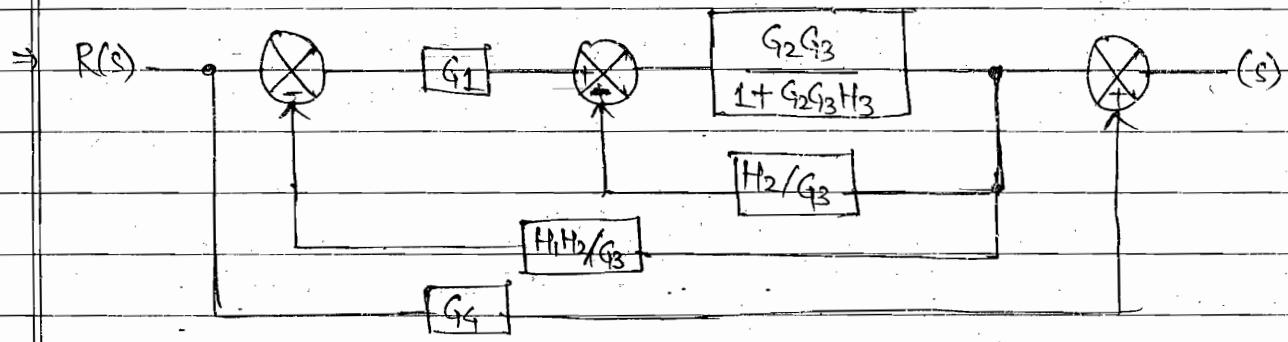
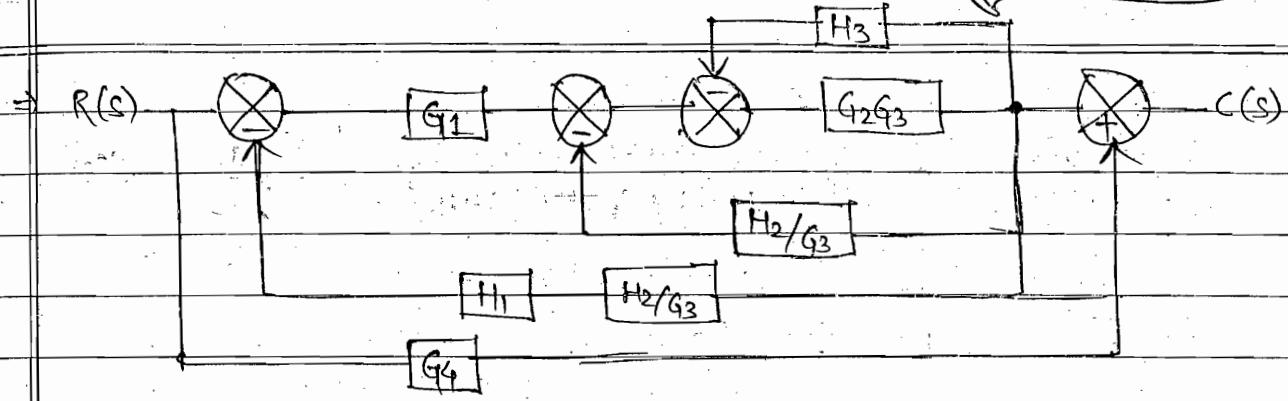
Numericals

Ques: (1) For the given block diagram, calculate transfer function using Block Reduction Technique.

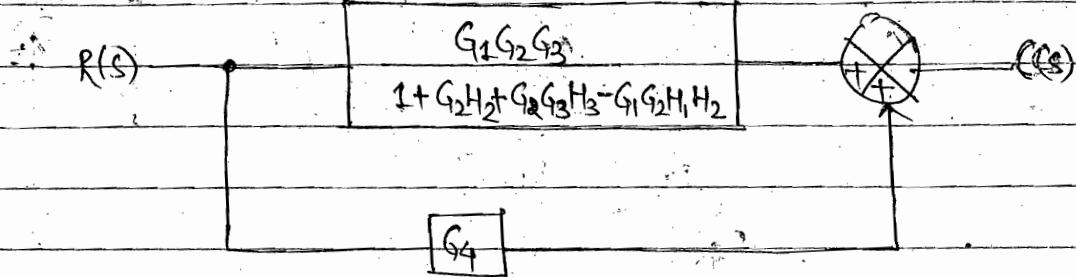


Ans: (1) Taking take-off point forward,





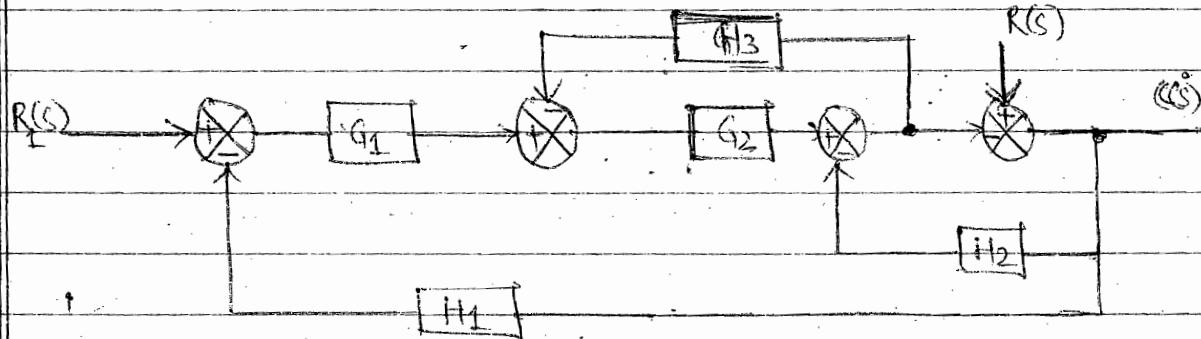
$$\begin{aligned} & \frac{G_1 G_2 G_3}{1 + G_2 H_2 + G_2 G_3 H_3} \Rightarrow \frac{G_1 G_2 G_3}{1 + G_2 H_2 + G_2 G_3 H_3 - G_1 G_2 H_1 H_2} \\ & \frac{1 + (-)G_1 G_2 G_3}{1 + G_2 H_2 + G_2 G_3 H_3} \times \frac{H_1 H_2}{H_1 H_2} \end{aligned}$$



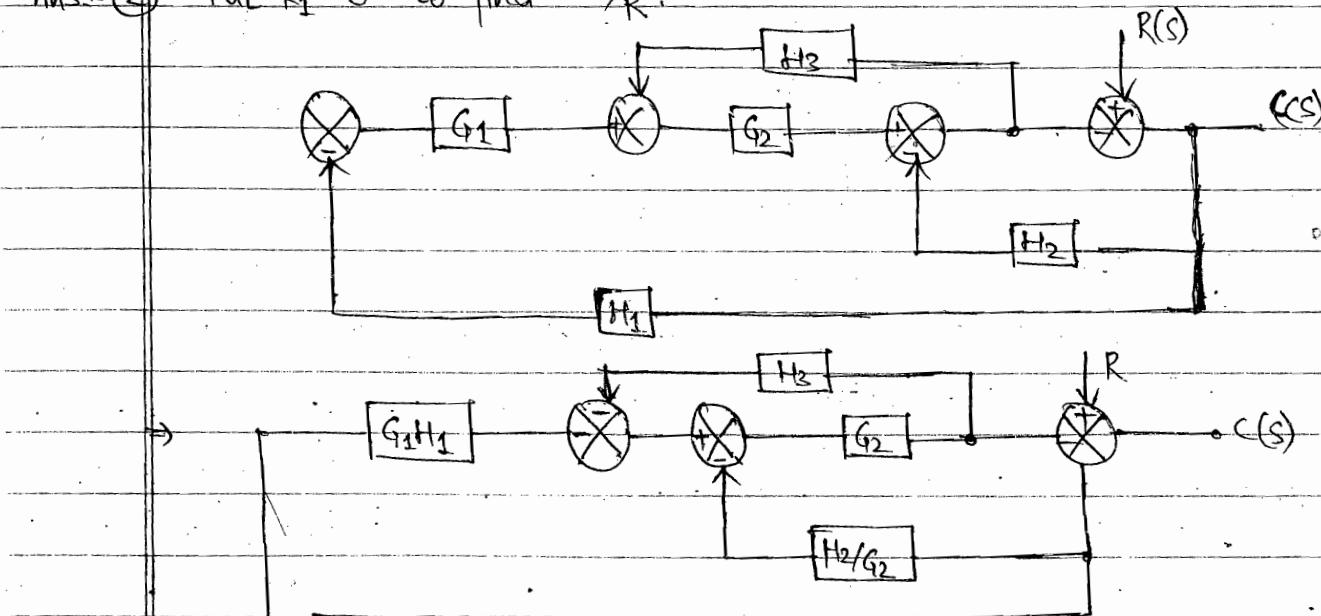
$$\therefore \text{They are in Parallel, Gain} = G_4 + \frac{G_1G_2G_3}{1 + G_2H_2 + G_2G_3H_3 - G_1G_2H_1H_2}$$

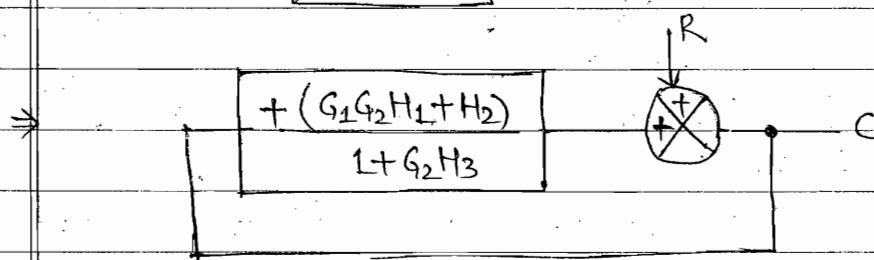
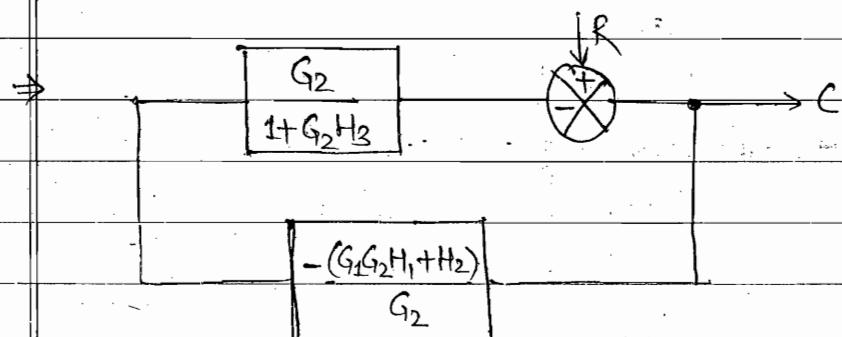
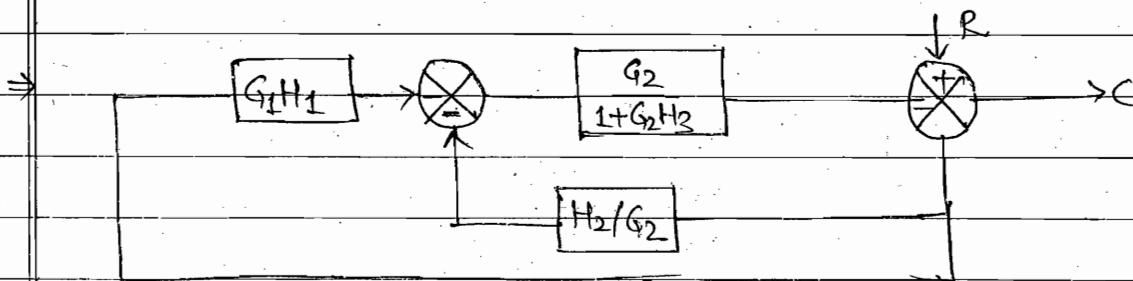
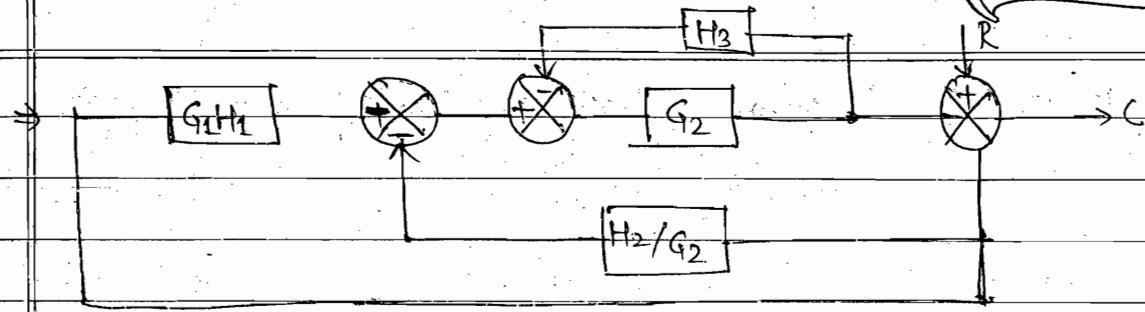
$$\therefore \frac{C(s)}{R(s)} = G_4 + \frac{G_1G_2G_3}{1 + G_2H_2 + G_2G_3H_3 - G_1G_2H_1H_2} *$$

Ques- (2) Obtain transfer function $\frac{C(s)}{R(s)}$ using Block Reduction Technique.



Ans- (2) Put $R_1=0$ to find C_R .

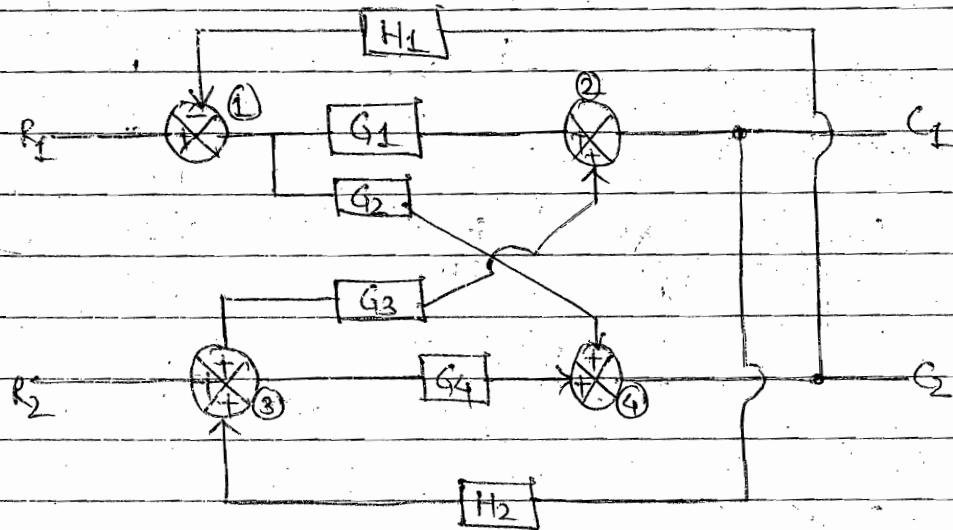




$$\therefore C_R = \frac{1 + G_2 H_3}{1 + G_2 H_3 - (G_1 G_2 H_1 + H_2)}$$

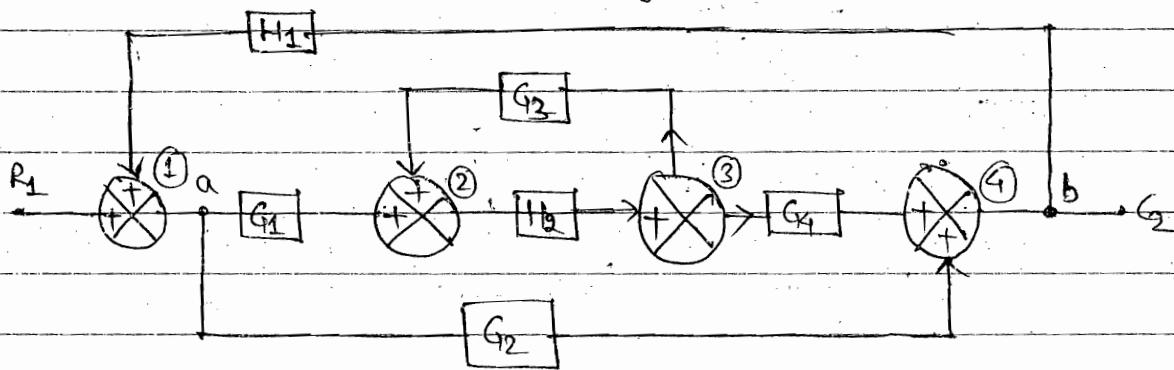
$$\frac{C(s)}{R(s)} = \frac{1 + G_2 H_3}{1 + G_2 H_3 - (H_2) - G_1 G_2 H_1} *$$

Ques(3) calculate $\frac{C_2}{R_1}$ for following block using Block Reduction Technique.

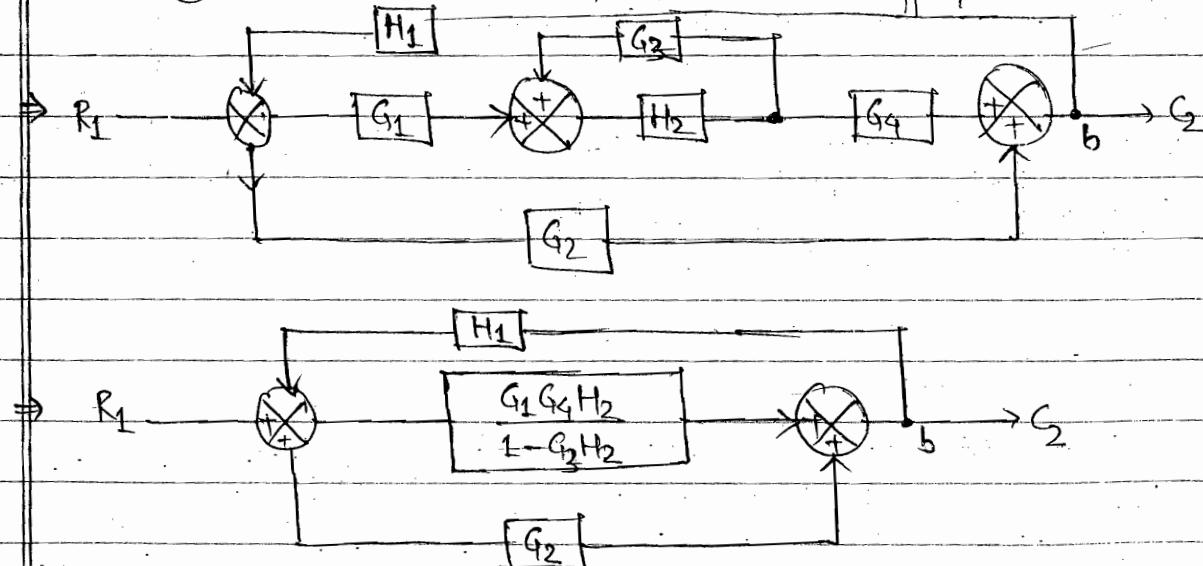


Ans: (3) set $R_2 = 0$, just don't show C_1 .

Converting into linear array of summations,

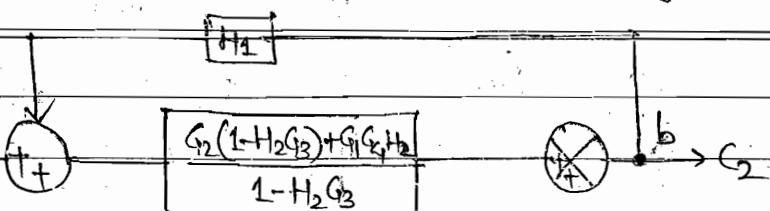


As (3) is not a summation, so, it is Take-off point.



$$\therefore \frac{C_2}{R_1} = G_2 + \frac{G_1 G_4 H_2}{1 - G_3 H_2} \Rightarrow \frac{C_2}{R_1} = G_2 + \frac{G_1 G_4 H_2}{1 - G_3 H_2} *$$

Then, R_1

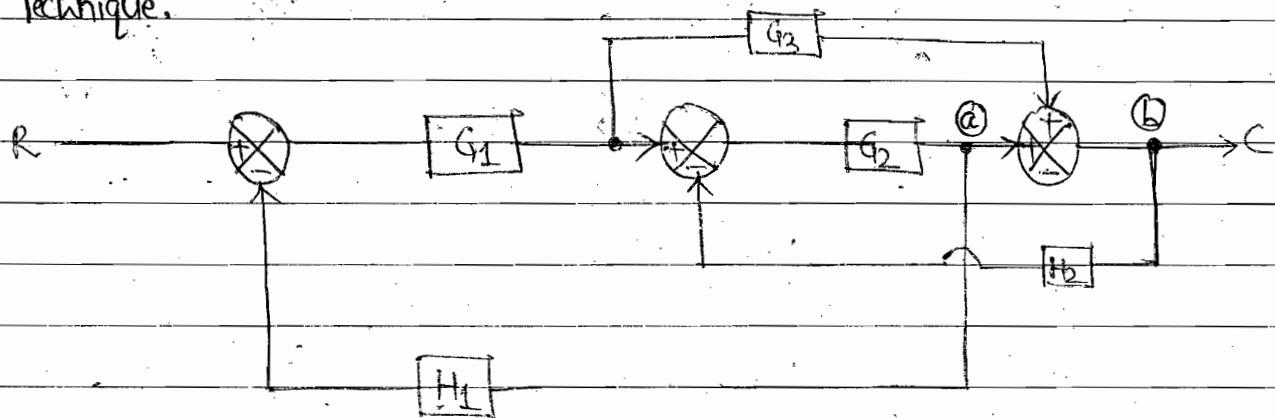


$$C_2 = \frac{G_2(1-G_3H_2) + G_1G_4H_2}{1-G_3H_2 - H_1[G_2(1-G_3H_2) + G_1G_4H_2]} *$$

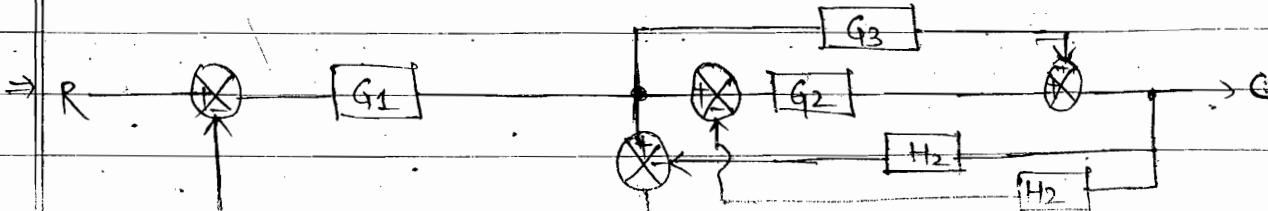
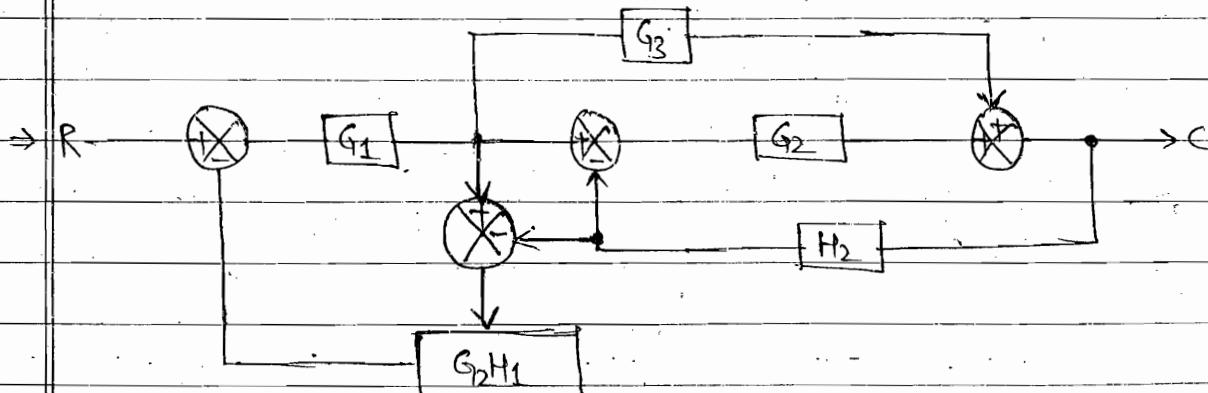
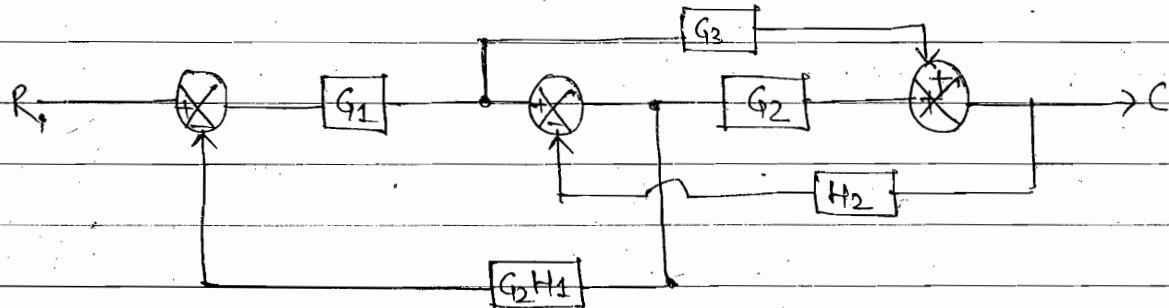
$$\frac{C_2}{R_1} = \frac{1-G_3H_2 - H_1[G_2(1-G_3H_2) + G_1G_4H_2]}{G_2(1-G_3H_2) + G_1G_4H_2}$$

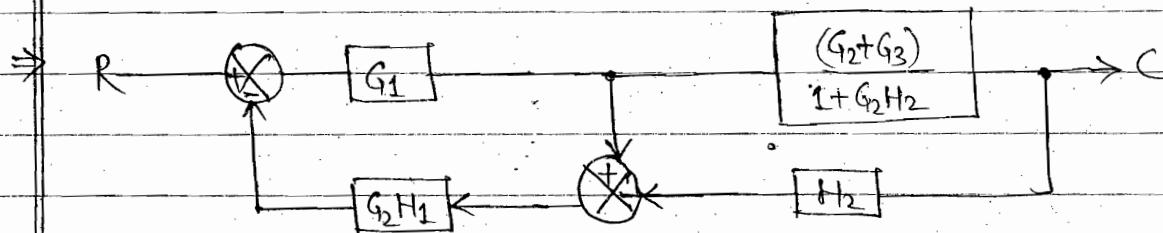
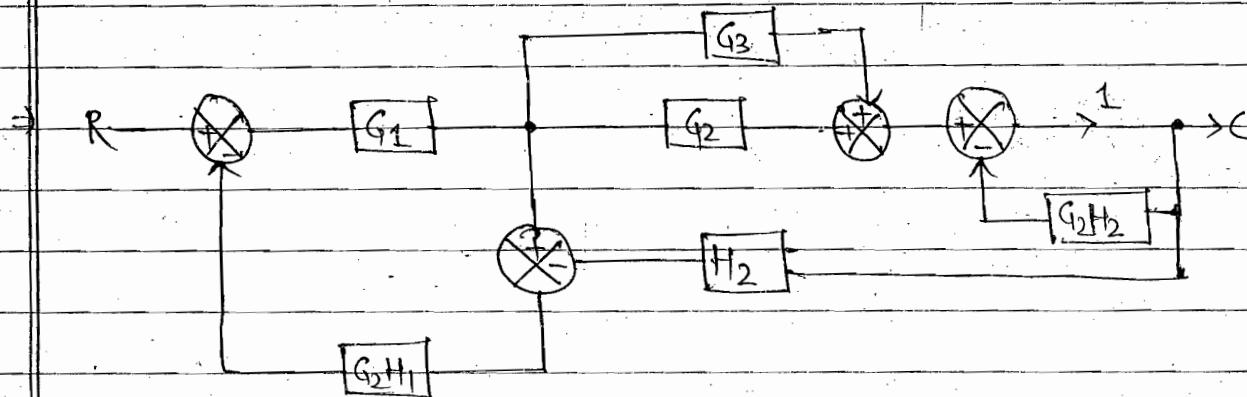
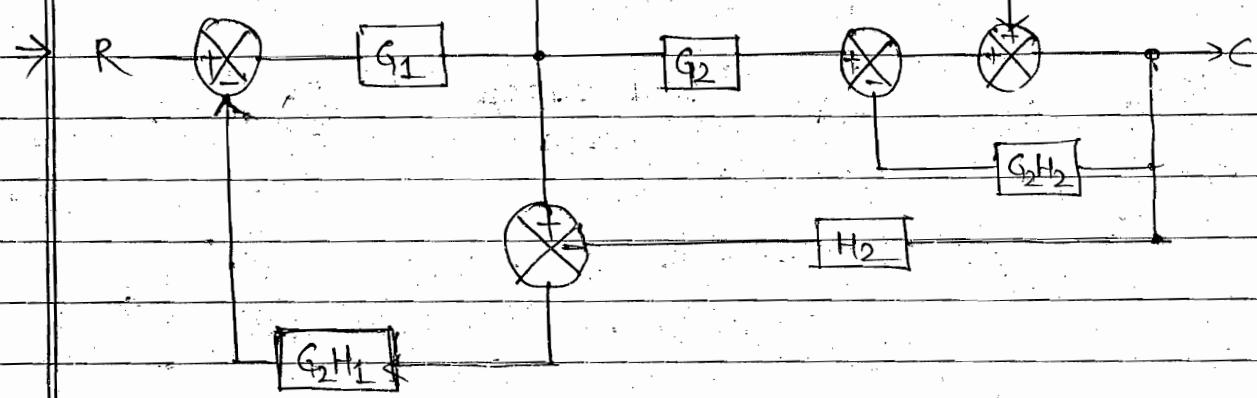
Ques: (4) For the given block, obtain its transfer function S_R using block reduction technique.

Ans: (4)

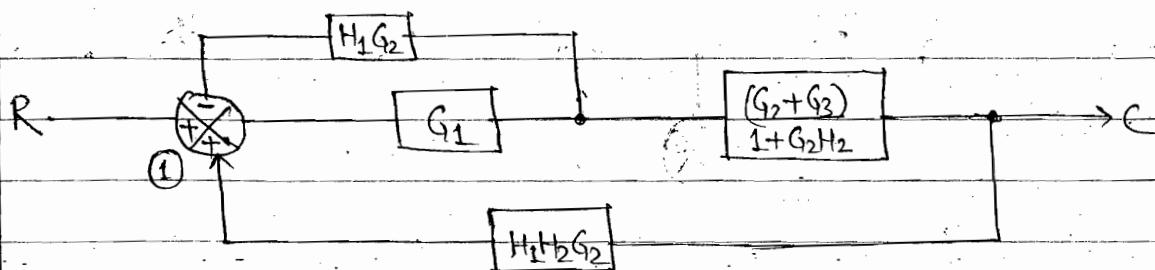
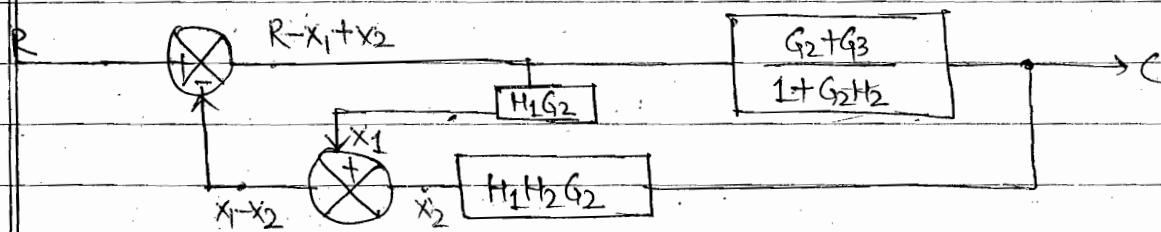


Take point @ before G_2 ,

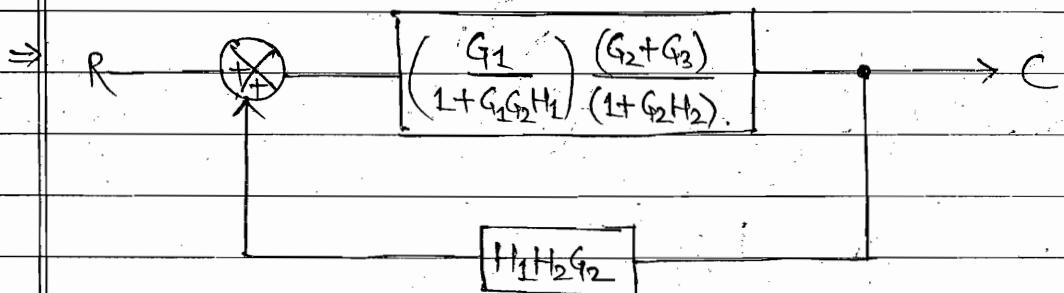
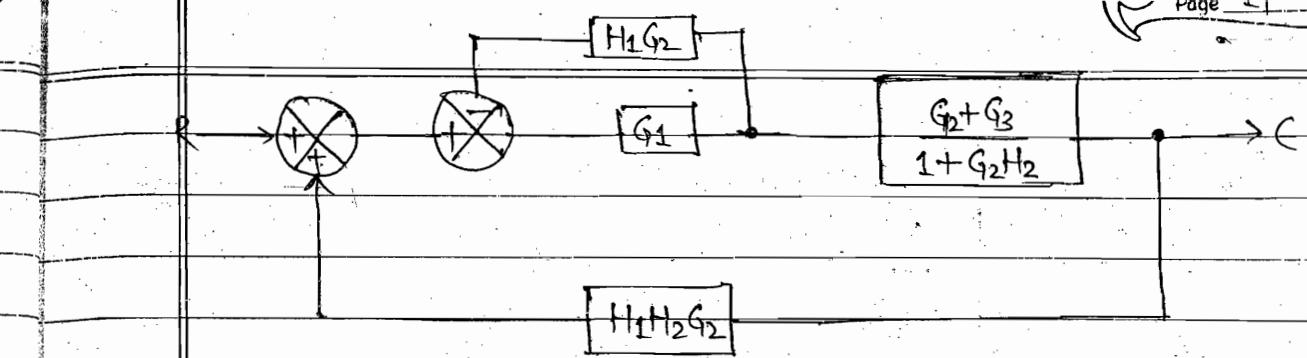




Moving summation before G_{2H_1} ,



• Breaking ① into 2 2-input summation,



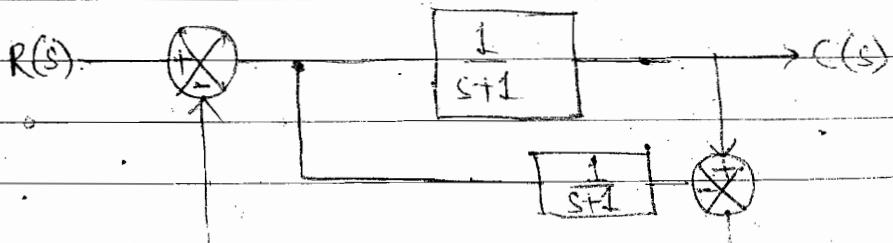
$$\therefore \frac{C_R}{R} = \frac{G_1G_2 + G_1G_3}{1 + G_2H_2 + G_1G_2H_1 + G_1G_2^2H_1H_2} + H_1H_2G_2.$$

$$\Rightarrow \frac{C_R}{R} = \frac{G_1G_2 + G_1G_3}{1 + G_2H_2 + G_1G_2H_1 + G_1G_2^2H_1H_2} \\ 1 - \frac{(G_1G_2 + G_1G_3)}{(1 + G_2H_2 + G_1G_2H_1 + G_1G_2^2H_1H_2)} \times H_1H_2G_2.$$

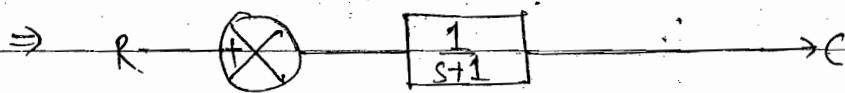
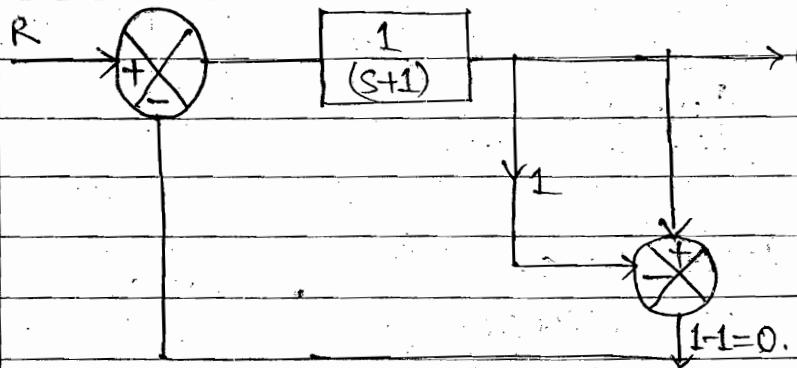
$$\frac{C_R}{R} = \frac{G_1G_2 + G_1G_3}{1 + G_2H_2 + G_1G_2H_1 + G_1G_2^2H_1H_2 - G_1G_2^2H_1H_2 - G_1G_3G_2H_1H_2}$$

$$\Rightarrow \frac{C}{R} = \frac{G_1G_2 + G_1G_3}{1 + G_1G_2H_1 + G_2H_2 - G_1G_2G_3H_1H_2} *$$

Ques: (5) For the given block, obtain its transfer function using block reduction technique.



Ans:- 5



$$C = \frac{1}{s+1} *$$

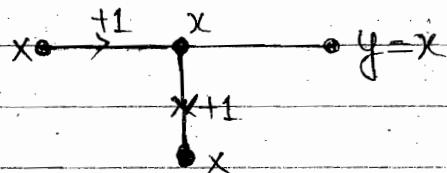
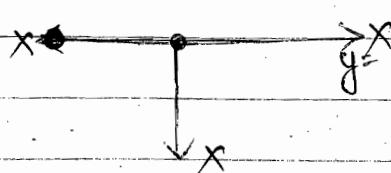
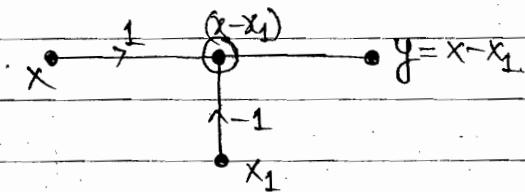
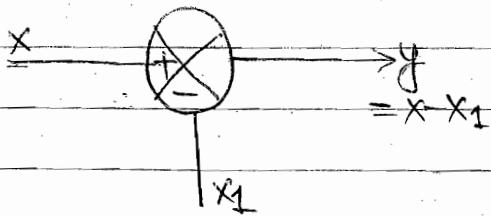
Comparison between Block Diagram and Signal flow Graph

BLOCK DIAGRAM

- Block Diagram is based on Lumped Parameter.
- In lumped Network, Gain exists only at particular point

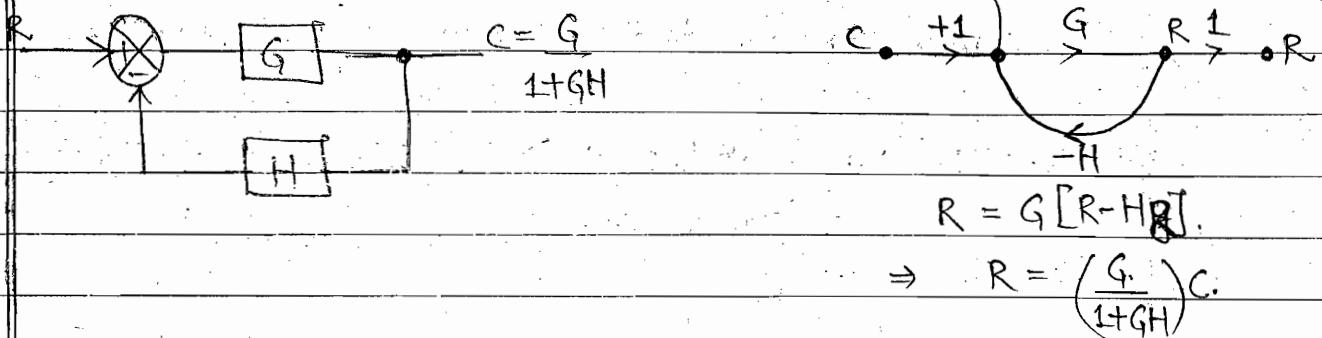
SIGNAL FLOW GRAPH

- Signal flow graph is based on distributed parameter.
- In distributed parameter, Gain is uniformly distributed across the line.

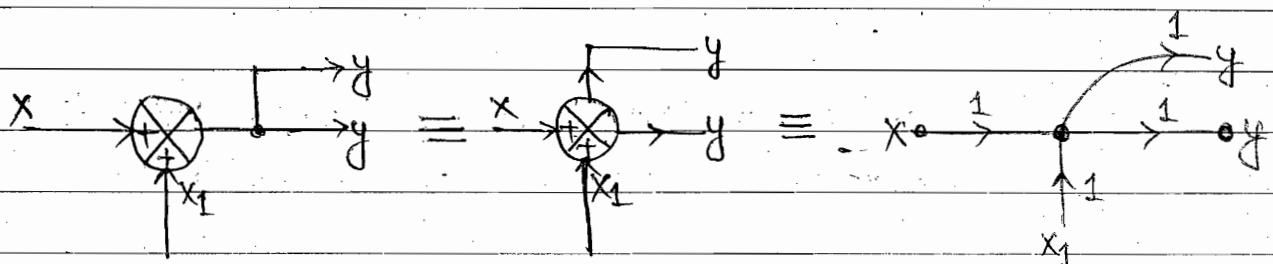


$$y = Gx$$

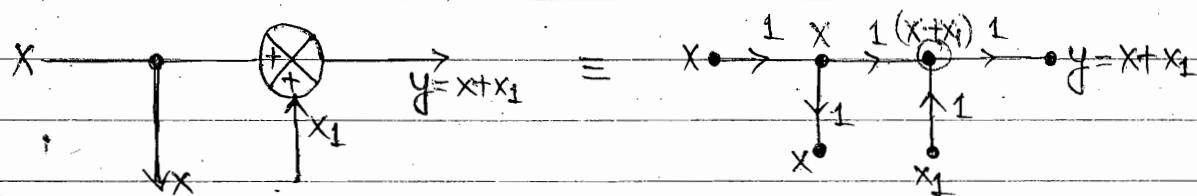
$$y = Gx$$



Case-I :- If summation is followed by Take-off point, we will use single node to represent both summation and take-off point.



Case-II :- If take-off point is followed by summation, we will use two independent nodes, one for take-off point and second for summation.



Date
31-07-14

* MASON'S GAIN FORMULA:

- It is used to calculate Transfer Function using Signal Flow Graph.

- According to Mason's Gain Formula:

$$\frac{Y}{X} = \sum_{k=1}^n \frac{P_k \cdot \Delta_k}{\Delta} *$$

where, n = Total number of Forward path.

P_k = k^{th} forward path.

$\Delta_k = 1 - [\text{sum of non-touching loops to } k^{th} \text{ forward path}] + [\text{sum of product of two non-touching loop to } k^{th} \text{ forward path}] -$

sum of three non-touching loops to k^{th} forward path] + - - -

Que

$$\Delta = 1 - [\text{sum of all loops}] + [\text{sum of two non-touching loops}] \\ - [\text{sum of three non-touching loops}] + - - -$$

\rightarrow Forward Path:

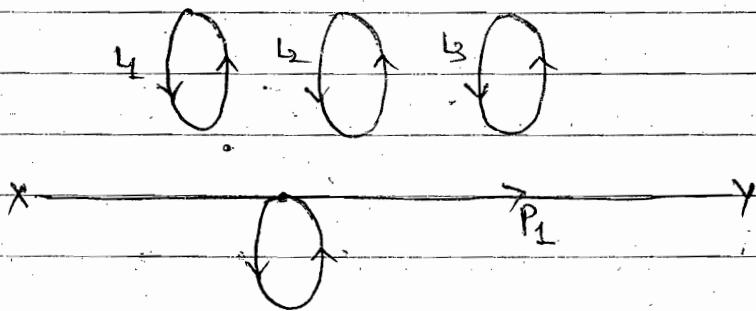
- It is the path which connects input with output and it will be not in loop form.

\rightarrow Loop:

- In case of Loop, origination node itself will be termination node and it won't traverse more than one node twice.

Ans

Example:-



Aus:-

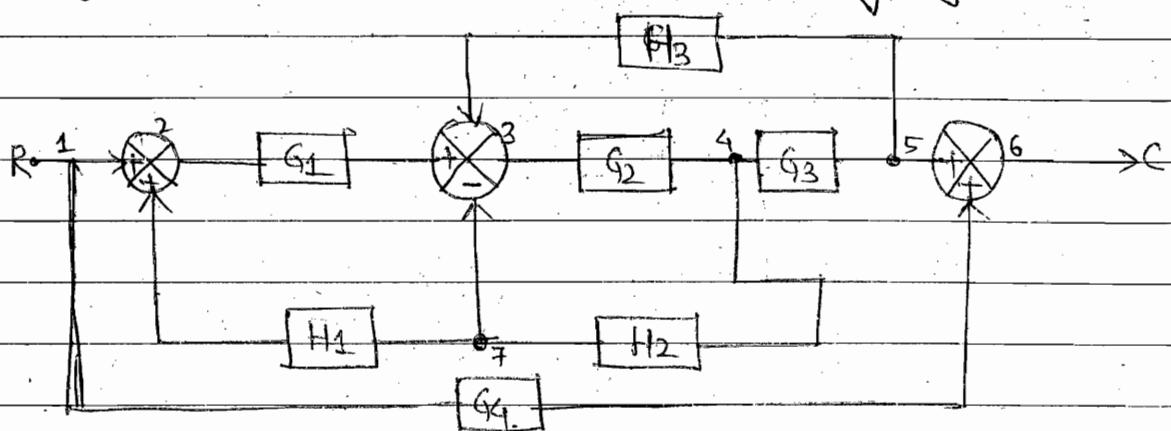
$$\Delta_1 = 1 - [l_1 + l_2 + l_3] + [l_1 l_2 + l_2 l_3 + l_3 l_1] - [l_1 l_2 l_3]$$

$$\Rightarrow \Delta = 1 - [l_1 + l_2 + l_3 + l_4] + [l_1 l_2 + l_2 l_3 + l_3 l_4] - [l_1 l_2 l_3] \\ + l_1 l_4 + l_2 l_4 + l_3 l_4 \\ + l_2 l_3 l_4 + l_3 l_4 l_1 + l_4 l_4 l_2] + l_1 l_2 l_3 l_4$$

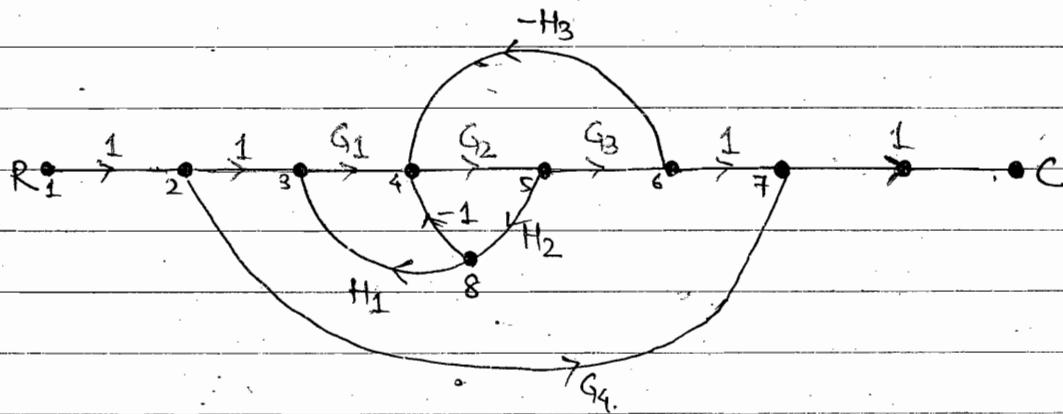
$$\therefore \frac{Y}{X} = \frac{P_1 \Delta_1}{\Delta}, \text{ Use this.}$$

Questions on Signal Flow Graph.

Ques-① For the given block, obtain its transfer function using Signal flow graph.



Ans:- ①



$$P_1 = G_1 G_2 G_3, \quad \Delta_1 = 1 - [0] = 1$$

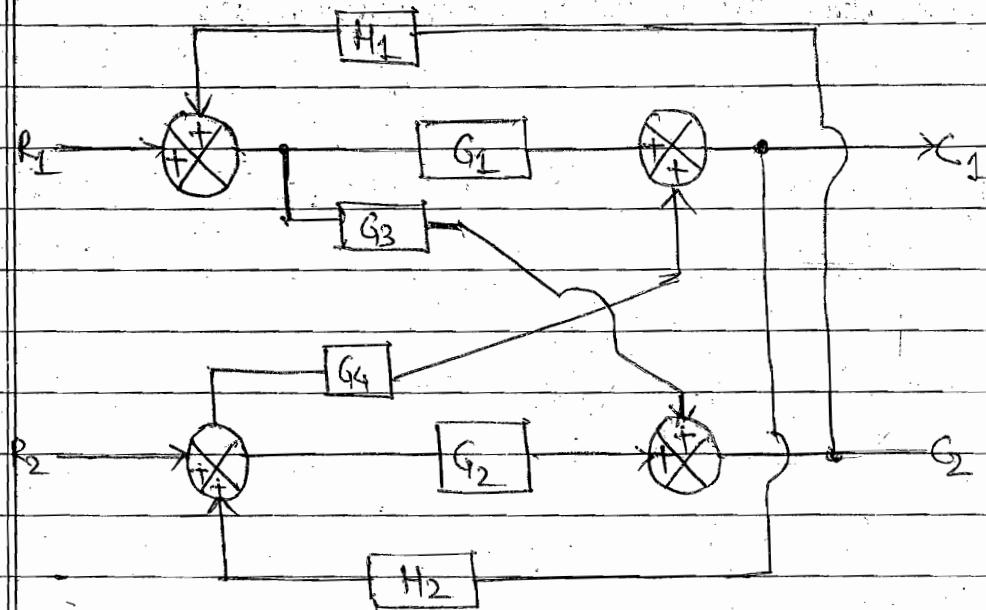
$$P_2 = G_4, \quad \Delta_2 = 1 - [G_1 G_2 H_1 - G_2 H_2 - G_2 G_3 H_3]$$

$$\Delta = 1 - [-G_2 H_2 - G_2 G_3 H_3 + G_1 G_2 H_1 H_2]$$

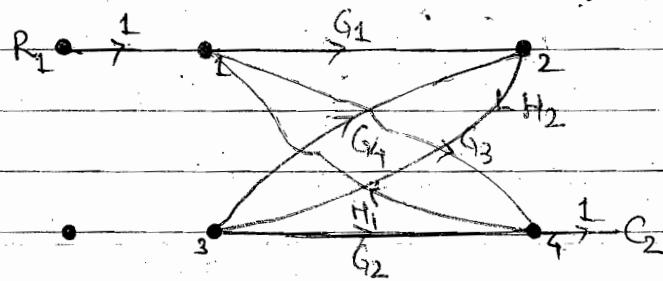
$$\therefore \frac{Y}{X} = \frac{G_1 G_2 G_3 + G_4 [1 + G_2 H_2 + G_2 G_3 H_3 - G_1 G_2 H_1 H_2]}{1 + G_2 H_2 + G_2 G_3 H_3 + G_1 G_2 H_1 H_2}$$

or $\frac{Y}{X} = G_4 + \frac{G_1 G_2 G_3}{1 + G_2 H_2 + G_2 G_3 H_3 - G_1 G_2 H_1 H_2}$ *

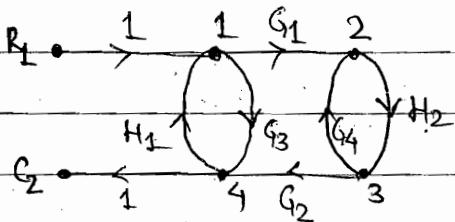
Ques:- ② Using signal flow graph, find G/R_1 .



Ans:- ②



To Simplify it:



$$P_1 = G_3, \quad \Delta_1 = 1 - [G_4 H_2]$$

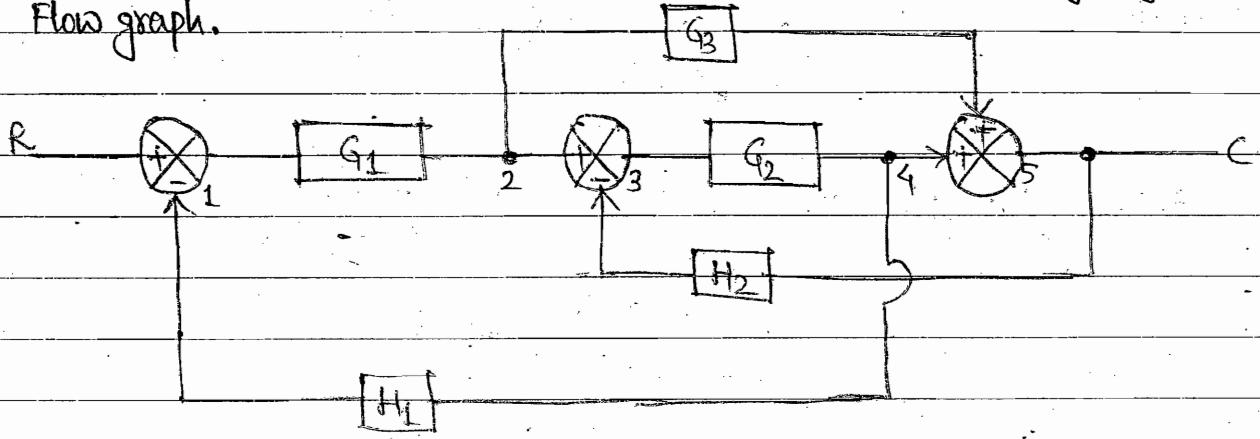
$$\therefore P_2 = G_1 G_2 H_2, \quad \Delta_2 = 1 - [0] = 1.$$

$$\Delta = 1 - [G_3 H_1 + G_4 H_2 + G_1 G_2 H_1 H_2] + [G_3 G_4 H_1 H_2].$$

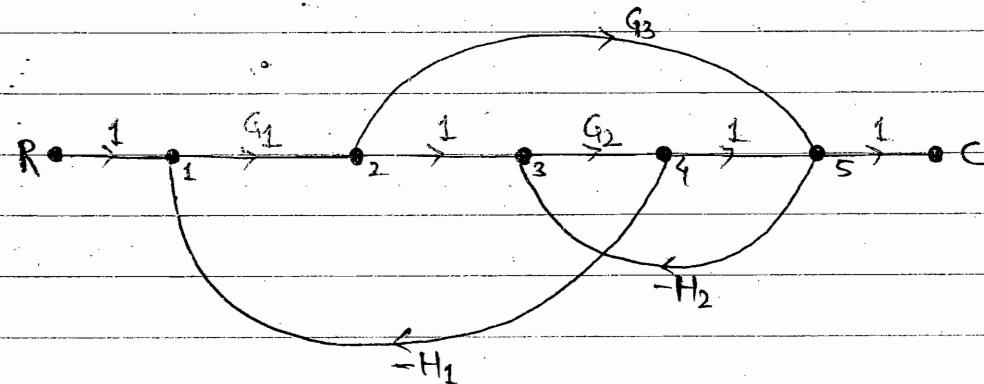
$$\therefore \frac{G_2}{R_L} = \frac{G_3 [1 - G_4 H_2] + G_1 G_2 H_2}{1 - G_3 H_1 + G_4 H_2 + G_1 G_2 H_1 H_2 + G_3 G_4 H_1 H_2}$$

$$\left| \begin{array}{l} C_2 = G_3 [1 - G_4 H_2] + G_1 G_2 H_2 \\ R_L \quad 1 - G_3 H_1 - G_4 H_2 - G_1 G_2 H_1 H_2 + G_3 G_4 H_1 H_2 \end{array} \right| *$$

Ques: (3) For the given block, obtain its transfer function (C/R) using signal flow graph.



Ans: (3)



$$P_1 = G_1 G_2, \quad \Delta_1 = 1 - [0] = 1$$

$$P_2 = G_1 G_3, \quad \Delta_2 = 1 - [0] = 1.$$

$$\Delta = 1 - [-G_1 G_2 H_1 - G_2 H_2 + G_1 G_2 G_3 H_1 H_2]$$

$$\left| \begin{array}{l} \therefore \frac{C}{R} = \frac{G_1 G_2 + G_1 G_3}{1 + G_1 G_2 H_1 + G_2 H_2 - G_1 G_2 G_3 H_1 H_2} \end{array} \right| *$$

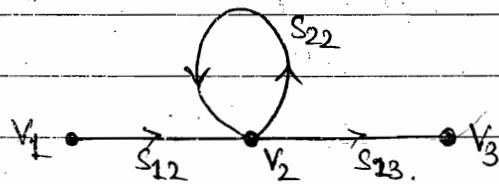
MASON'S GAIN LIMITATION

- Mason Gain Limitation exists on Self-sustaining Loop.

Self-Sustaining Loop

- It contains only single node and origination node itself will be termination node.

Example:



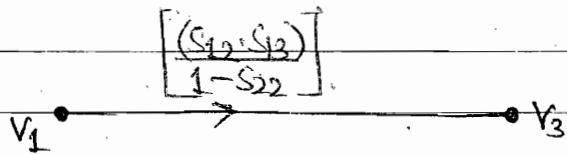
Ans:- Potential at V_2 , $V_2 = S_{12}V_1 + V_2S_{22}$.

$$\therefore V_2 = \frac{S_{12}V_1}{1 - S_{22}} *$$

Now, potential at V_3 , $V_3 = V_2 \cdot S_{23}$

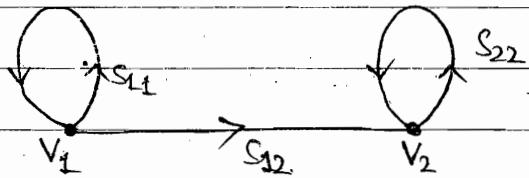
$$\text{or } V_3 = \left(\frac{S_{12} \cdot S_{23}}{1 - S_{22}} \right) V_1$$

\therefore Given signal flow graph can be replaced with:



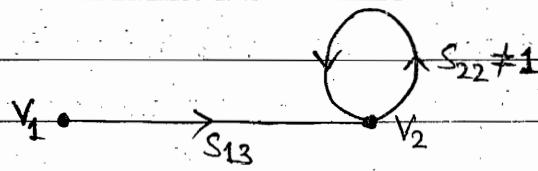
Here, S_{22} must not be zero.

Other Limitation:



- Potential at V_1 , $V_1 = S_{11}V_1$

Here, necessarily, $S_{11} = 1$, to satisfy Node Equation.



$$\therefore V_2 = V_1 \cdot S_{13} + S_{22} \cdot V_2$$

| | |
|--------------------------|---|
| $V_2 = S_{12} \cdot V_1$ | * |
| $1 - S_{22}$ | |

Chapter:-2

TIME RESPONSE ANALYSIS

* Open Loop System:

- In case of Open Loop system, the location of pole is independent of any parameter which means its pole will not locate on right side of s-plane. Hence, system will be highly stable.

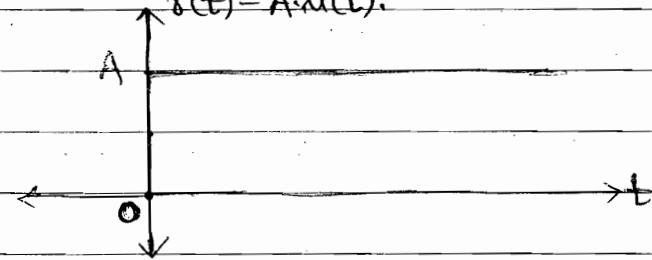
* Closed Loop System with Unity Feedback:

- Here, the location of pole is parameter-dependent, so under specific condition, there is possible chances that pole will go towards right side of s-plane thereby making the system unstable.

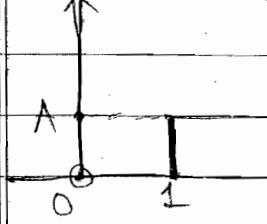
Hence, Basic Open Loop system is more stable than Closed Loop system.

* Basic Open Loop system with Step input:

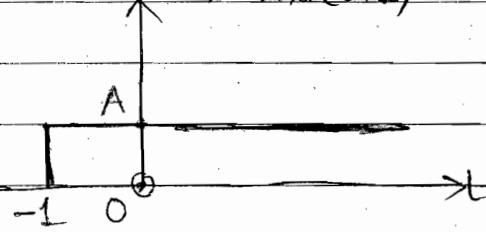
$$r(t) = A \cdot u(t).$$



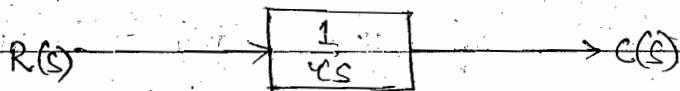
$$r(t) = A u(t-1)$$



$$r(t) = A u(t+1)$$

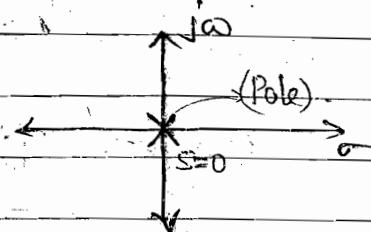


* For block given below:



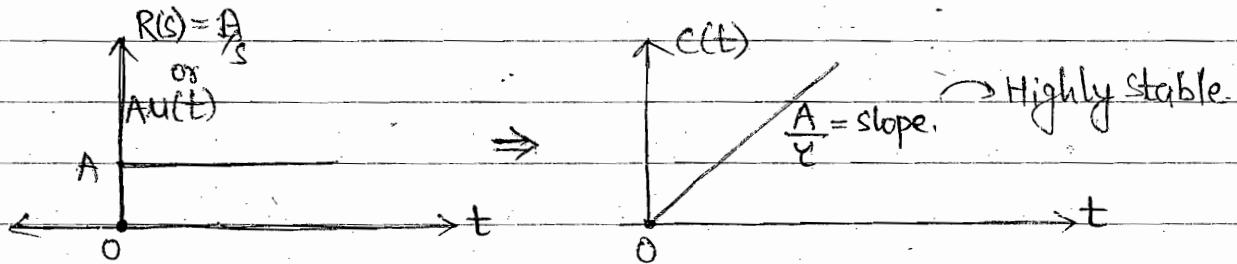
$$\therefore \frac{C(s)}{R(s)} = \frac{1}{RC}$$

$$\text{or } C(s) = \frac{1}{RC} \cdot R(s)$$



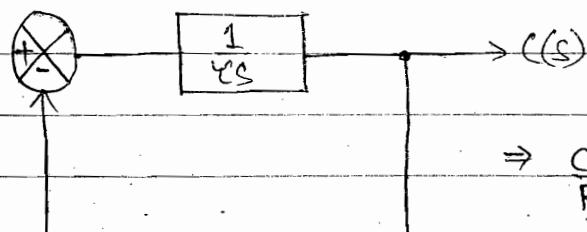
- For step input, $R(s) = \frac{A}{s}$

$$\therefore C(s) = \frac{A}{sRC} \Rightarrow C(t) = \left(\frac{A}{RC}\right)t \quad * \quad [\text{Ramp as output}]$$

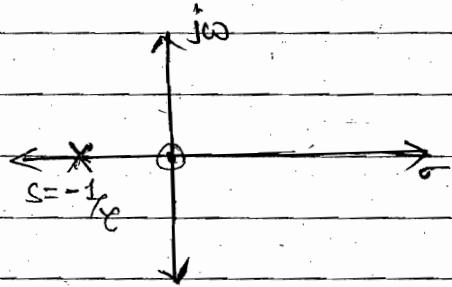


* BIBO stability condition is not applicable here as it applies only on voltage and current gains and not on impedances.
i.e. input and output must be of same nature.

* First order closed loop system for step input:



$$\Rightarrow \frac{C(s)}{R(s)} = \frac{\frac{1}{RC}}{1 + \frac{1}{RC}} = \frac{1}{s + \frac{1}{RC}}$$



- Here, closed loop system depends upon τ and can be unstable for some specific value of τ .

As Input $R(s) = A/s$

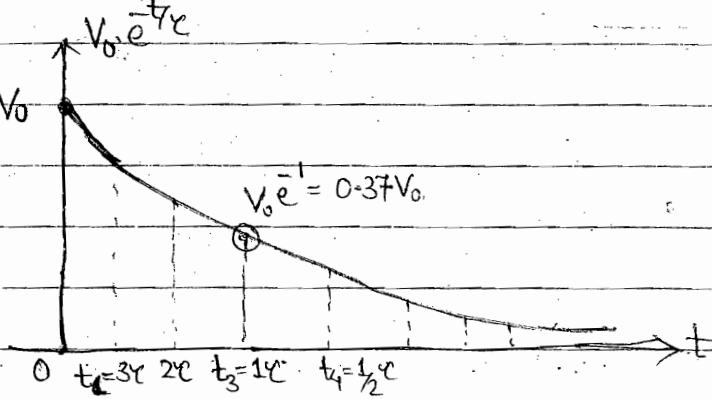
$$\therefore C(s) = \frac{(A/\tau)}{s(s + 1/\tau)}$$

$$\text{or } C(s) = \frac{A}{s} - \frac{A}{(s + 1/\tau)} \quad [\text{Partial Fractions}]$$

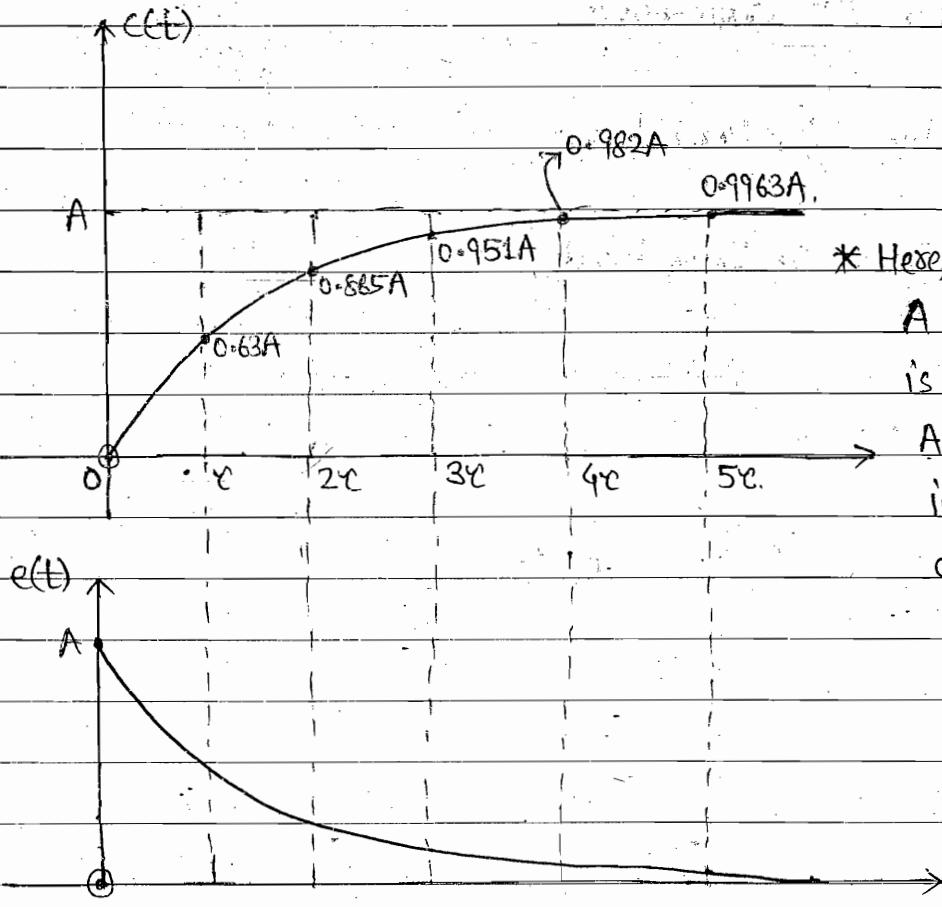
$$\therefore C(t) = A \left[1 - e^{-t/\tau} \right] u(t) \quad * \quad (1)$$

- Time Constant is inverse of the location of Real part of pole.
- If any system contains 'n' number of poles, then due to 'n' number of Exponential terms will exist in the output response and Time constant will be inverse of real part of respective pole location.
- Time constant is defined as, "that time at which Amplitude decreases by 63% of Maximum Amplitude."

$$\boxed{\text{Time Constant } (\tau) = t_3} *$$



- Output as given by eq-(1) can be drawn as:



* Here, final point is A and output is trying to reach A which is input itself and also pre-defined value.

- At $t=0$; $c(0) = A[1-1] = 0$. 100%
- At $t=\tau$; $c(\tau) = A[1-e^{-1}] = A[1-0.37] = 0.63A$. 37%
- At $t=2\tau$; $c(2\tau) = A[1-e^{-2}] = A[1-0.135] = 0.865A$. 13.5%
- At $t=3\tau$; $c(3\tau) = A[1-e^{-3}] = A[1-0.049] = 0.951A$. 4.9%
- At $t=4\tau$; $c(4\tau) = A[1-e^{-4}] = A[1-0.018] = 0.982A$. 1.8%
- At $t=5\tau$; $c(5\tau) = A[1-e^{-5}] = A[1-0.0037] = 0.9963A$. 0.37%
- At $t=6\tau$; $c(6\tau) = A[1-0.0022] = 0.9978A$. 0.22%
- At $t=\infty$; $c(\infty) = A$

• For 1% Error-band, $t_s = 5\text{c}$

• For 2%, Error band, $t_s = 4\text{c}$.

• For 5% Error band, $t_s = 3\text{c}$.

Now, from eq-(1), t_s at opti output = 98% with error band of 2%

$$0.98A = A [1 - e^{-t_s/c}]$$

$$\text{or } e^{-t_s/c} = 0.018$$

$$\text{or } -t_s/c = \ln(0.018)$$

$$\text{or } t_s = 3.99c \quad * \quad \text{or } t_s = 4c \quad *$$

* For 1% Error band:

$$0.99A = A [1 - e^{-t_s/c}]$$

$$\Rightarrow t_s = 4.62c \quad *$$

* For 5% Error band: $0.95A = A [1 - e^{-t_s/c}]$

$$\Rightarrow t_s = 2.99c \quad * \quad \text{or } t_s = 3c \quad *$$



Error Response :

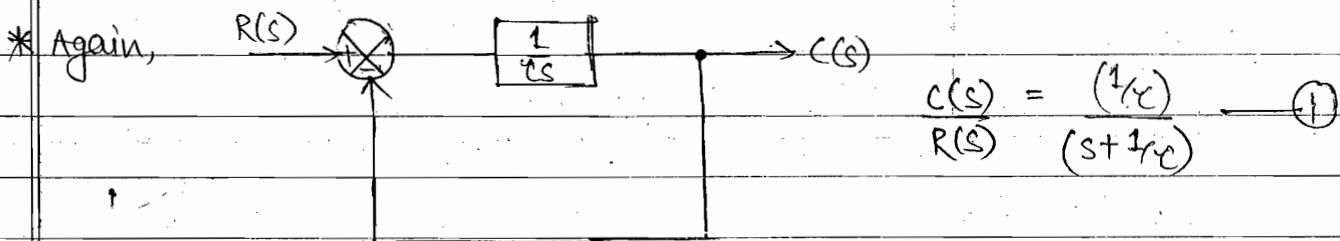
$$e(t) = \text{Desired Output} - \text{Actual Output}$$

or

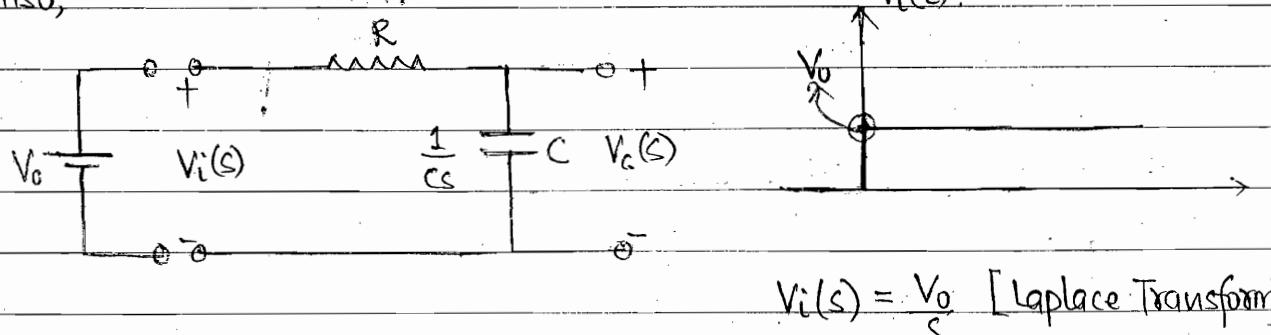
$$e(t) = r(t) - c(t)$$

$$\therefore e(t) = A u(t) - A [1 - e^{-\frac{t}{RC}}] = A e^{-\frac{t}{RC}}$$

- At $t=0$; $e(0) = A$
- At $t=\tau$; $e(\tau) = 0.37A$.
- At $t=2\tau$; $e(2\tau) = 0.185A$
- At $t=3\tau$; $e(3\tau) = 0.049A$
- At $t=4\tau$; $e(4\tau) = 0.018A$ (2% error-band).
- At $t=5\tau$; $e(5\tau) = 0.0033A$
- At $t=\infty$; $e(\infty) = 0$.



Also,



$$\text{Now, } \frac{V_c(s)}{V_i(t)} = \frac{\frac{1}{RC}}{R + \frac{1}{RC}} = \frac{1}{RCs + 1} = \frac{1}{s + \frac{1}{RC}} \quad \text{--- (2)}$$

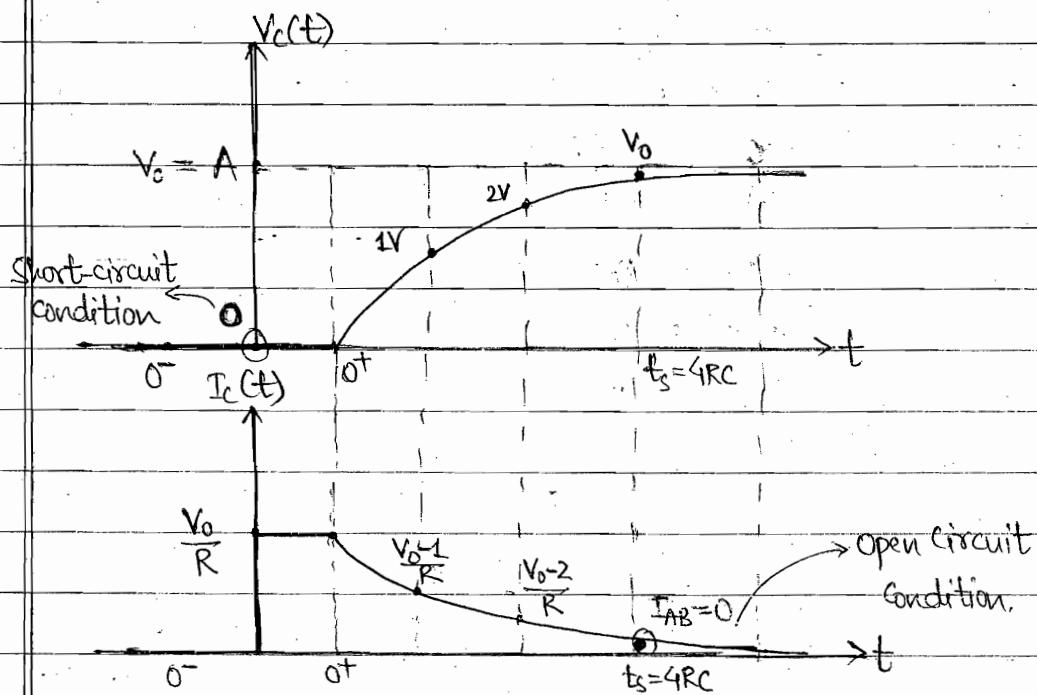
Comparing (1) and (2),

$$\tau = RC$$

$$\therefore V_c(t) = V_0 [1 - e^{-\frac{t}{RC}}] *$$

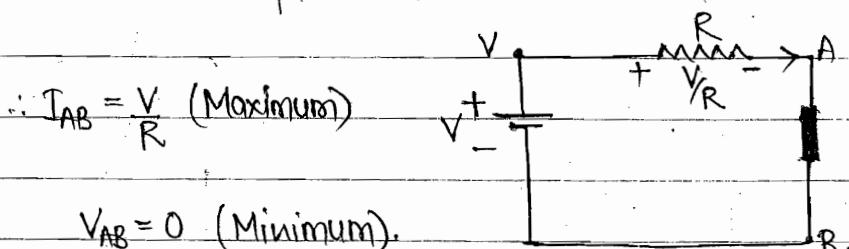
or in terms of block diagram,

$$c(t) = A [1 - e^{-\frac{t}{RC}}] *$$



(I) Short circuit Condition ↓

* Capacitor is short-circuited.



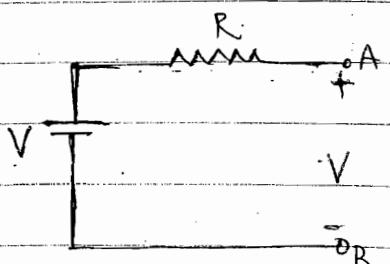
$$V_{AB} = 0 \text{ (Minimum).}$$

(II) Open Circuit Condition :

* Capacitor is open-circuited

$$V_{AB} = V \text{ (Maximum)}$$

$$I_{AB} = 0 \text{ (Minimum).}$$

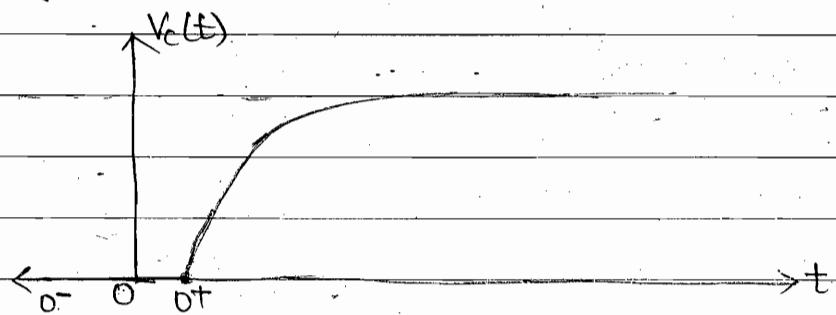


- For Capacitor, Voltage cannot change instantaneously but current does. i.e.

$$V_c(0) = V_c(0^+) *$$

But $I_c(0) \neq I_c(0^+) *$

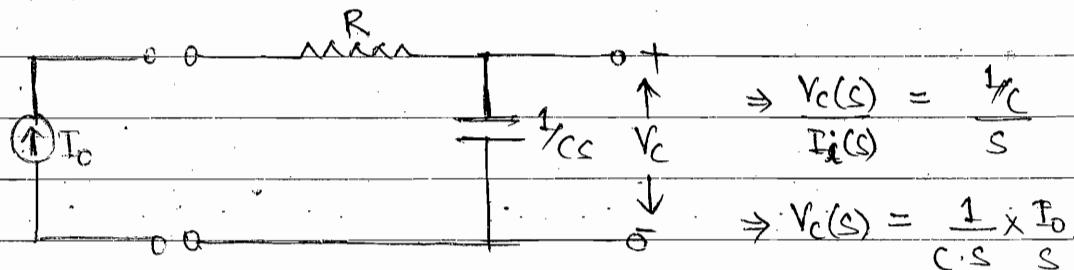
- Now, by decreasing Resistance or more accurately Time constant of the system, I_{AB} will increase i.e. more charge will flow across plates of capacitor and it charges more rapidly, thus time of voltage decreases from $t=0^+$ to some other decreased value.



- If Time constant is made 0, then $0^- = 0 = 0^+ = \infty$ and capacitor voltage increases instantaneously (Not possible generally).

* Here, voltage V_0 is given to RC circuit and output is also a voltage i.e. $V_c(t)$, so it will be a Closed Loop System but in general, RC circuit will not always be Open or closed loop system and it depends on input to be applied.

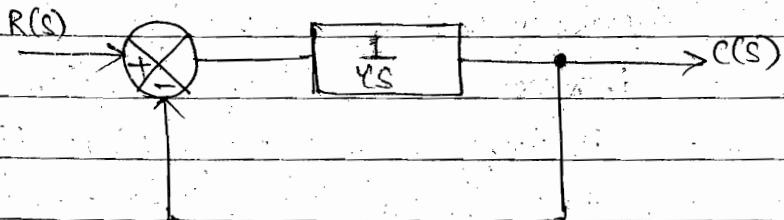
* For example :- If instead of V_0 , I_0 is given, then :



$$\therefore V_c(t) = \left(\frac{I_0}{C}\right) \cdot t *$$

- Here, capacitor will charge to infinite time and current will not become 0. It will be highly stable.
- It is also an Open Loop System.

~~2014~~ * Closed Loop First order system for Ramp Input is



$$C(s) = \frac{1/r_c}{R(s)} (s + 1/r_c)$$

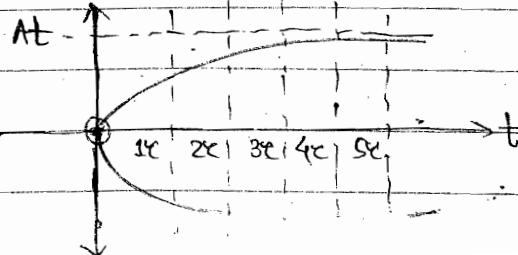
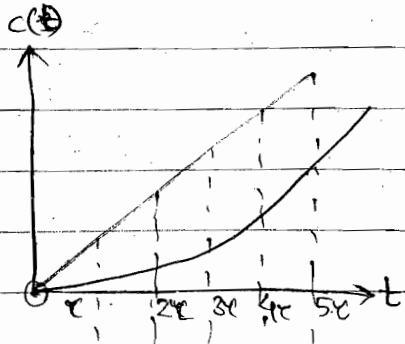
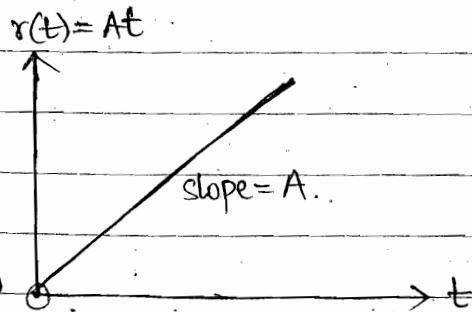
$$\text{As } R(s) = \frac{1}{s^2} \text{ (For Ramp Input)}$$

$$\therefore C(s) = \frac{1/r_c}{s^2(s + 1/r_c)}$$

$$\therefore C(s) = \frac{A}{s^2} - \frac{A/r_c}{s} + \frac{A/r_c}{s + 1/r_c}$$

$$\therefore C(t) = At - A/r_c u(t) + A/r_c e^{-t/r_c}$$

$$\text{or } C(t) = At - A/r_c + A/r_c e^{-t/r_c}$$



Now, Error Response, $e(t) = r(t) - c(t)$

$$\therefore e(t) = At - \{At - Ae^{-\frac{t}{\tau}} + Ae^{-\frac{t}{\tau}}\}$$

$$\therefore e(t) = Ae^{-\frac{t}{\tau}} [1 - e^{-\frac{t}{\tau}}] *$$

- At $t=0$, $c(t) = 0$; $e(0) = 0$.
- At $t=1\tau$; $c(\tau) = 0.37A\tau$; $e(\tau) = 0.63A\tau$.
- At $t=2\tau$; $c(2\tau) = 1.135A\tau$; $e(2\tau) = 0.865A\tau$.
- At $t=3\tau$; $c(3\tau) = 2.049A\tau$; $e(3\tau) = 0.951A\tau$.
- At $t=4\tau$; $c(4\tau) = 3A\tau$; $e(4\tau) = A\tau$.
- At $t=\infty$; $c(\infty) = At - Ae^{-\frac{t}{\tau}} [t \geq t_0 = \infty]$
- At $t=5\tau$; $c(5\tau) = 4A\tau$; $e(5\tau) = A\tau$.

* System Error; $e_s(t) = \text{Slope of Input} - \text{Slope of Output}$.

$$\therefore e_s(t) = A - A[1 - e^{-\frac{t}{\tau}}]$$

$\boxed{\text{As, } r(t) = At}$

$$\therefore \frac{dr(t)}{dt} = A$$

$$\text{and } e(t) = At - Ae^{-\frac{t}{\tau}} [1 - e^{-\frac{t}{\tau}}].$$

$$\therefore \frac{dc(t)}{dt} = A - Ae^{-\frac{t}{\tau}}.$$

$$\therefore e_s(t) = A - A[1 - e^{-\frac{t}{\tau}}].$$

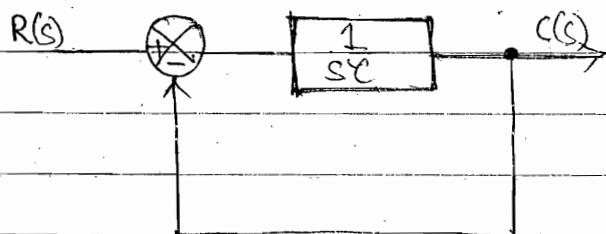
$$\therefore e_s(t) = Ae^{-\frac{t}{\tau}} *$$

- At $t=0$; $e_c(t=0) = A \quad (100\%)$
- At $t=\tau$; $e_c(\tau) = 0.037A \quad (37\%)$
- At $t=2\tau$; $e_c(2\tau) = 0.135A \quad (13.5\%)$

- At $t=3\tau$; $e_c(3\tau) = 0.049A \quad (4.9\%)$
- At $t=4\tau$; $e_c(4\tau) = 0.018A \quad (1.8\%)$
- At $t=5\tau$; $e_c(5\tau) = 0.0033A \quad (0.33\%)$

- At $t=\infty$; $e(\infty) = 0 \quad (0\%)$.

* Closed Loop First Order System with Impulse Input:



$$\frac{C(s)}{R(s)} = \frac{1/s_C}{s + 1/s_C}$$

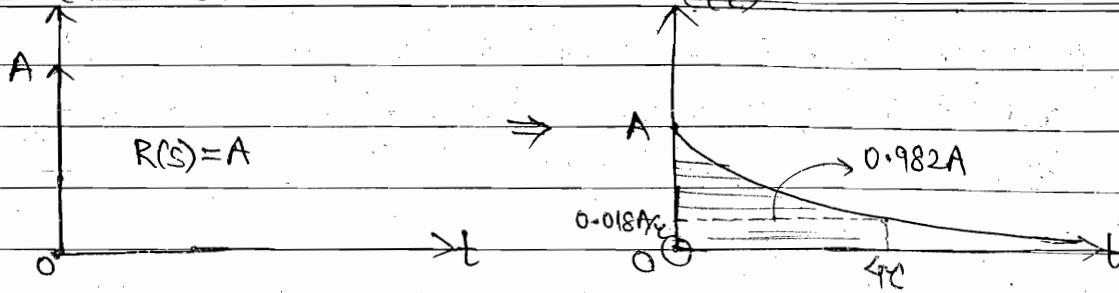
As $R(s) = A$ [Impulse Input].

$$\therefore C(s) = \frac{(A)e^{-t_C}}{(s + 1/s_C)}$$

$$\therefore C(t) = \frac{A}{s_C} e^{-t_C} \quad *$$

- At $t=4\tau$, $C(4\tau) = \frac{A}{s_C} \cdot 0.018$.

$$r(t) = A \cdot \delta(t)$$



Now, Area under the curve at $4c$,

$$\therefore \text{Area} = \int_0^{4c} C(t) \cdot dt = \int_0^{4c} \frac{A}{e^{\frac{t}{c}}} \cdot dt.$$

$$\text{Area} = -A [e^{-4c} - e^0] = -A [0.018 - 1].$$

$$\therefore \boxed{\text{Area} = 0.982A} * \quad [18\% \text{ error}]$$

But for limits upto $t=0$ to $t=\infty$,

$$\boxed{\text{Area} = A} *$$

* In case of impulse input, output error is not defined but system error is defined in terms of Area.

$$\therefore e_s(t) = \text{Input Area} - \text{Output Area}.$$

$$\Rightarrow e_s(t) = A - \int_0^t C(t) \cdot dt$$

$$\therefore \boxed{e_s(t) = A e^{-\frac{t}{c}}} *$$

- At $t=0$; $e_s(0) = 0$.
- At $t=c$; $e_s(c) = 0.37A$.
- At $t=2c$; $e_s(2c) = 0.135A$
- At $t=3c$; $e_s(3c) = 0.049A$.
- At $t=4c$; $e_s(4c) = 0.018A$.

- In case of Parabolic input, rate of change of slope will be constant i.e. system error will depend now on rate of change of slope.

Now,

$$(i) \quad c_R(t) = At - Ae^{-t/\tau_c} \quad x_R(t) = At$$

$$\frac{d}{dt}(c_R(t)) = A - Ae^{-t/\tau_c} \quad \frac{d}{dt}(x_R(t)) = A = x_s(t)$$

$$(ii) \quad c_s(t) = A[1 - e^{-t/\tau_c}] \quad x_s(t) = Au(t).$$

$$\frac{d}{dt}(c_s(t)) = A \cdot e^{-t/\tau_c} \quad \frac{d}{dt}(x_s(t)) = A\delta(t) = x_i(t).$$

As In Laplace transform:

$$(i) \quad C_R(s) = \frac{1}{s} \left[\frac{(A\tau_c)}{s(s+\tau_c)} \right] \quad R_R(s) = \frac{1}{s}[A].$$

$$C_s(s) = sC_R(s) = \frac{(A\tau_c)}{s(s+\tau_c)} \quad R_s(s) = sR_R(s) = A/s.$$

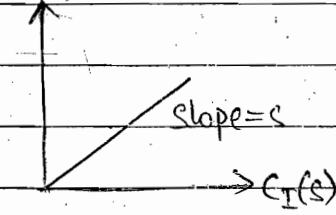
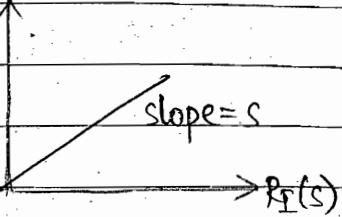
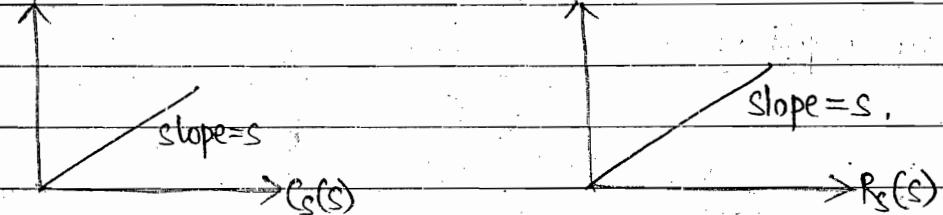
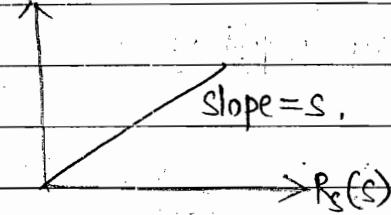
$$\boxed{C_s(t) = \frac{d}{dt}[c_R(t)]} * \quad \boxed{x_s(t) = \frac{d}{dt}[x_R(t)]} *$$

$$(ii) \quad C_I(s) = \frac{1}{s} \left[\frac{A\tau_c}{(s+\tau_c)} \right] \quad R_I(s) = \frac{1}{s}[A].$$

$$C_I(s) = sC_s(s) = \frac{A\tau_c}{s+\tau_c} \quad R_I(s) = sR_s(s) = A.$$

$$\boxed{C_I(t) = \frac{d}{dt}[c_s(t)]} *$$

$$\boxed{x_I(t) = \frac{d}{dt}[x_s(t)]} *$$

$C(s)$  $R(s)$  $C_p(s)$  $R_p(s)$ 

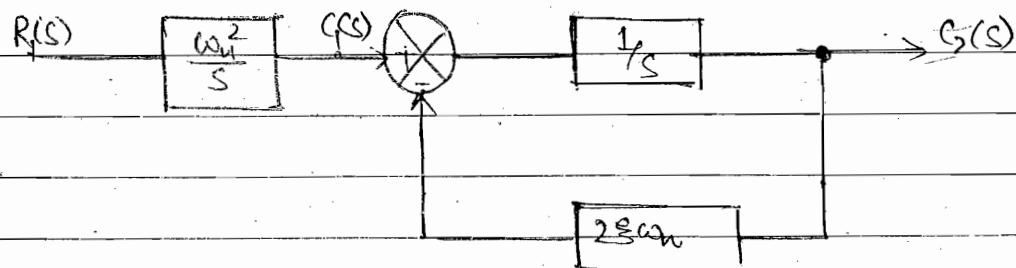
* For Parabolic Input : $x_p(t) = At^2$

$$\therefore R_p(s) = \frac{A \cdot 2!}{s^3} = \frac{2A}{s^3}$$

$$\text{or } SR_p(s) = 2R_p(s) \Rightarrow R_p(s) = \frac{s \cdot R_p(s)}{2}$$

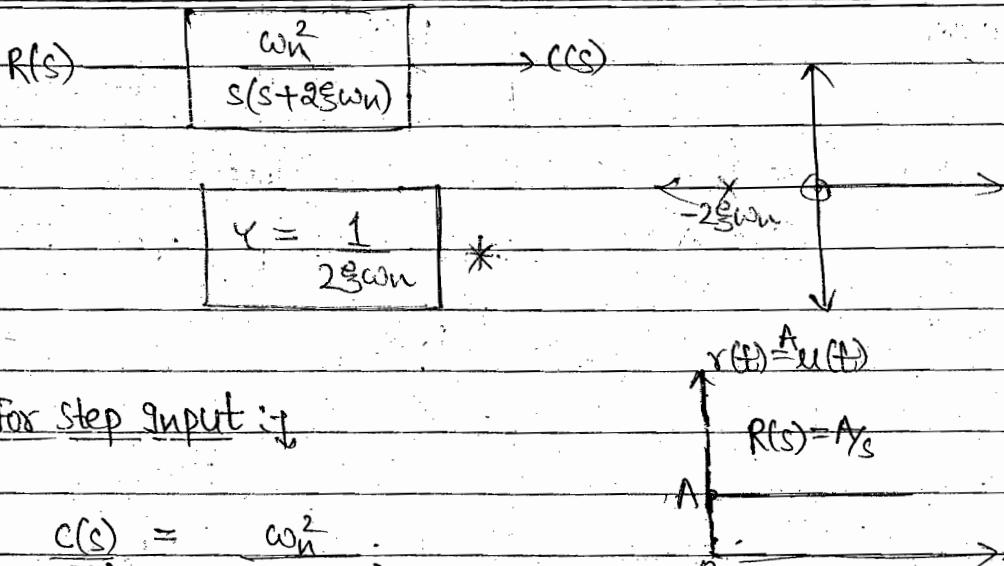
∴ To maintain linearity, given input as : $x_p(t) = \frac{At^2}{2}$

* OPEN LOOP SECOND ORDER SYSTEM



$$\therefore \frac{C(s)}{R(s)} = \frac{w_n^2}{s} \times \frac{1}{(s + 2s w_n)}$$

$$\Rightarrow \frac{C(s)}{R(s)} = \frac{w_n^2}{s(s + 2s w_n)}$$



(i) For step input:

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s(s+2\zeta\omega_n)}$$

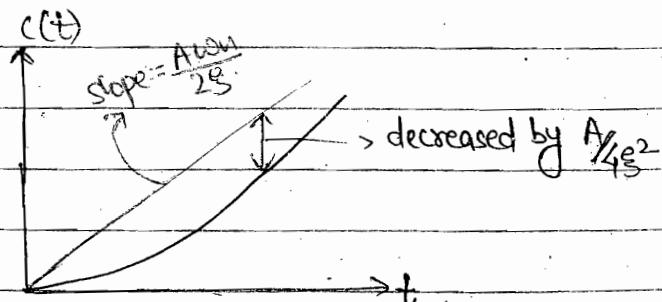
$$\Rightarrow R(s) = A/s \text{ (For Step Input)}$$

$$\therefore C(s) = \frac{A \cdot \omega_n^2}{s^2(s+2\zeta\omega_n)}$$

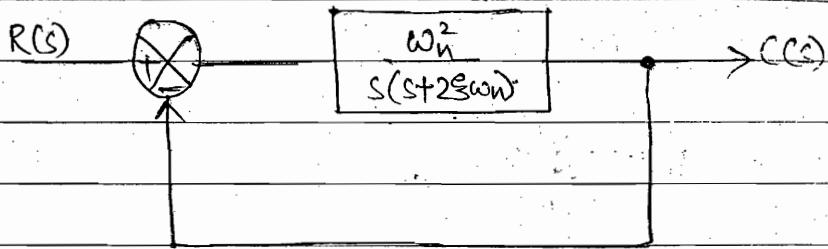
$$\therefore C(s) = \frac{A \cdot \omega_n}{s} - \frac{A/4\zeta^2}{s} + \frac{A/4\zeta^2}{(s+2\zeta\omega_n)}$$

$$\therefore C(t) = \left[\frac{A \cdot \omega_n \cdot t}{2\zeta} - \frac{A}{4\zeta^2} + \frac{A}{4\zeta^2} e^{-2\zeta\omega_n t} \right] *$$

$$\text{Also, } C[t \geq t_s = 4\zeta^2] = \frac{A \cdot \omega_n \cdot t}{2\zeta} - \frac{A}{4\zeta^2}$$



→ CLOSED LOOP SECOND ORDER SYSTEM :



$$\therefore C(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

so, for location of pole, $s^2 + 2\xi\omega_n s + \omega_n^2 = 0$.

$$\therefore s_{1,2} = -\xi\omega_n \pm j\omega_n \sqrt{1-\xi^2} \quad *$$

where, ξ = Damping Ratio, ω_n = Natural Frequency.

- In Time Response Analysis, ω_n is constant and ξ is variable.

** Case-I :- Underdamped System :

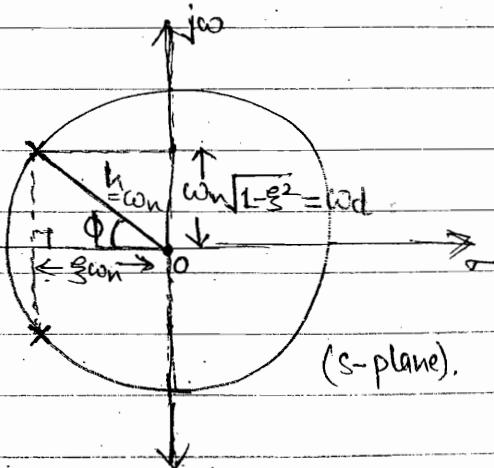
- In this case,

$$0 < \xi < 1 \quad *$$

$$s_{1,2} = -\xi\omega_n \pm j\sqrt{1-\xi^2}\omega_n \quad *$$

Here, as real part of pole is: $-\xi\omega_n$.

$$\therefore \text{Time Constant} (\tau) = \frac{1}{\xi\omega_n} \quad *$$



$$\text{Now, } h = \sqrt{\omega_n^2(1-\xi^2) + \xi^2\omega_n^2}$$

$$\therefore h = \omega_n \quad *$$

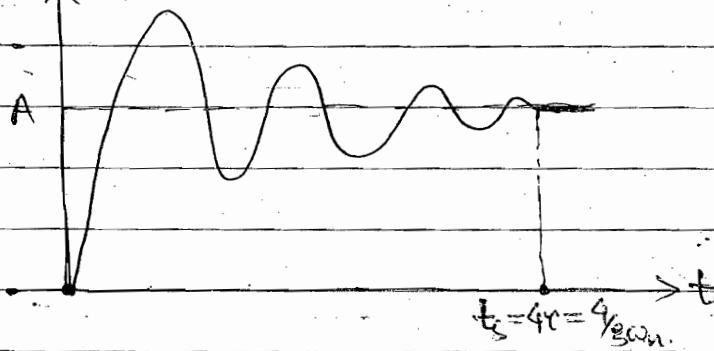
$$\text{Now, } \cos\phi = \frac{\omega_{\text{com}}}{\omega_n} \quad \sin\phi = \frac{\omega_n \sqrt{1-\xi^2}}{\omega_n}$$

$$\cos\phi = \xi \quad * \quad \sin\phi = \sqrt{1-\xi^2} \quad *$$

$$\tan\phi = \frac{\sqrt{1-\xi^2}}{\xi} \quad *$$

- If ξ is now changed, then location of pole will be on locus of circle formed by constant radius ω_n .

(Response).

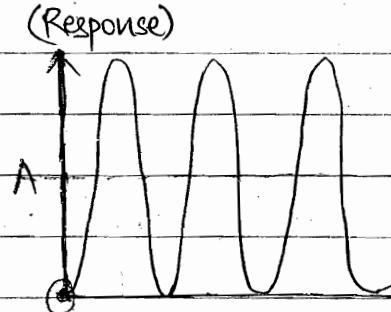


$$\therefore \text{settling time} = 4r = \frac{4}{\xi\omega_n} \quad *$$

* Case-II: Undamped System :

Here, $\xi=0$ *

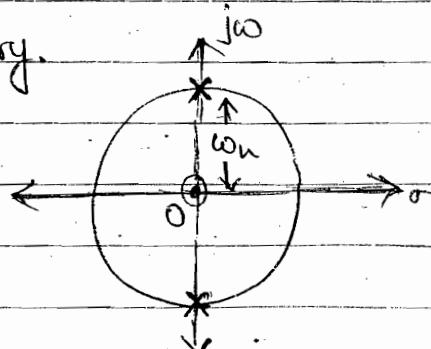
$$s_{1,2} = \pm j\omega_n \quad *$$



- Roots will be purely Imaginary.

$$\gamma = \infty \quad *$$

$$t_s = \infty \quad *$$



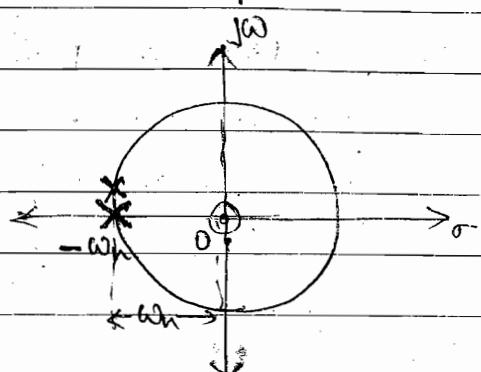
- Undamped system will oscillate between two finite values continuously.
This type of system is Marginally Stable System.
- In this system, output contains no exponential terms but contains sinusoidal terms.

Case-III:- Critically Damped system :-

Here,

$$\xi = 1 *$$

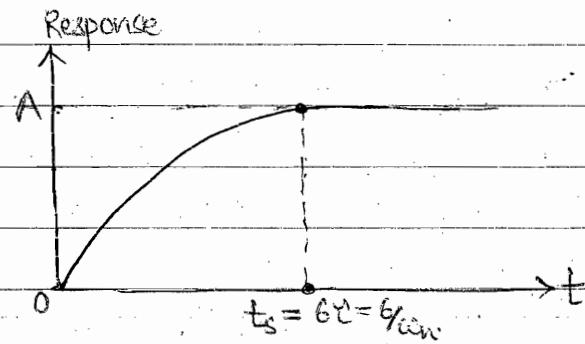
$$\therefore S_{1,2} = \pm \omega_n *$$



- Roots are purely real and equal.

- $\zeta = \frac{1}{\sqrt{\omega_n}}$ *

- $t_s = 6\zeta$ *



Relating Critically and Underdamped systems :-

$$t_s(C-D) = t_s(U.D) \Rightarrow 6 = \frac{4}{\omega_n \xi \sqrt{1-\xi^2}}$$

$$\Rightarrow \xi = \frac{2}{3} *$$

$$\therefore \text{If } \xi = \frac{2}{3}; \quad t_s(C-D) = t_s(U.D)$$

$$\text{If } \xi < \frac{2}{3}; \quad t_s(e) < t_s(D)$$

$$\text{If } \xi > \frac{2}{3}; \quad t_s(e) > t_s(D)$$

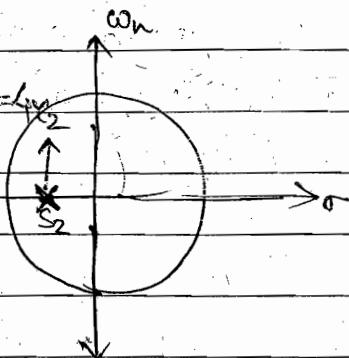
Case-IV: Overdamped System

Here,

$$\xi > 1 \quad *$$

$$s_{1,2} = -\xi \omega_n \pm \omega_n \sqrt{\xi^2 - 1}$$

$$t_s = 4\tau_1 \quad t_s = 4\tau_2$$



- Roots are Real and Distinct.
- There will be two Time constants in overdamped system i.e.

$$\tau_1 = \frac{1}{\xi \omega_n + \omega_n \sqrt{\xi^2 - 1}}, \quad \tau_2 = \frac{1}{\xi \omega_n - \omega_n \sqrt{\xi^2 - 1}}$$

$$\therefore \text{As } \tau_2 > \tau_1 \text{ or } \frac{\tau_2}{\tau_1} > 1$$

$$\text{or } \frac{\tau_1}{\tau_2} < 1. \quad *$$

- settling time of output will be : $4\tau_2$

As with input as unit step,

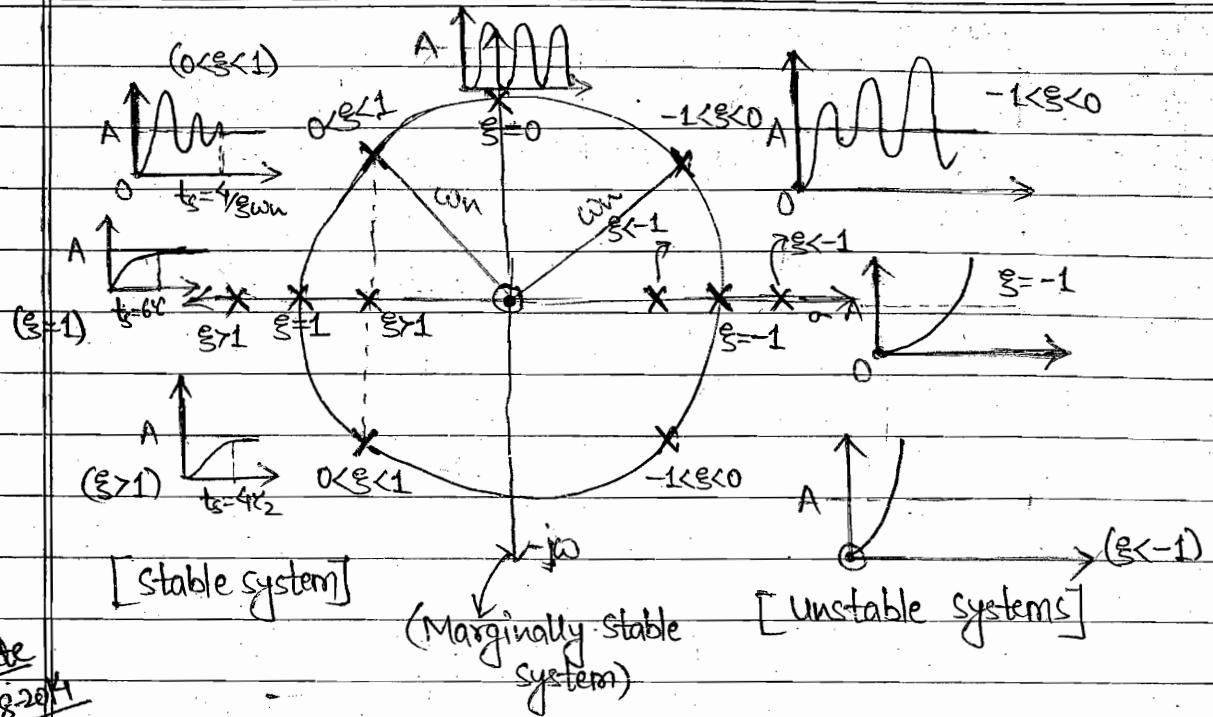
$$c(t) = A [1 - \tau_1 e^{-\frac{t}{\tau_1}} - \tau_2 e^{-\frac{t}{\tau_2}}].$$

$$\bullet \text{At } t = 4\tau_1, c(4\tau_1) = A [1 - \tau_1 e^{-4} - \tau_2 e^{-4}]$$

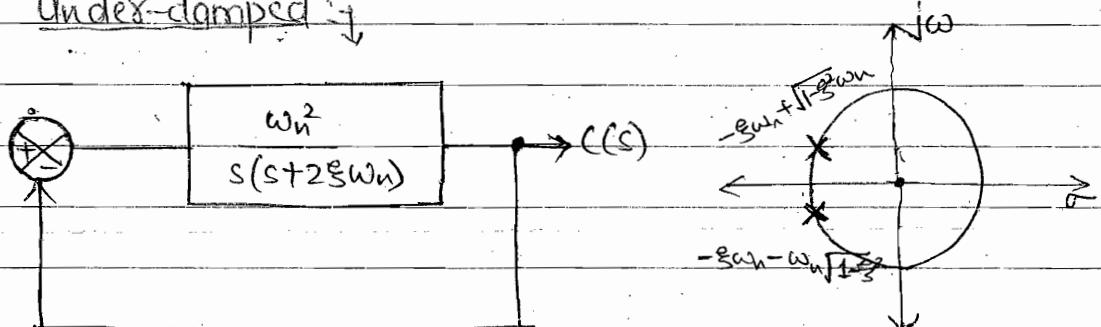
$$\bullet \text{At } t = 4\tau_2, c(4\tau_2) = A [1 - \tau_1 e^{-4(\frac{\tau_1}{\tau_2})} - \tau_2 e^{-4}] \text{ [settled entirely]}$$

$$\therefore t_s = 4\tau_2 = \frac{4}{\xi \omega_n - \omega_n \sqrt{\xi^2 - 1}} \quad *$$

* t_s will depend on the pole nearer to origin or simply Dominant Pole.



Case-I: Under-damped

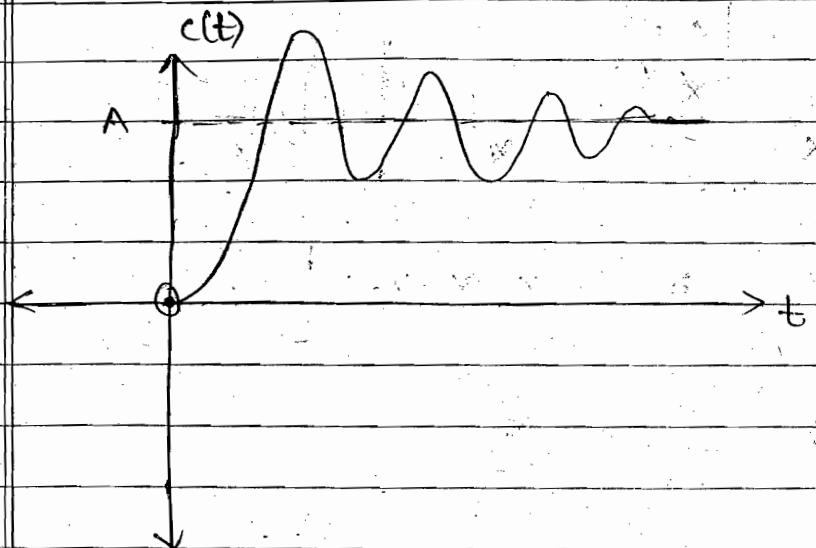


$$C(s) = \frac{\omega_n^2}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2} = \frac{\omega_n^2}{(s + \xi\omega_n + j\sqrt{1-\xi^2}\omega_n)(s + \xi - j\sqrt{1-\xi^2}\omega_n)}$$

$$\therefore \text{For } R(s) = \frac{1}{s}$$

$$\therefore C(t) = 1 - \frac{-\xi\omega_n t}{\sqrt{1-\xi^2}} \sin(\omega_n \sqrt{1-\xi^2} t + \phi)$$

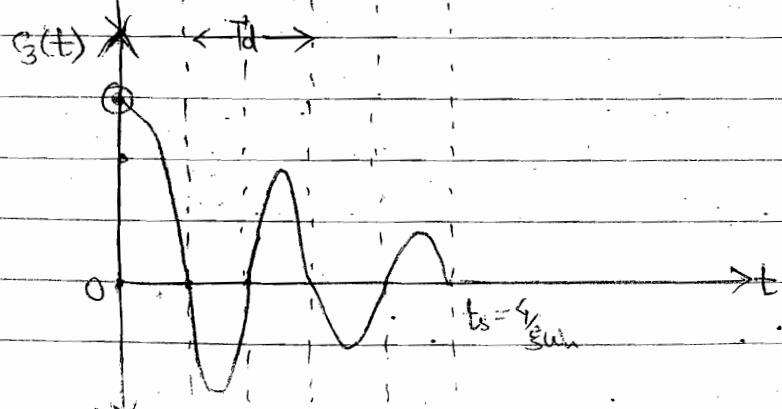
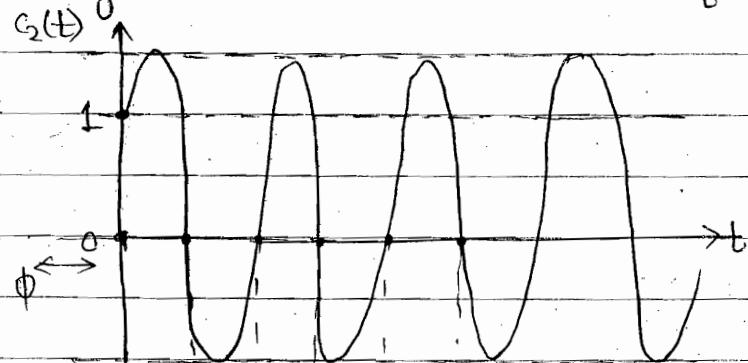
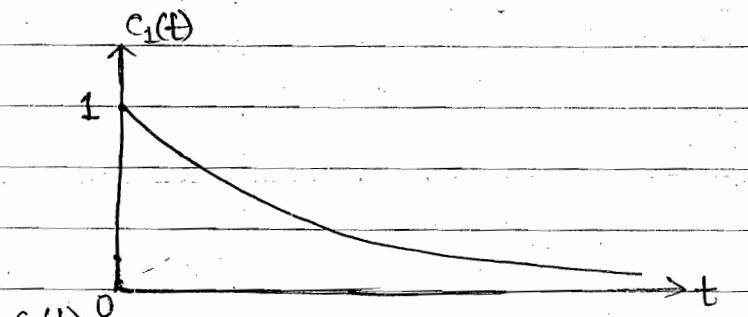
$$\text{where, } \phi = \tan^{-1} \left(\frac{\sqrt{1-\xi^2}}{\xi} \right).$$



• Suppose

$$c_1(t) = e^{-\xi \omega_n t} ; \quad c_2(t) = \frac{1}{\sqrt{1-\xi^2}} \sin[\omega_n \sqrt{1-\xi^2} t + \phi].$$

$$\text{At } t=0, \quad c_1(0) = 1 \quad ; \quad c_2(0) = \frac{1}{\sqrt{1-\xi^2}} \times \sqrt{1-\xi^2} = 1.$$



$$\therefore G_3(t) = G_1(t) \cdot G_2(t), \Rightarrow G_3(t) = \frac{e^{-\xi_{\text{sw}} t}}{\sqrt{1-\xi^2}} \sin(\omega_d t + \phi).$$

$$\text{or } G_3(t=0) = \frac{1}{\sqrt{1-\xi^2}} = 1.$$

$$\text{or } G_3(t=\frac{4}{\xi_{\text{sw}}}) = \frac{1}{\sqrt{1-\xi^2}} \sin \left[\omega_n \sqrt{1-\xi^2} \times \frac{4}{\xi_{\text{sw}}} + \phi \right] e^{-\xi_{\text{sw}} \times \frac{4}{\xi_{\text{sw}}}}$$

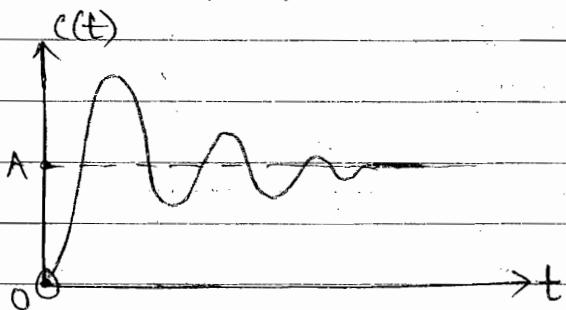
$$G_3(\frac{4}{\xi_{\text{sw}}}) = \frac{1}{\sqrt{1-\xi^2}} \sin \left(\frac{4\sqrt{1-\xi^2}}{\xi} + \phi \right) e^{-4}$$

e^{-4} is assumed to be 0 under 2% error-band.

$$\therefore G_3(t_s) = 0 *$$

$$\text{Now, } C(t) = A [1 - G_3(t)]$$

\therefore As $G_3(t)$ decreases, $C(t)$ increases as shown.



- Always Exponential term is responsible for settling of Response.

① RTSE TIME (t_s):

- It is defined as time when output reaches 0 to 100% of desired output for under-damped system and 10% to 90% of desired output of overdamped systems.
- Rise time (t_s) is Non-periodic in nature.
- It exists only in first oscillation cycle.

So, when output is 100%, time will be rise time.

$$\therefore C(t) = A \left[1 - e^{-\frac{\zeta \omega_n t}{\sqrt{1-\zeta^2}}} \sin(\omega_d t + \phi) \right]$$

$$\Rightarrow A = A \left[1 - e^{-\frac{\zeta \omega_n t_r}{\sqrt{1-\zeta^2}}} \sin(\omega_d t_r + \phi) \right].$$

$$\Rightarrow e^{-\frac{\zeta \omega_n t_r}{\sqrt{1-\zeta^2}}} \cdot \sin(\omega_d t_r + \phi) = 0.$$

$$\therefore \sin(\omega_d t_r + \phi) = 0$$

$$\Rightarrow \sin(\omega_d t_r + \phi) = \sin(0^\circ).$$

$$\Rightarrow \omega_d t_r + \phi = n\pi.$$

And as t_r exists only for first oscillation cycle, so, $n=1$ *

$$\therefore t_r = \frac{\pi - \phi}{\omega_d} = \frac{\pi - \phi}{\omega_n \sqrt{1-\zeta^2}} * (\phi \text{ in Radians}).$$

② PEAK TIME (t_p):

- It is defined as, time in which slope of output response is zero and output is either Maxima or Minima.
- If slope is 0 and output is Maximum, then that time will be known as Peak overshoot time.
- If slope is 0 and output is Minimum, then that time will be known as Peak undershoot time.

* Both Peak overshoot time and Peak undershoot time are periodic in nature and exist in each oscillation cycle alternately.

- To get t_p , Differentiate $c(t)$ and equate to 0,

$$\therefore \frac{dc(t)}{dt} = 0.$$

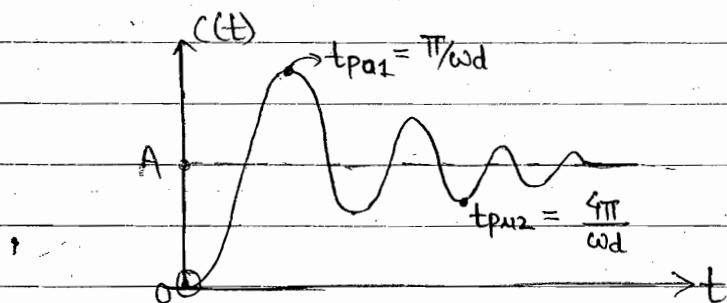
$$\therefore t_{pon} = \frac{(2n-1)\pi}{\omega_n \sqrt{1-\xi^2}} = \frac{(2n-1)\pi}{\omega_d}$$

$$\therefore t_{pon} = \boxed{\frac{(2n-1)\pi}{\omega_d}} * \text{(For overshoots).}$$

* $n = \text{Odd } (1, 3, 5, \dots)$ for Peak overshoots. } for $t_p = \frac{n\pi}{\omega_d}$ *

* $n = \text{Even } (2, 4, 6, \dots)$ for Peak Undershoots.

* For Undershoot : $t_{pun} = \boxed{\frac{(2n)\pi}{\omega_d}}$ *



(3) PERCENTAGE OVERSHOOT ($M_{po}\%$):

- It exists at Peak Overshoot time.
- As peak overshoot time is periodic, $\% M_{po}$ is also Periodic in nature.
- It will exist in each oscillation.

$$\% M_{pon} = \frac{c(t)_{\max} - c(t)_{\text{desired}}}{c(t)_{\text{desired}}} \times 100 \%$$

$$\% M_{pon} = e^{-\frac{(2n-1)\pi\xi^2}{1-\xi^2}} \times 100 \%$$

$$\therefore \text{For first Maximum overshoot, } \% M_{po1} = e^{-\frac{\pi\xi^2}{1-\xi^2}} \times 100 \%$$

(4) PERCENTAGE UNDERSHOOT :

- It exists at peak undershoot time.
- It is periodic in nature.

$$\% M_{pu} = \frac{e(t)_{desired} - e(t)_{min}}{e(t)_{desired}} \times 100\% = e^{\frac{-2\pi t}{T_w}} \times 100\%$$

* Note :-

$$\frac{\% M_{p01}}{\% M_{u1}} = \frac{\% M_{pu1}}{\% M_{p02}}$$

- Between Peak overshoot time and peak undershoot time, time difference will always remain constant and is equal to $(\frac{\pi}{\omega_d})$ and it is half of the Time period of Damped sinusoid.

so, note * First Undershoot = Time period of Damp Sinusoid = $T_d = \frac{2\pi}{\omega_d}$

(5) SETTLING TIME (t_s) :

$$t_s = \frac{4}{\xi \omega_n} = 4\tau$$

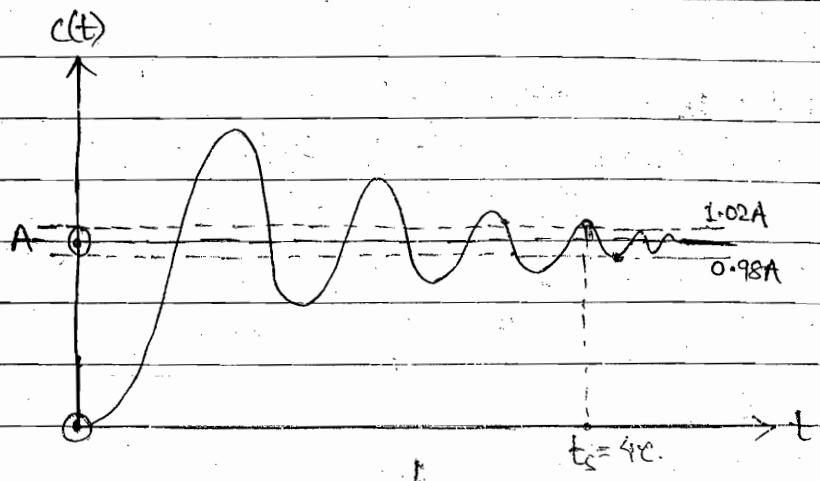
- In case of Settling time, in Underdamped system, it is defined as time when output will reach 98% of desired value or 102% of desired value.

$$t_s = 4\tau ; \text{ For } 2\% \text{ error-band}$$

$$t_s = 3\tau ; \text{ For } 5\% \text{ error-band.}$$

$$t_s = 4.62\tau ; \text{ For } 1\% \text{ error band.}$$

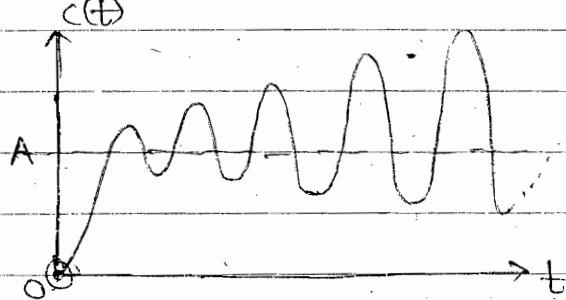
$$\text{No. of cycles} = \frac{t_s}{T_d}$$



* Subcase :- If exponential term is positive:

$$\text{for } c(t) = A \left[1 - e^{\frac{-\xi \omega_n t}{2}} \sin(\omega_n t + \phi) \right].$$

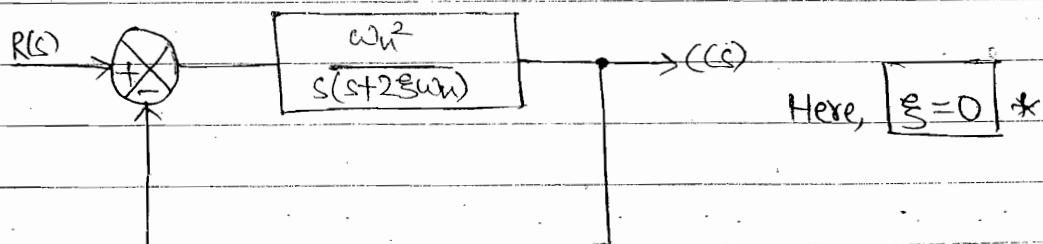
- Here, roots will lie on Right-half of s-plane and output response will be as shown :



* If Exponential term is negative, then with time, output will settle.

* If Exponential term is positive, with time output never settles.

Case-II :- Undamped system



$$\therefore \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2} \Rightarrow \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + \omega_n^2}$$

• For $R(s) = \frac{1}{s}$, $C(s) = \frac{Aw_n^2}{s(s+j\omega_n)(s-j\omega_n)}$

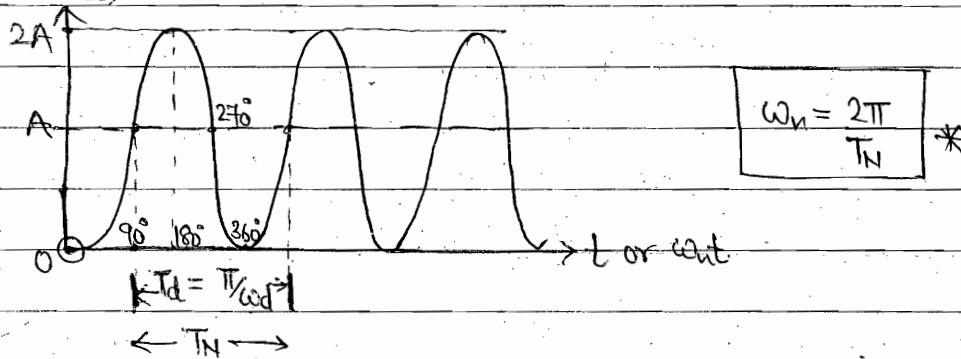
$$\therefore C(s) = \frac{A - A/2}{s} - \frac{A/2}{(s-j\omega_n)} - \frac{A/2}{(s+j\omega_n)}$$

$$\Rightarrow c(t) = A \left[1 - \frac{1}{2} \left(e^{j\omega_n t} + e^{-j\omega_n t} \right) \right].$$

$$c(t) = A \left[1 + \cos(\omega_n t) \right] \cdot u(t) *$$

• Here,

* * ω_n = Frequency of oscillation = Location of imaginary part of pole
 $c(t)$ or $c(j\omega_n)$



• Now, %M_{po} = $\frac{2A-A}{A} \times 100 = 100\%$

Also, %M_{pu} = $\frac{A-0}{A} \times 100 = 100\%$

* * In case of Undamped systems, Frequency of oscillation of output is : ω_n [as $\omega_n = \omega_d$ here].

* * But in Underdamped systems, frequency of oscillation of output is : ω_d . [$\omega_d = \omega_n \sqrt{1-S^2}$].

• In Undamped systems, %M_{po} and %M_{pu} remain constant i.e 100%.

* Case III > Critically Damped System

$$\text{Here, } \boxed{\xi = 1} * \quad C(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

$$\Rightarrow \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\omega_n s + \omega_n^2} = \frac{\omega_n^2}{(s + \omega_n)^2}$$

$$\tau = \frac{1}{\omega_n}; \quad t_s = 6\tau = 6/\omega_n.$$

$$\therefore C(s) = \frac{A}{s} - \frac{A\omega_n}{(s + \omega_n)^2} - A \quad [\text{for } R(s) = 1/s]$$

$$\therefore C(t) = A - A\omega_n t e^{-\omega_n t} - A e^{-\omega_n t}$$

$$\therefore \boxed{C(t) = A \left[1 - e^{-\omega_n t} \{ 1 + \omega_n t \}^2 \right]} *$$

$$\text{Now, } C(t_s = 6/\omega_n) = A \left[1 - e^{-\frac{\omega_n \times 6}{\omega_n}} \{ 1 + \omega_n \times \frac{6}{\omega_n} \}^2 \right] = A \left[1 - e^{-6} \right]^4$$

$$\boxed{C(6/\omega_n) = 0.91A} *$$

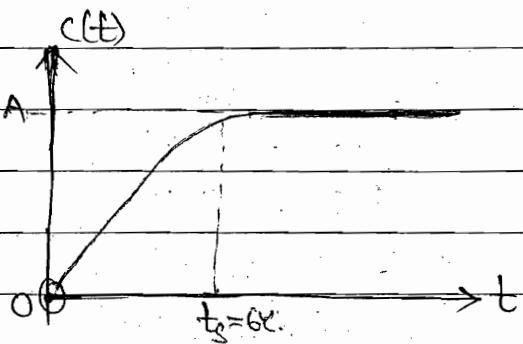
• Here, at $t = 6/\omega_n$, output has only reached to 91% with 9% error.
We can't apply 2% error-band criterion here, so in critically damped system, $t_s \neq 4\tau \neq 6/\omega_n$.

$$\text{So, } C(t = 6/\omega_n) = A \left[1 - e^{-\frac{\omega_n \times 6}{\omega_n}} \{ 1 + \omega_n \times \frac{6}{\omega_n} \}^2 \right] = A \left[1 - e^{-6} \right]^4$$

$$\therefore \boxed{C(6/\omega_n) = 0.983A} *$$

∴ At $t = 6\tau = 6/\omega_n$, output has reached 98.3%. So, using 2% error-band criterion, we can say that output has got settled.

$$\therefore \text{So, } \boxed{t_s = 6\tau = \frac{6}{\omega_n}} *$$



* Case IV:- Overdamped System

$$\text{Here, } \xi > 1 * \quad C(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

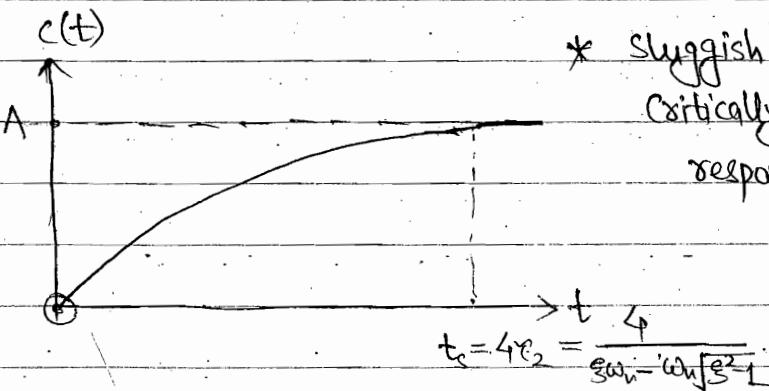
$$\therefore C(s) = \frac{\omega_n^2}{s^2 + \xi\omega_n s + \omega_n^2} \\ R(s) = (s + \xi\omega_n + \omega_n\sqrt{\xi^2 - 1})(s + \xi\omega_n - \omega_n\sqrt{\xi^2 - 1}).$$

$$\text{or for } R(s) = A_s.$$

$$\therefore C(s) = \frac{A\omega_n^2}{s(s + \xi\omega_n + \omega_n\sqrt{\xi^2 - 1})(s + \xi\omega_n - \omega_n\sqrt{\xi^2 - 1})}$$

$$\therefore C(s) = \frac{A}{s} + \frac{\frac{1}{2}\sqrt{\xi^2 - 1}(s + \sqrt{\xi^2 - 1})}{(s + \xi\omega_n + \omega_n\sqrt{\xi^2 - 1})} + \frac{\frac{1}{2}\sqrt{\xi^2 - 1}(s - \sqrt{\xi^2 - 1})}{(s + \xi\omega_n - \omega_n\sqrt{\xi^2 - 1})}$$

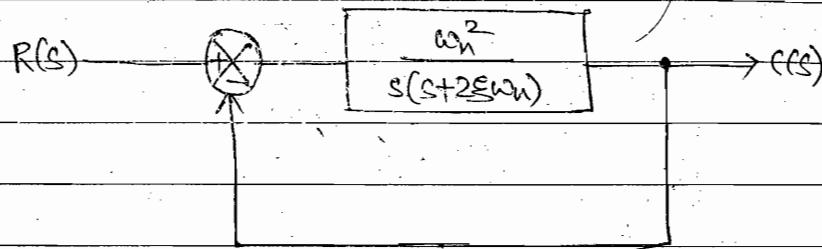
$$\therefore C(t) = A \left[1 - e^{-\frac{-(\xi\omega_n - \omega_n\sqrt{\xi^2 - 1})t}{2\sqrt{\xi^2 - 1}}} + \frac{e^{-\frac{-(\xi\omega_n + \omega_n)t}{2\sqrt{\xi^2 - 1}}}}{2\sqrt{\xi^2 - 1}} \right].$$



* Sluggish response than
critically damped system
response.

$$t_s = 4\zeta_2 = \frac{1}{\xi\omega_n - \omega_n\sqrt{\xi^2 - 1}}$$

* CLOSED LOOP SECOND ORDER SYSTEM FOR IMPULSE INPUT:



$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} \quad (1)$$

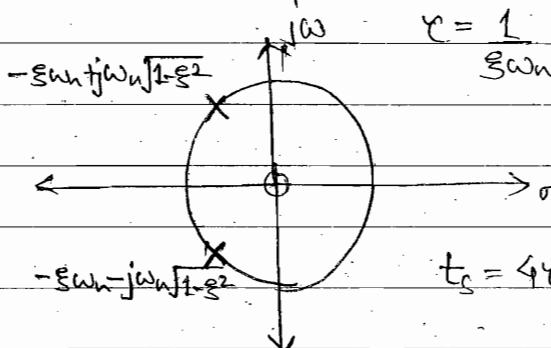
* Case-I: Under-damped System

• $\zeta < 1$

For $R(s) = A$.

∴ From eq-(1),

$$C(s) = \frac{A \cdot \omega_n^2}{(s + \zeta\omega_n - j\omega_n\sqrt{1-\zeta^2})(s + \zeta\omega_n + j\omega_n\sqrt{1-\zeta^2})}$$



$$t_s = 4\zeta = \frac{4}{\zeta\omega_n}$$

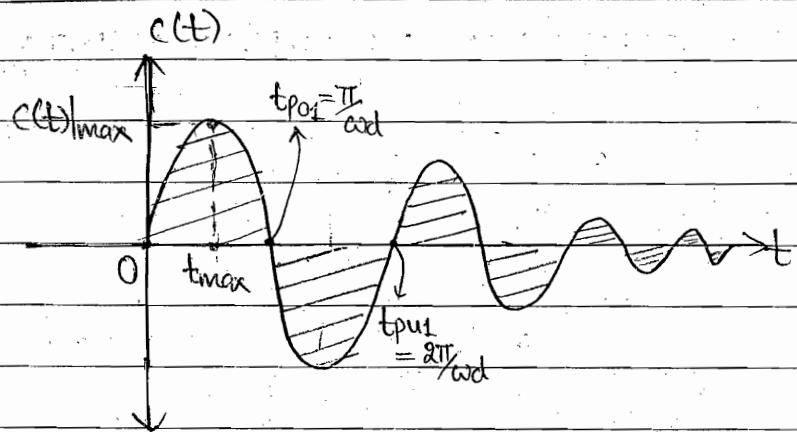
$$\omega_d = \omega_n \sqrt{1-\zeta^2}$$

$$\therefore C(s) = \frac{A\omega_n}{j\sqrt{1-\zeta^2}} \cdot \frac{-A\omega_n}{(j2)\sqrt{1-\zeta^2}} \cdot \frac{(s + \zeta\omega_n - j\omega_n\sqrt{1-\zeta^2})}{(s + \zeta\omega_n + j\omega_n\sqrt{1-\zeta^2} + s)}$$

$$\Rightarrow C(t) = \frac{A\omega_n}{\sqrt{1-\zeta^2}} \left[\frac{-e^{-\zeta\omega_n t} j\omega_n \sin(\omega_d t)}{e^{j\omega_d t} - e^{-j\omega_d t}} \right]$$

$$\Rightarrow C(t) = \frac{A\omega_n}{\sqrt{1-\zeta^2}} e^{-\zeta\omega_n t} \left[\frac{j\omega_d t - -j\omega_d t}{e^{j\omega_d t} - e^{-j\omega_d t}} \right]$$

$$C(t) = \frac{A \cdot \omega_n \cdot e^{-\zeta\omega_n t} \cdot \sin(\omega_d t) \cdot u(t)}{\sqrt{1-\zeta^2}} *$$



$$t_{\max} = \tan^{-1} \left(\frac{\sqrt{1-\xi^2}}{\xi} \right) = \phi \quad * \\ \frac{\omega_n \sqrt{1-\xi^2}}{\omega_d} \quad \omega_d$$

$$c(t)|_{\max} = A \cdot \omega_n \cdot e^{-\frac{\xi}{\sqrt{1-\xi^2}} \phi} \quad *$$

$$\therefore t_{p0n} = (2n-1) \frac{\pi}{\omega_d} \quad * \quad t_{p1n} = 2n \frac{\pi}{\omega_d} \quad * \quad \begin{cases} \text{in terms of} \\ \text{Area.} \end{cases}$$

- M_{p0} and M_{p1} are system's characteristics.

Here, % Mp(_{on}) = $\frac{\text{Maximum Area} - \text{Desired Value}}{\text{Desired Area}} \times 100\%$.

$$\% Mp(_{on}) = e^{-\frac{(2n-1)\pi\xi}{\sqrt{1-\xi^2}}} \times 100\%$$

and % Mp(_{un}) = $\frac{\text{Desired Area} - \text{Minimum Area}}{\text{Desired Area}} \times 100\%$

$$\% Mp(_{un}) = e^{-\frac{2n\pi\xi}{\sqrt{1-\xi^2}}} \times 100\%$$

- M_{p0} and M_{p1} percentage will remain constant and equal.

* % M_{p0} and % M_{p1} in both for Step as well as Impulse inputs will remain equal as they are system parameters and don't depend on Input applied.

* Their time constant and settling time will also be same.

$$t_c = 4\tau$$

$$\tau = 1 \text{ sec}$$

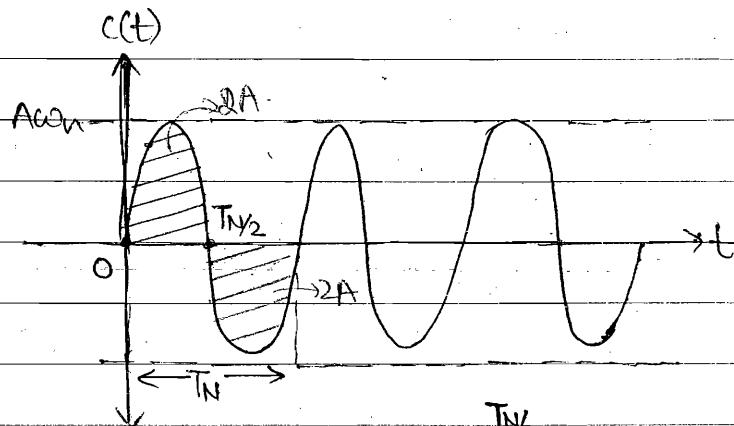
Case-II: Undamped system

$$\xi = 0 * \text{ From eq-1, } C(s) = \frac{\omega_n^2}{R(s)} = \frac{\omega_n^2}{s^2 + \omega_n^2}$$

For $R(s) = A$ [Impulse input].

$$\therefore C(s) = \frac{A \omega_n^2}{s^2 + \omega_n^2} = A \omega_n \cdot \frac{\omega_n}{s^2 + \omega_n^2}$$

$$C(t) = A \omega_n \cdot \sin(\omega_n t) \cdot u(t) * . \quad \omega_n = \omega_d = \frac{2\pi}{T_N}$$



$$\text{Area under curve} = \int_0^{T_N/2} c(t) \cdot dt = \int_0^{T_N/2} A \cdot \omega_n \cdot \sin(\omega_n t) \cdot dt$$

$$\Rightarrow \text{Area} = -A \omega_n \left[\cos(\omega_n t) \right]_0^{T_N/2} = -A \left[\cos\left(\frac{2\pi}{T_N} \times \frac{T_N}{2}\right) - \cos(0) \right]$$

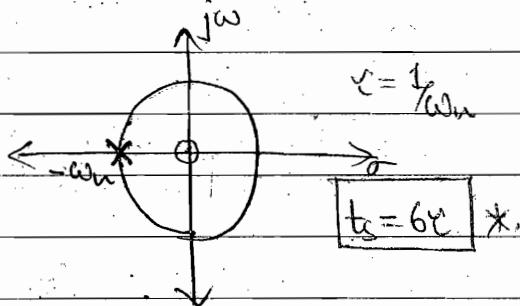
$$\therefore \text{Area} = 2A = \text{Same as in Step Input case} *$$

Case-III: Critically Damped System

$$\zeta = 1 * \text{ From eq.(1), } \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\omega_n s + \omega_n^2} = \frac{\omega_n^2}{(s + \omega_n)^2}$$

For Impulse input, $R(s) = A$.

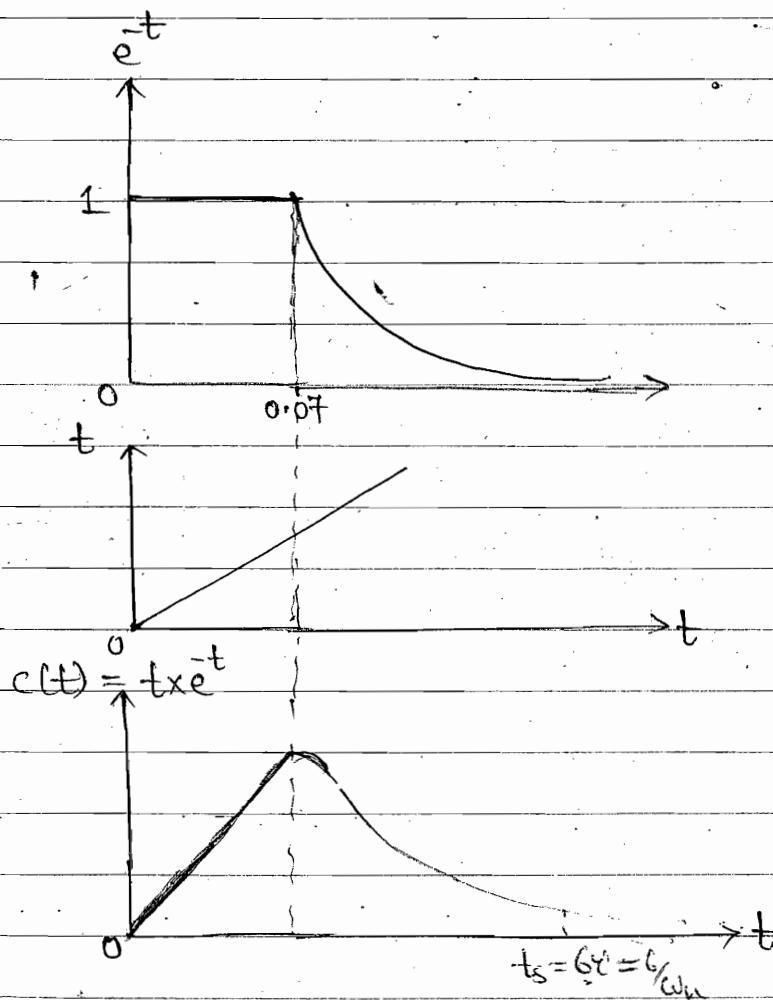
$$\therefore C(s) = \frac{A \cdot \omega_n^2}{(s + \omega_n)^2}$$



$$C(t) = A \cdot \omega_n^2 \cdot t \cdot e^{-\omega_n t} \cdot u(t) *$$

Plotting Output:

$$\text{Let, } A = \omega_n = 1, \quad C(t) = t \cdot e^{-t} \cdot u(t).$$



Case-IV:- Over-damped System

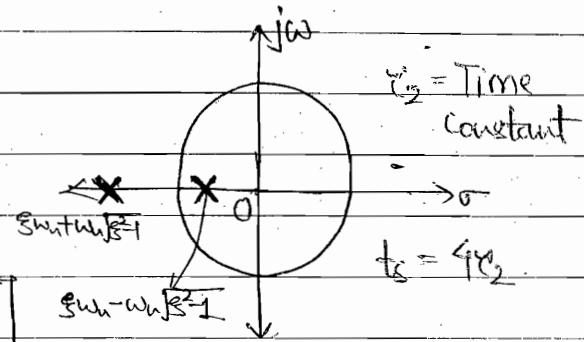
$$\boxed{\xi > 1} * \text{From eq-1, } \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

For Impulse input of $R(s) = A$,

$$\therefore C(s) = \frac{A \cdot \omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2} = \frac{A \cdot \omega_n^2}{(s + \xi\omega_n + \omega_n\sqrt{\xi^2 - 1})(s + \xi\omega_n - \omega_n\sqrt{\xi^2 - 1})}$$

$$C(s) = \frac{A \cdot \omega_n}{2\sqrt{\xi^2 - 1}} \cdot \frac{A \cdot \omega_n}{2\sqrt{\xi^2 - 1}}$$

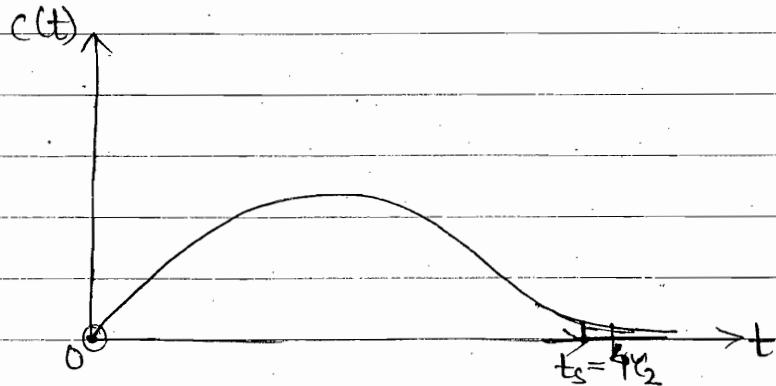
$$(s + \xi\omega_n - \omega_n\sqrt{\xi^2 - 1}) (s + \xi\omega_n + \omega_n\sqrt{\xi^2 - 1})$$



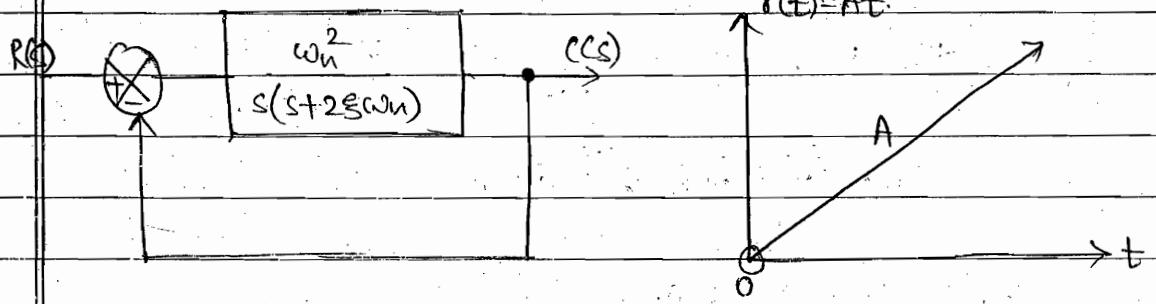
$$\therefore C(t) = \frac{A \cdot \omega_n}{2\sqrt{\xi^2 - 1}} \left[\frac{e^{-\xi\omega_n t} - e^{-\omega_n\sqrt{\xi^2 - 1}t}}{e^{-\xi\omega_n t} - e^{-\omega_n\sqrt{\xi^2 - 1}t}} \right]$$

$$\therefore C(t) = \frac{A \cdot \omega_n \cdot e^{-\xi\omega_n t}}{2\sqrt{\xi^2 - 1}} \left[\frac{e^{-\omega_n\sqrt{\xi^2 - 1}t} - e^{-\xi\omega_n t}}{2} \right]$$

$$\therefore C(t) = \frac{A \cdot \omega_n \cdot e^{-\xi\omega_n t}}{2\sqrt{\xi^2 - 1}} \left[\frac{e^{+\xi\omega_n t} - e^{-\xi\omega_n t}}{2} \right] *$$



* CLOSED LOOP SECOND ORDER SYSTEM FOR RAMP INPUT:



$$\therefore C(s) = \frac{A \cdot w_n^2}{s^2 + 2\xi w_n s + w_n^2} \quad (1)$$

* Case: Under-damped systems:

$\xi < 1$ * From eq-(1), Also, $R(s) = \frac{A}{s^2}$ [For Ramp Input].

$$\therefore C(s) = \frac{A \cdot w_n^2}{(s + \xi w_n - j\omega_d)(s + \xi w_n + j\omega_d)}$$

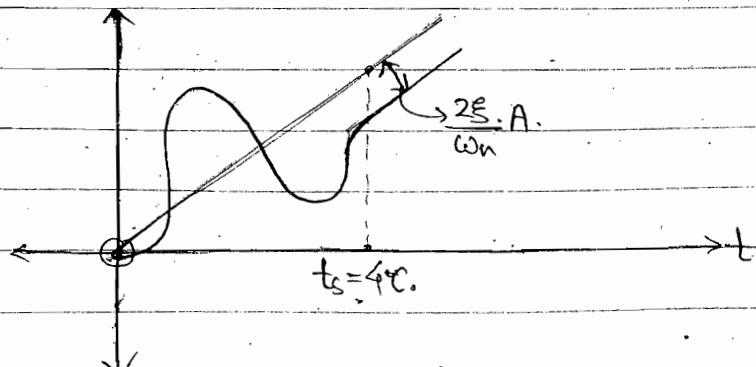
$$\text{or } C(s) = \frac{A \cdot w_n^2}{(s + \xi w_n - j\omega_d)(s + \xi w_n + j\omega_d)}$$

$$\therefore C(t) = A \left[1 - \frac{2\xi}{\omega_n} + \frac{e^{-\xi t}}{\omega_d} \sin(\omega_d t + \phi) \right] u(t) *$$

where,

$$\phi = \tan^{-1} \frac{2\xi \sqrt{1-\xi^2}}{2\xi^2 - 1} *$$

$C(t)$



→ Reason for Graph:

$$\tan \phi = \frac{2\zeta \sqrt{1-\zeta^2}}{2\zeta^2 - 1} = \frac{P}{B}$$

$$\therefore P = 2\zeta \sqrt{1-\zeta^2}; B = 2\zeta^2 - 1$$

$$H = \sqrt{P^2 + B^2} \Rightarrow H = 1$$

$$\therefore \sin \phi = 2\zeta \sqrt{1-\zeta^2}; \cos \phi = 2\zeta^2 - 1; t_s = \frac{4}{\zeta \omega_n}, \tau = \frac{1}{\zeta \omega_n}$$

$$\text{Now, } c(t) = [A - \frac{2\zeta A}{\omega_n} + \frac{A \cdot e^{-\zeta \omega_n t}}{\omega_d} \cdot \sin(\omega_d t + \phi)] \cdot u(t)$$

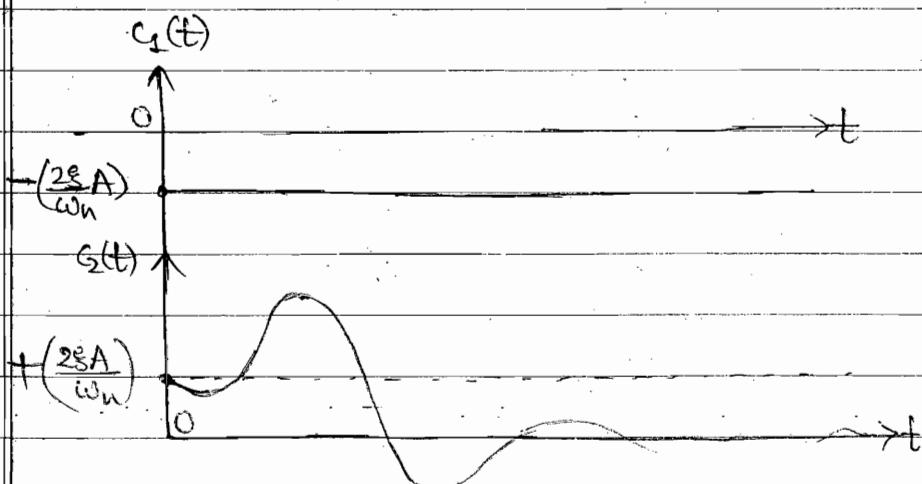
$$\therefore C_1 = -\frac{2\zeta A}{\omega_n}$$

$$C_2 = \frac{A \cdot e^{-\zeta \omega_n t}}{\omega_d} \sin(\omega_d t + \phi)$$

$$\text{Now, } C_2(t=0) = \frac{2\zeta A}{\omega_n}$$

$$C_2(t=4\tau) = \frac{A \times \sin[\omega_d \times \frac{4}{\zeta \omega_n} + \phi]}{\omega_d} \cdot e^{-4}$$

$$C_2(t=4\tau) = 0 *$$



Now, $c(t) = At - \frac{2\xi \cdot A}{\omega_n} t + c_2(t)$.

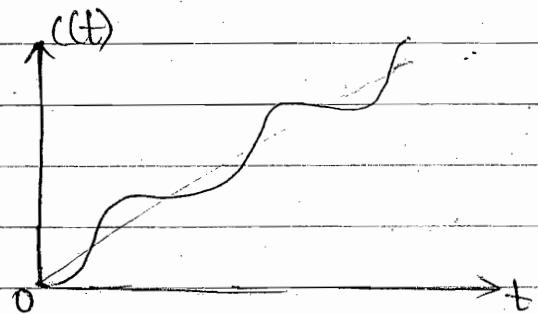
At $t=0$, $c(t=0) = 0 - \frac{2\xi \cdot A}{\omega_n} \cdot 0 + \frac{2\xi \cdot A}{\omega_n} \cdot 0 = 0$.

Case-II: Undamped System

$\xi = 0$ *

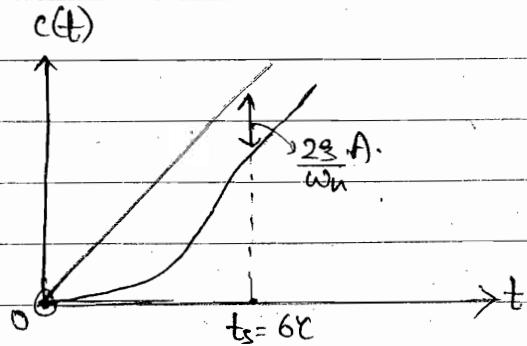
$$c(t) = At + \frac{A}{\omega_n} \sin \{\omega_n t + 180^\circ\} * \phi = 180^\circ = \tan^{-1}\left(\frac{0}{1}\right).$$

$\therefore [c(t) = At - \frac{A}{\omega_n} \sin(\omega_n t)] *$



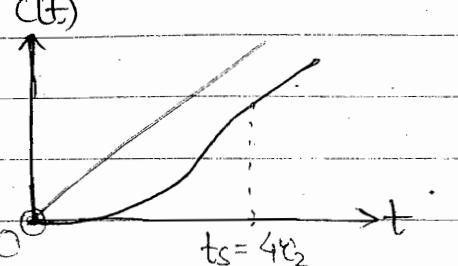
Case-III: Critically Damped System

$\xi = 1$ *



Case-IV: Overdamped Systems

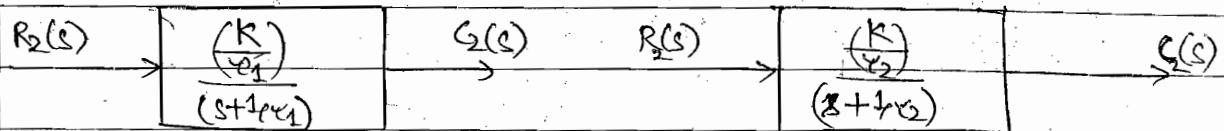
$\xi > 1$ *



* HIGHER ORDER SYSTEMS

Cascading of First Order System with First order System

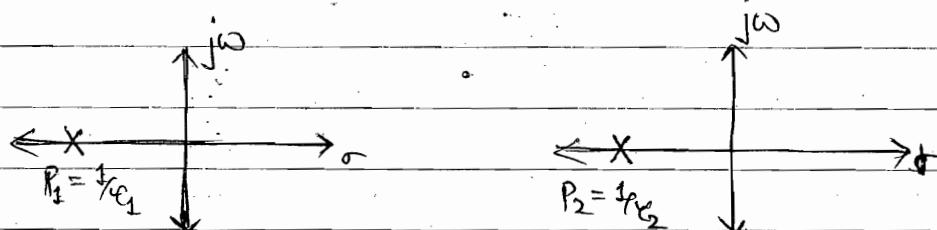
- If systems are not cascaded, then



$$\frac{G_1(s)}{R_1(s)} = \frac{(K_1 \cdot e_1)}{(s + \frac{1}{e_1})} \quad \frac{G_2(s)}{R_2(s)} = \frac{\frac{1}{e_2}}{(s + \frac{1}{e_2})}$$

For Impulse Input,

$$G_1(t) = K_1 \cdot P_1 \cdot e^{-P_1 t} \quad G_2(t) = \frac{1}{e_2} \cdot P_2 \cdot e^{-P_2 t}$$

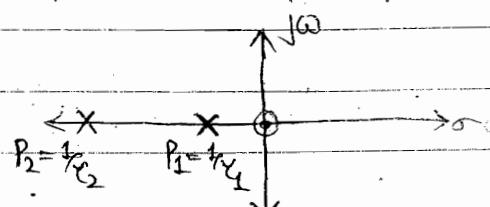


- Now, we cascade the two systems. So,



$$\therefore \frac{G(s)}{R(s)} = \frac{(K_1 \cdot e_1) \cdot (\frac{1}{e_2})}{(s + \frac{1}{e_1})(s + \frac{1}{e_2})} = \frac{(K_1 \cdot P_1) \cdot P_2}{(s + P_1)(s + P_2)}$$

- Here, system has become second order system with P_1 as Dominant Pole.



- For Impulse input;

$$C(s) = \frac{(K \cdot P_1) \cdot P_2}{(s + \tau_{\tau_1})(s + \tau_{\tau_2})} = \frac{(K \cdot P_1 \cdot P_2)/(P_2 - P_1)}{(s + P_1)} - \frac{(K \cdot P_1 \cdot P_2)/(P_2 - P_1)}{(s + P_2)}$$

$$\therefore C(t) = \frac{K \cdot P_1 \cdot P_2}{P_2 - P_1} \cdot \left[e^{-P_1 t} - e^{-P_2 t} \right] * \text{(Exact Analysis).} \quad \textcircled{1}$$

↓ Dominant Pole output

- We can convert Second order system into First order by
 - Approximation Method.

• If

$$\boxed{\frac{P_2 > 5}{P_1}} * \quad P_1 \text{ being Dominant pole, then 's' term of } P_2 \text{ can be equated to zero.}$$

$$\therefore \frac{C(s)}{R(s)} = \frac{K \cdot P_1 \cdot P_2}{(s + P_1)(s + P_2)}, \text{ so, put 's' term of } P_2 = 0.$$

$$\therefore \frac{C_{\text{approx}}(s)}{R(s)} = \frac{K \cdot P_1 \cdot P_2}{(s + P_1)(P_2)}$$

$$\therefore \boxed{\frac{C_{\text{approx}}(s)}{R(s)} = \frac{K \cdot P_1}{(s + P_1)}} *$$

* For Example :- $K = 100, P_1 = -2, P_2 = -5$.

* By Exact Analysis : $C(t) = \frac{100 \times 2 \times 5}{3} [e^{-2t} - e^{-5t}]$.

$$\boxed{C(t) = 42.85} * \quad \textcircled{1}$$

With $P_1 = -2, P_2 = -5$,

$$\frac{C_{\text{approx}}(s)}{R(s)} = \frac{100 \times 2 e^{-2t}}{3} = 27.06. \quad \textcircled{2}$$

- As by approximation, error exceeds the error band of 20%, so Approximation analysis can't be used.

similarly if $K=100$, $P_1 = -2$, $P_2 = -12$.

$$c(t) = \frac{100 \times 24}{10} [e^{-2t} - e^{-12t}] = 240 [e^{-2t} - e^{-12t}]$$

$$c(t) = 32.48 * \quad \text{--- (3)}$$

As, $\frac{P_2}{P_1} > 5$, we can use Approximation,

$$\therefore C_{app}(t) = 100 \times 2 e^{-2t} = 200 e^{-2t}$$

$$\therefore C_{app}(t) = 27.06 * \quad \text{--- (4)}$$

Here, error is below 20% error band, So we can use Approximate Analysis.

* From Exact Analysis eq(3), divide it by $P_1 \cdot P_2$,

$$\therefore c(t) = \frac{K}{\frac{1}{P_1} - \frac{1}{P_2}} [e^{-P_1 t} - e^{-P_2 t}]$$

If P_2 will be at infinity, then

$$c(t) = \frac{P_1 \cdot K}{1} [e^{-P_1 t}] * . \quad (\text{equation of First order system})$$

* As pole in any second order system moves towards Infinity, the second order systems will transform into first order systems.

* Consider a Fourth Order System:

$$C(s) = 288$$

$$R(s) = (s+2)(s+5)(s+12)(s+24).$$

As $R(s) = 1$ [Impulse].

$$c(t) = a_0 e^{-2t} + a_1 e^{-5t} + a_2 e^{-12t} + a_3 e^{-24t}. \quad [\text{Exact Analysis}]$$

$$c(t=1/6) = a_0 e^{-\frac{2}{3}} + a_1 e^{-\frac{5}{6}} + a_2 e^{-2} + a_3 e^{-4}, \rightarrow 0 \text{ (settles)}$$

$$c(t=1/3) = a_0 e^{-\frac{2}{3}} + a_1 e^{-\frac{5}{3}} + a_2 e^{-4} + a_3 e^{-8}, \rightarrow 0$$

$$c(t=4/5) = a_0 e^{-\frac{8}{5}} + a_1 e^{-4} + a_2 e^{-\frac{48}{5}} + a_3 e^{-\frac{96}{5}}, \rightarrow 0.$$

$$c(t=2) = a_0 e^{-4} + a_1 e^{-10} + a_2 e^{-24} + a_3 e^{-48}, \rightarrow 0.$$

Now, using Approximation,

$P_2 = 5$ can't be neglected.

But $P_3 = 12$ and $P_4 = 24$ can be neglected as: $\frac{P_4}{P_1} = \frac{P_3}{P_1} \gg 5$.

$$\therefore \frac{C(s)}{R(s)} = \frac{288}{(s+2)(s+5) \times 12 \times 24} = \frac{1}{(s+2)(s+5)}$$

\therefore For $R(s) = 1$ [Impulse input].

$$\therefore c(s) = \frac{1}{s+2} - \frac{1}{s+5}$$

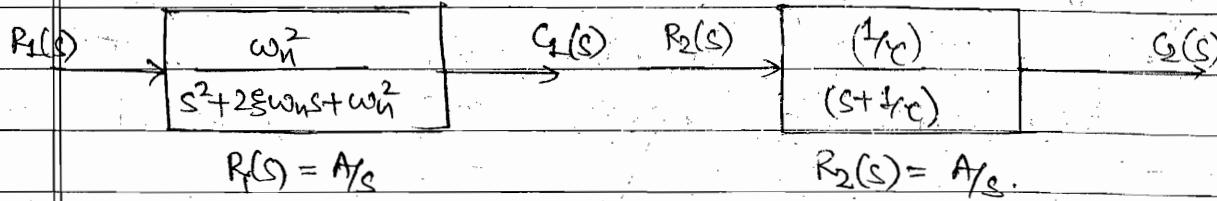
$$\Rightarrow c(t) = \frac{1}{3} [e^{-2t} - e^{-5t}] * (\text{Approximate Analysis}).$$

→ Higher Order systems (Continued...).

2 Cascading of Second order with First order system.

$$r_1(t) = A \cdot u(t)$$

$$r_2(t) = A \cdot u(t)$$

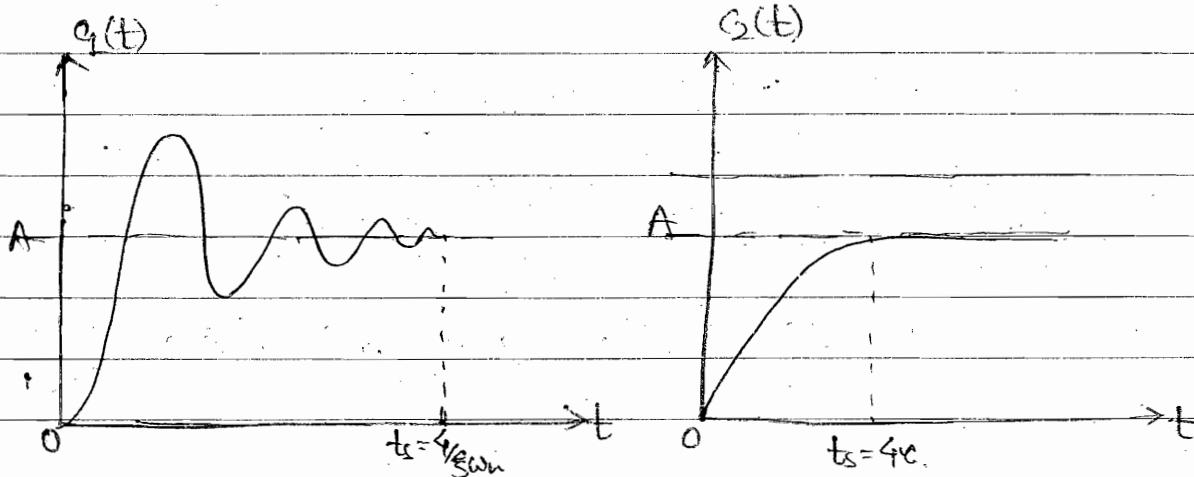


$$\frac{G_1(s)}{R_1(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

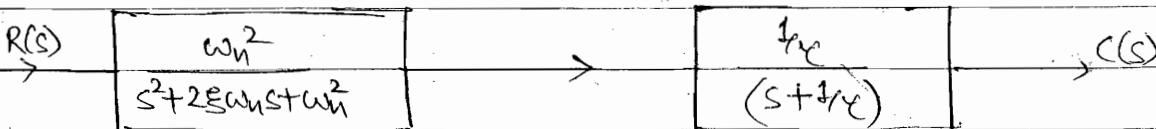
$$\frac{G_2(s)}{R_2(s)} = \frac{1/\tau_C}{s + 1/\tau_C}$$

$$c_1(t) = A \left[1 - \frac{e^{-\xi\omega_n t}}{\sqrt{1-\xi^2}} \sin(\omega_n t + \phi) \right]$$

$$c_2(t) = A \left[1 - e^{-t/\tau_C} \right].$$

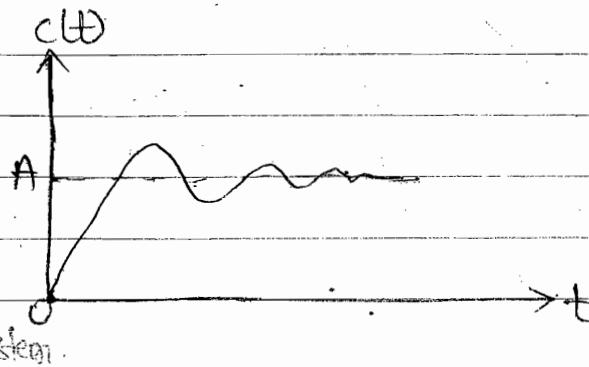


Now, if the two systems are cascaded, then,



- * It becomes Third order system, oscillation reduces but not fully.

- * t_s will remain same as that of 2nd order system.



** Case-I: Second order pole is Dominant Pole :)

- In this case, when II^{nd} order pole will come towards First order system, the % overshoot of III^{rd} order system will be less than pure II^{nd} order system.
- t_r of III^{rd} order system will be greater than t_r of pure II^{nd} order system, while t_s of III^{rd} and II^{nd} both systems will remain same.
- * When first order pole approaches closer towards II^{nd} order pole, % overshoot will further increase, t_r will also increase, t_s will remain same.

Now, $\tau_{fc} > \tau_{sw}$ or $1 > \zeta(\tau_{sw})$.

$$\therefore c(t) = A \left[1 - (-)^{\frac{-\pi}{\omega_n t}} e^{-\zeta \omega_n t} \sin(\omega_n t + \phi) \right] + e^{-t_r}$$

$$\text{For } c(t=4\tau_{sw}) = A \left[1 - (-)^{\frac{-4\pi}{\omega_n \tau_{sw}}} e^{-4\zeta \omega_n \tau_{sw}} \sin(\omega_n \tau_{sw} + \phi) \right] + e^{-4t_r}$$

\downarrow does not settle

$$c(t=4\tau_{sw}) = A \left[1 - (-)^{\frac{-4\pi}{\omega_n \tau_{sw}}} e^{-4\zeta \omega_n \tau_{sw}} \sin(\omega_n \tau_{sw} + \phi) \right] + e^{-4t_r}$$

\downarrow Both settle

** Case-II: Second order as well as First order pole are dominant :)

- When both the poles are dominant poles, the output response of third order system will be analogous to critically Damped Response of pure II^{nd} order system.

* t_s will remain same.

** Case-III: First order pole is Dominant Pole :)

- In this case, when Second order pole is cascaded with first order pole and 1st order pole is dominant pole, then output of III^{rd} order system will be analogous to overdamped system of pure II^{nd} order system and its t_s will be $4\tau_c$.

which is greater than t_s of pure II^{nd} order system.

Approximate Analysis for Case-I

$$\text{As } P_2 = \frac{1}{\zeta c}, \quad P_1 = \xi \omega_n$$

$$\frac{1}{\zeta c} > 5$$

$$\therefore T_{\text{approx}} = \frac{\omega_n^2 \times \frac{1}{\zeta c}}{(s^2 + 2\xi \omega_n s + \omega_n^2)(s + \frac{1}{\zeta c})}, \text{ put } s=0 \text{ in } (s + \frac{1}{\zeta c}).$$

$$\therefore T_{\text{Fapprox}} = \frac{\omega_n^2}{(s^2 + 2\xi \omega_n s + \omega_n^2)} \quad [\text{second order system}]$$

Approximate Analysis for case III

$$P_2 = \xi \omega_n, \quad P_1 = \frac{1}{\zeta c}.$$

$$\therefore \frac{P_2}{P_1} > 5 \Rightarrow \xi \omega_n > 5 \frac{1}{\zeta c}$$

$$\therefore T_{\text{Fapprox}} = \frac{\omega_n^2 \times \frac{1}{\zeta c}}{(s^2 + 2\xi \omega_n s + \omega_n^2)(s + \frac{1}{\zeta c})}, \text{ put } s=0 \text{ in II}^{\text{nd}} \text{ order.}$$

$$T_{\text{Fapprox}} = \frac{\frac{1}{\zeta c}}{(s + \frac{1}{\zeta c})}. \quad [\text{first order system}]$$

Ques: ① A third order system is approximated into second under-damped order system. What will be its effect on t_r of II^{nd} order system?

- (a) t_r will increase (b) t_r will decrease (c) remains same.

Ans: ① t_r will decrease, % overshoot will increase, t_s will remain same.

Ans (b).

Ques: ② $T(s) = \frac{100}{(s^2 + 2\xi \omega_n s + 1)(s + 10)}$, approximation into II^{nd} order system will be:-

- (a) $\frac{10}{(s^2 + 2s + 1)}$ (b) $\frac{100}{(s+10)}$ (c) $\frac{100}{(s^2 + 2s + 1)}$ (d) None.

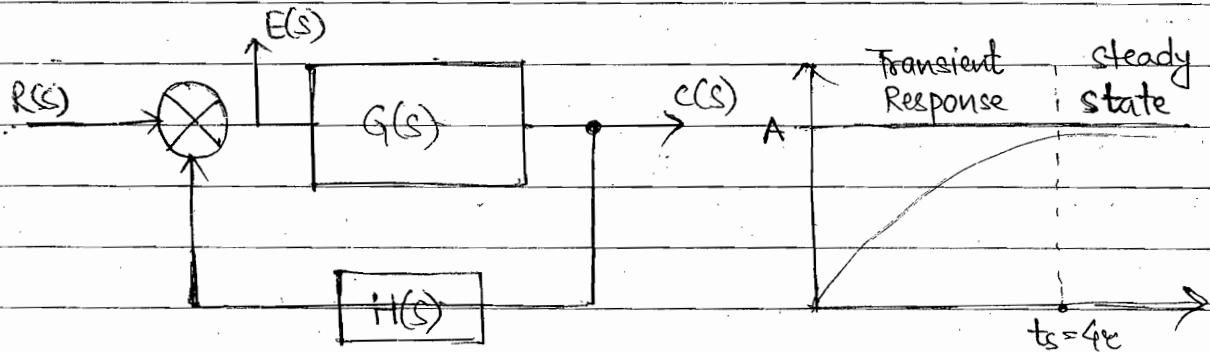
Ans:- (2) $\xi \omega_n = 1$, $c = \frac{1}{10}$

$\therefore \frac{10}{1} > 5 \Rightarrow$ Approximation can be used.

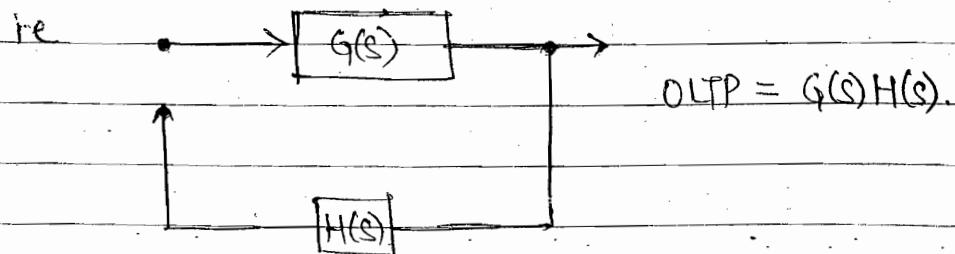
$$\therefore T = \frac{100}{(s^2 + 2s + 1)(10)}$$

$$\Rightarrow T_{app}(s) = \frac{10}{s^2 + 2s + 1} * \text{Ans (a).}$$

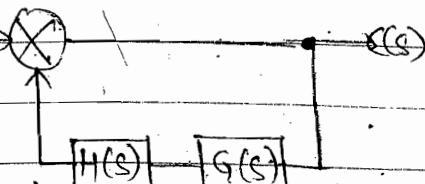
* STEADY STATE ERROR :



- If we withdraw summation from closed loop system, then closed loop system will convert into Open loop system whose Transfer function is: $G(s) \cdot H(s)$. and steady state error of closed loop system solely depends on its open loop transfer function.



Now, for block given below:



$$\frac{E(s)}{R(s)} = \frac{1}{1 + \{G(s) \cdot H(s)\}^2}$$

| | |
|------------------------------------|---|
| $E(s) = \frac{R(s)}{1 + G(s)H(s)}$ | * |
|------------------------------------|---|

| | |
|--|---|
| $\lim_{t \rightarrow \infty} e(t) = \lim_{s \rightarrow 0} s \cdot E(s) = \lim_{s \rightarrow 0} \frac{sR(s)}{1 + G(s)H(s)}$ | * |
|--|---|

Case-I: For Step Input ↴

$$R(s) = A/s$$

$$e_{ss} = \lim_{s \rightarrow 0} \frac{A \cdot s \cdot s/s}{1 + G(s)H(s)} = \frac{A}{1 + \lim_{s \rightarrow 0} \{G(s)H(s)\}}$$

| | | | |
|----|------------------------------|---|---|
| or | $e_{ss} = \frac{A}{1 + k_p}$ | * | k_p = Positional Error Constant or co-efficient. |
|----|------------------------------|---|---|

| | |
|---|---|
| $k_p = \lim_{s \rightarrow 0} G(s)H(s)$ | * |
|---|---|

Case-II: For Ramp Input ↴

$$R(s) = A/s^2$$

$$e_{ss} = \lim_{s \rightarrow 0} \frac{A/s}{1 + G(s)H(s)} = \frac{A}{\lim_{s \rightarrow 0} (s + sG(s)H(s))}$$

| | | |
|--------------------------|---|------------------|
| $e_{ss} = \frac{A}{k_v}$ | * | k_v = Position |
|--------------------------|---|------------------|

k_v = Velocity Error Constant or Coefficient

| | |
|---|---|
| $k_v = \lim_{s \rightarrow 0} s \cdot G(s)H(s)$ | * |
|---|---|

** Case-III: For Parabolic Input:

$$R(s) = A \frac{1}{s^2} \quad (\gamma(t) = At^2/2)$$

$$\therefore e_{ss} = \lim_{s \rightarrow 0} \frac{A/s^2}{1 + G(s)H(s)}$$

$$e_{ss} = \lim_{s \rightarrow 0} \frac{A}{s^2 + s^2 G(s)H(s)} = \frac{A}{0 + \lim_{s \rightarrow 0} s^2 G(s)H(s)}$$

$$\therefore e_{ss} = \frac{A}{K_a} \quad * \quad K_a = \text{Acceleration Error Constant or Co-efficient.}$$

$$K_a = \lim_{s \rightarrow 0} s^2 G(s)H(s) \quad *$$

* Type and order of the System:

** Type:

- It is defined by total number of poles locating at origin and order is defined by total number of poles in a system.

- Type and order of a system is defined by its open loop transfer function.

** Type 0 System:

$$\text{Example: } G(s)H(s) = \frac{K(sT_1+1)(sT_2+1)}{(sT_3+1)(sT_4+1)}$$

- Here $K = \text{DC gain of the system here.}$

$$s_2 = -\frac{1}{T_1} > -\frac{1}{T_2}$$

$$s_p = -\frac{1}{T_3}, -\frac{1}{T_4}$$

1) For Step Input:

$$\therefore K_p = \lim_{s \rightarrow 0} G(s)H(s) = K \text{ (DC gain).}$$

$$\therefore K_p = K = \text{DC Gain} \quad *$$

$$e_{ss} = A = \frac{A}{1+K} = \text{Finite} \quad *$$

2) For Ramp Input:

$$K_r = \lim_{s \rightarrow 0} s \cdot G(s)H(s) = \lim_{s \rightarrow 0} \frac{s \times (sT_1+1)(sT_2+1)}{(sT_3+1)(sT_4+1)}$$

$$\therefore K_r = 0 \quad * \quad e_{ss} = \infty \quad *$$

3) For Parabolic Input:

$$K_d = \lim_{s \rightarrow 0} s^2 \cdot G(s)H(s) \Rightarrow K_d = 0 \quad * \quad e_{ss} = \infty \quad *$$

** Type 1 System:

$$* \text{ Example: } G(s)H(s) = \frac{K(sT_1+1)(sT_2+1)}{s(sT_3+1)(sT_4+1)} \quad [\text{order} = 3, \text{Type} = 1]$$

1) For Step Input:

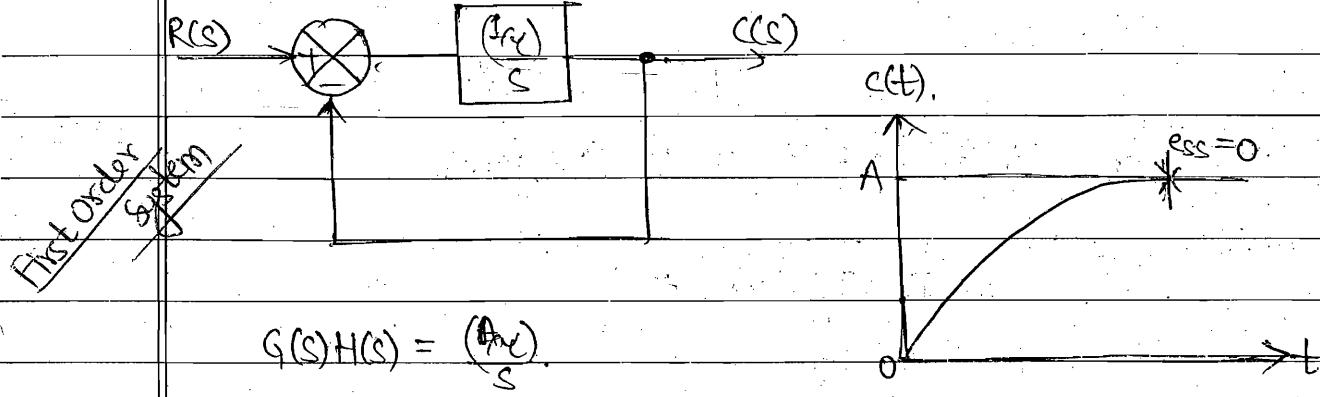
$$K_p = \lim_{s \rightarrow 0} G(s)H(s) = \frac{1}{0} \Rightarrow K_p = \infty \quad * \quad e_{ss} \approx 0 \quad *$$

2) For Ramp Input:

$$K_r = \lim_{s \rightarrow 0} s \cdot G(s)H(s) = K \Rightarrow K_r = K = \text{DC Gain} \quad * \quad e_{ss} = \frac{A}{K} \quad *$$

3) For Parabolic Input:

$$K_d = \lim_{s \rightarrow 0} s^2 \cdot G(s) \cdot H(s) = 0 \Rightarrow K_d = 0 \quad * \quad e_{ss} = \infty \quad *$$

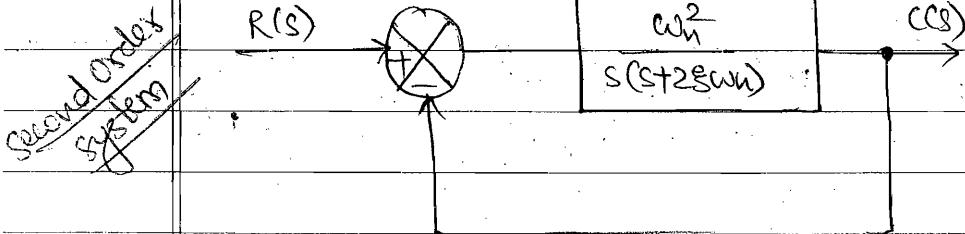
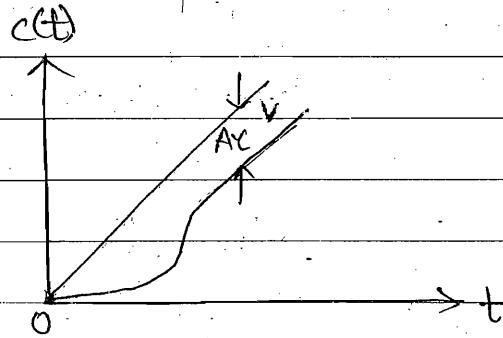


$$\therefore k_p = \lim_{s \rightarrow 0} s \cdot \frac{1}{s} = \infty$$

$$\therefore e_{ss} \approx 0 *$$

$$\therefore k_v = \lim_{s \rightarrow 0} s \cdot \frac{1}{(s)} = \frac{A}{C}$$

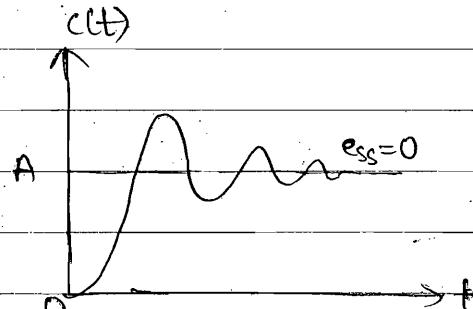
$$\therefore e_{ss} = Ay *$$



$$G(s)H(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s}$$

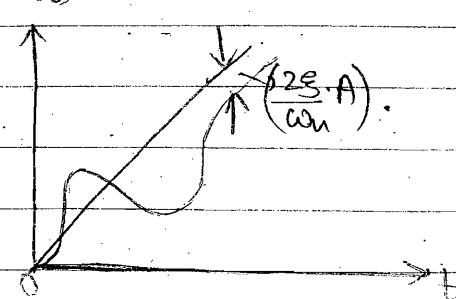
$$\therefore k_p = \lim_{s \rightarrow 0} \frac{\omega_n^2}{s(s+2\xi\omega_n)} = \infty$$

$$e_{ss} = 0 *$$



$$\therefore k_v = \lim_{s \rightarrow 0} s \cdot \frac{\omega_n^2}{s^2 + 2\xi\omega_n s} = \frac{\omega_n}{2\xi}$$

$$e_{ss} = \frac{2\xi \cdot A}{\omega_n} *$$



* Type 2-system

Example: $G(s)H(s) = \frac{K}{s^2(sT_3+1)(sT_4+1)} [Type \rightarrow 2, Order \rightarrow 4]$

1) For step Input

$$K_p = \lim_{s \rightarrow 0} G(s)H(s) \Rightarrow K_p = \infty * e_{ss} = 0 *$$

2) For Ramp Input

$$K_v = \lim_{s \rightarrow 0} s \cdot G(s)H(s) \Rightarrow K_v = \infty * e_{ss} = 0 *$$

3) For Parabolic Input

$$K_a = \lim_{s \rightarrow 0} s^2 \cdot G(s)H(s) \Rightarrow K_a = K = DC \text{ Gain} * e_{ss} = A = \frac{A}{K_a} *$$

- * Increasing type of a system will reduce Steady state error but it also reduces stability of the system.

* DYNAMIC ERROR CO-EFFICIENT

$$As \quad E(s) = \frac{1}{R(s) + G(s)H(s)}$$

Using Long Division,

$$\frac{1}{1 + G(s)H(s)} \quad 1 \quad (C_0 + C_1s + C_2s^2)$$

$$\frac{E(s)}{R(s)} = C_0 + C_1(s) + C_2(s)$$

where C_0, C_1 and C_2 are dynamic error coefficients.

$$\therefore \frac{E(s)}{R(s)} = C_0 + C_1(s) + C_2(s) = \frac{1}{1 + K_p} + \frac{s}{K_v} + \frac{s^2}{K_a}$$

because, $G_0 = \frac{1}{1+K_p}$; $G_1(s) = \frac{s}{K_V}$, $G_2(s) = \frac{s^2}{K_A}$

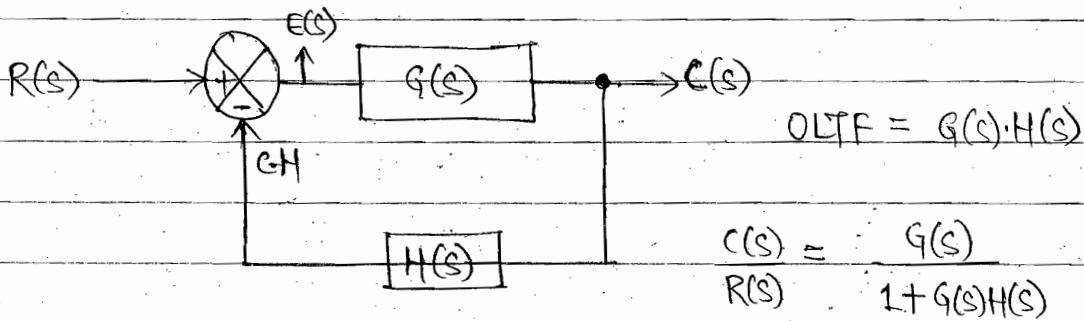
$$\therefore E(s) = \frac{R(s)}{1+K_p} + \frac{s \cdot R(s)}{K_V} + \frac{s^2 \cdot R(s)}{K_A}$$

$$\Rightarrow e(t) = \left[\frac{r(t)}{1+K_p} + \frac{\{ \frac{d}{dt} r(t) \}}{K_V} + \frac{\{ \frac{d^2}{dt^2} r(t) \}}{K_A} \right]$$

Taking time $\rightarrow \infty$ under limits,

$$\therefore e_{ss} = \lim_{t \rightarrow \infty} \left[\frac{r(t)}{1+K_p} + \frac{\{ \frac{d}{dt} r(t) \}}{K_V} + \frac{\{ \frac{d^2}{dt^2} r(t) \}}{K_A} \right] *$$

* UNITY FEEDBACK SYSTEM



Now, we will convert this non-unity feedback system to unity feedback system having same Closed Loop Transfer function.

$$* \frac{C(s)}{R(s)} = \frac{G(s)}{1 + G(s)H(s)} = \frac{G'(s)}{1 + G'(s)}$$

$$\Rightarrow G(s)[1 + G'(s)] = G'(s)[1 + G(s)H(s)].$$

$$\Rightarrow G'(s) = \frac{G(s)}{1 + G(s)H(s) - G(s)} *$$

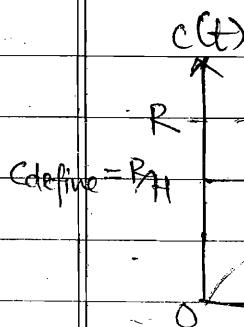
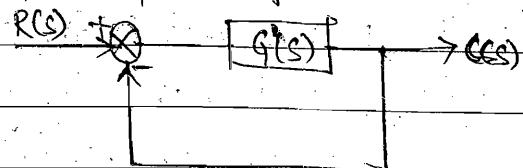
$$\therefore \text{OLTF of u.f.b system} = G'(s) = \frac{G(s)}{1 + G(s)H(s) - G(s)} *$$

- Point to be noted here is that:

Both non-unity feedback system and u.f.b will have same closed Loop transfer function but Open Loop Transfer Functions of both will be different.

$$C(s) = \frac{R(s) \cdot G(s)}{1 + G(s)H(s)}$$

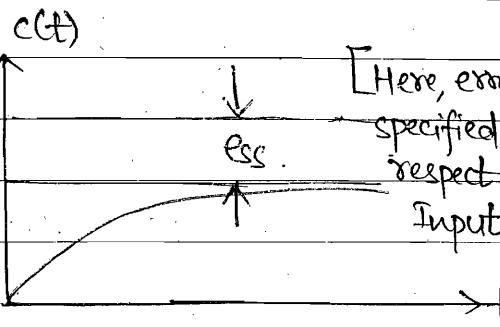
$$C(s) = \frac{G'(s) \cdot R(s)}{1 + G'(s)} = \frac{G(s) \cdot R(s)}{1 + G(s)H(s)}$$



$$E = R - C$$

For $E = 0$,

$$C_{\text{define}} = \frac{R}{H} *$$



$$E = R - C$$

for $E = 0$,

$$R = C_{\text{define}} *$$

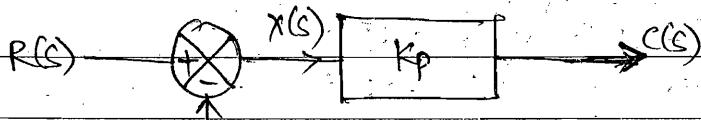
[Here, error is specified with respect to Input]

Chapter: 3

CONTROLLERS

1) Proportional Controller:

- It represents Gain of the system. It is zero-order system because it does not contain either pole or zero.

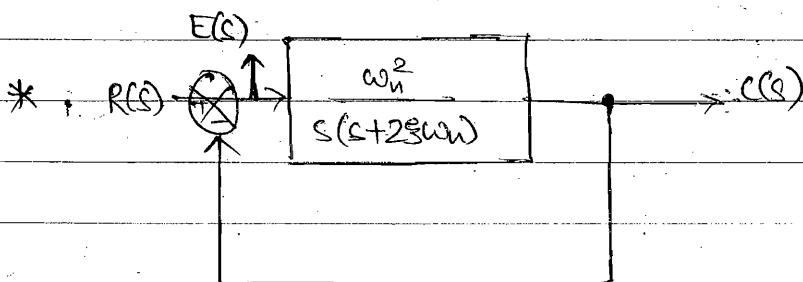
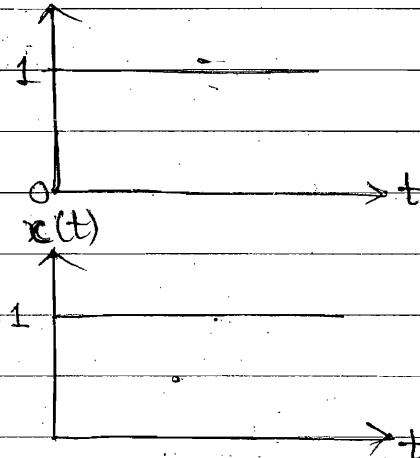


$$x(t) = u(t)$$

$$\frac{C(s)}{X(s)} = K_p$$

$$C(s) = K_p X(s).$$

$$C(t) = K_p \cdot x(t) *$$



$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

$$\Rightarrow s^2 + 2\xi\omega_n s + \omega_n^2 = 0.$$

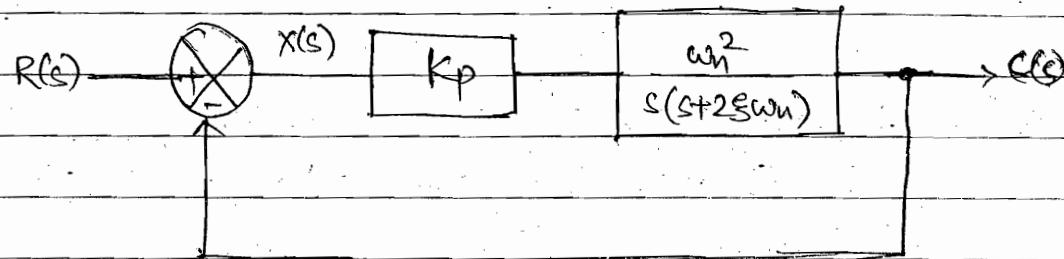
$$s_{1,2} = -\xi\omega_n \pm j\omega_n \sqrt{1-\xi^2}$$

Now, Open Loop T.F. = $\frac{\omega_n^2}{s(s+2\zeta\omega_n)}$

$$\therefore k_v = \lim_{s \rightarrow 0} s \cdot \frac{\omega_n^2}{s(s+2\zeta\omega_n)} \Rightarrow k_v = \frac{\omega_n}{2\zeta}$$

$$e_{ss} = \frac{2\zeta \cdot A}{\omega_n} *$$

Now, when Proportional controller is applied in system:



$$G(s) \cdot H(s) = \frac{K_p \cdot \omega_n^2}{s(s+2\zeta\omega_n)}$$

$$\text{Now, } \frac{C(s)}{R(s)} = \frac{K_p \cdot \omega_n^2}{s^2 + 2\zeta\omega_n s + K_p \cdot \omega_n^2}$$

$$\therefore s^2 + 2\zeta\omega_n s + K_p \cdot \omega_n^2 = 0$$

$$\therefore s^2 + 2\zeta\omega_n' s + (\omega_n')^2 = 0.$$

$$\therefore \omega_n' = \sqrt{K_p \cdot \omega_n} *, \quad \xi' = \frac{\zeta}{\sqrt{K_p}} *$$

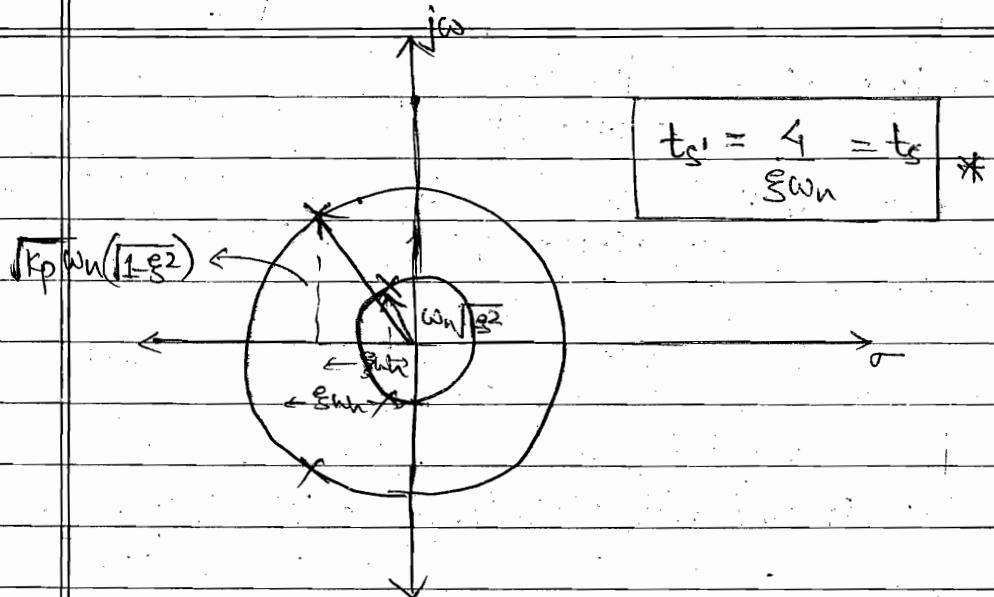
$$s_{1,2} = -\xi' \omega_n' \pm j \omega_n' \sqrt{1 - \xi'^2}$$

$$\therefore s_{1,2} = -\frac{\xi}{\sqrt{K_p}} \cdot \sqrt{K_p \cdot \omega_n} \pm j \cdot \sqrt{K_p \cdot \omega_n} \sqrt{1 - \frac{\xi^2}{K_p}}$$

$$s_{1,2} = -\xi \omega_n \pm j \sqrt{K_p \cdot \omega_n} \sqrt{1 - \frac{\xi^2}{K_p}}$$

* Location of poles
for controller used
control system.

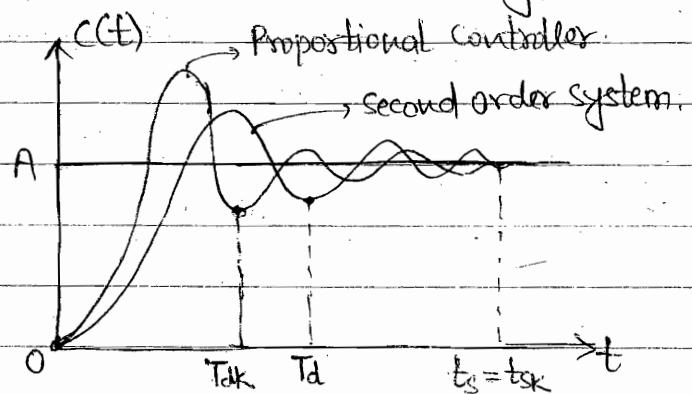
So, Real part will be same but imaginary part will change.



* With application of Proportional Controller :-

* ζ will decrease by factor of $\sqrt{K_p}$, as a result, %Mp will increase, t_r will decrease while settling time will remain same.

* Stability will remain unaffected because stability is defined in terms of, "Distance of poles from Imaginary axis" and that distance is same for both the system.



$$\omega_d = \omega_n \sqrt{1 - \zeta^2} ; \quad \omega_{dk} = \sqrt{K_p \cdot \omega_n \frac{1 - \zeta^2}{K_p}}$$

$$\therefore \frac{2\pi}{\omega_{dk}} = T_{dk} \text{ or } \frac{2\pi}{T_{dk}} = \omega_{dk} > \omega_d = \frac{2\pi}{T_d}$$

$$\therefore \boxed{T_{dk} < T_d} *$$

** With application of Proportional controller :-

* Damped Angular frequency will increase. As a result, Time period of Damped oscillation will decrease. Hence number of oscillation cycles upto t_r will also increase.

Now, e_{ss} will be :

$$K_V = \lim_{s \rightarrow 0} s \times \frac{K_p \omega_n^2}{s(s+2\zeta\omega_n)} \Rightarrow K_V = \frac{K_p \omega_n}{2\zeta} *$$

$$e_{ss} = \frac{R_s}{K_V}$$

$$e_{ss} = \frac{2\zeta \cdot A}{K_p \omega_n} *$$

- * With application of Proportional controller :

- * Steady State Error will decrease by a factor of K_p .

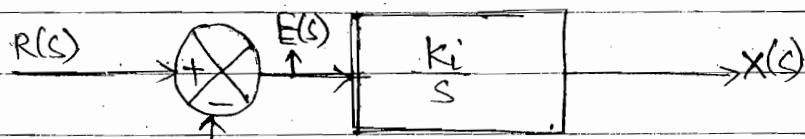
- Proportional controller does not affect Time Constant and it affects only frequency parameter which is Undamped Natural Frequency (ω_n).

3) Integral Controller :

- Integral controller is used to suppress Offset Error.

* Offset Error :- It is defined as, "Error in output when input is 0".

Thus, whenever we want to reduce e_{ss} , we use Integral controller but the drawback of it is that, to reduce e_{ss} , number of oscillation cycles gets increased. As a result, t_s will increase and stability will decrease.



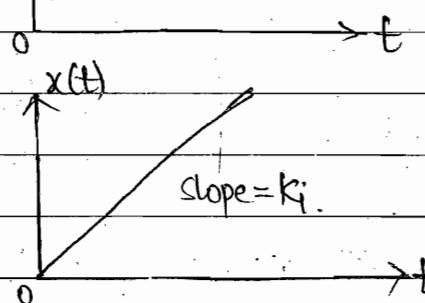
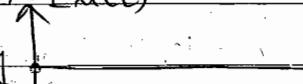
$$\frac{X(s)}{E(s)} = \frac{K_i}{s} \Rightarrow X(s) = K_i \left[\frac{E(s)}{s} \right]$$

$$\Rightarrow x(t) = K_i \int e(t) dt$$

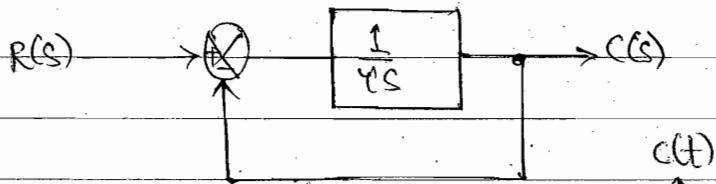
$$\therefore x(t) = K_i \int e(t) dt *$$

∴ For $e(t) = 1 \cdot u(t)$. ∴ $x(t) = k_i \int 1 \cdot dt$.

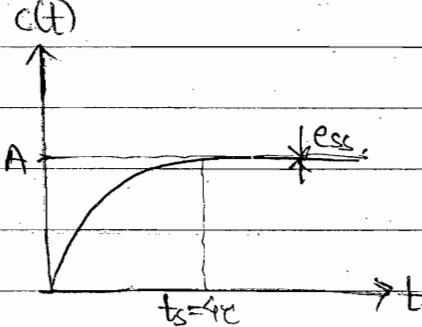
$$\therefore x(t) = k_i t \quad * \quad e(t) = 1 \cdot u(t)$$



* Now, consider a first order system. ↴



$$\frac{C(s)}{R(s)} = \frac{1/T_c}{s + 1/T_c}$$

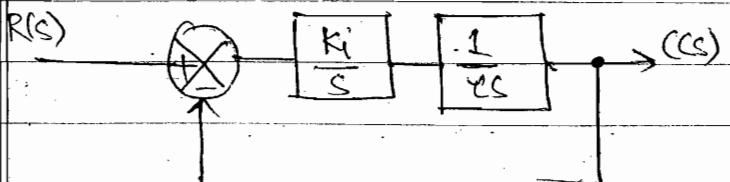


$$\text{Apply } R(s) = A/s$$

$$\therefore C(s) = \frac{(A/s)}{s + 1/T_c} \Rightarrow C(t) = A [1 - e^{-t/T_c}]$$

$$e(t) = A e^{-t/T_c} \quad *$$

Now, applying integral controller to this 1st order system:

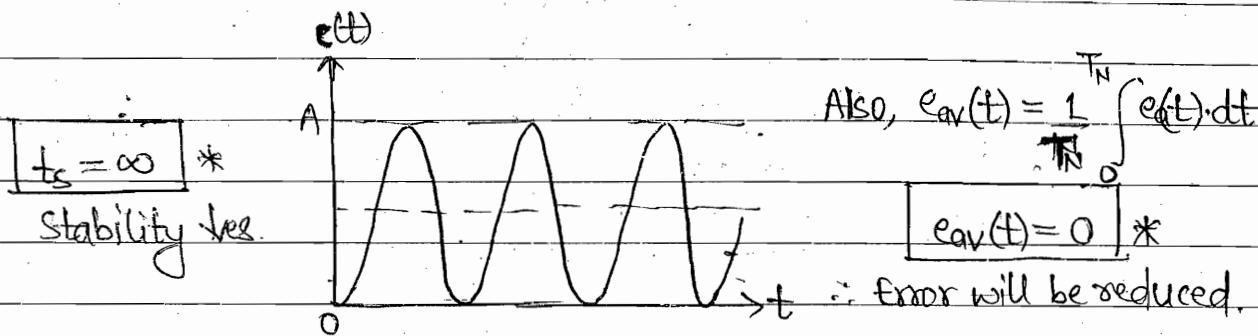


$$\frac{C(s)}{R(s)} = \frac{(K_i/s)}{s^2 + (K_i/T_c)} \quad \text{, Here poles come on Imaginary axis, system becomes Marginally stable when Integral controller is}$$

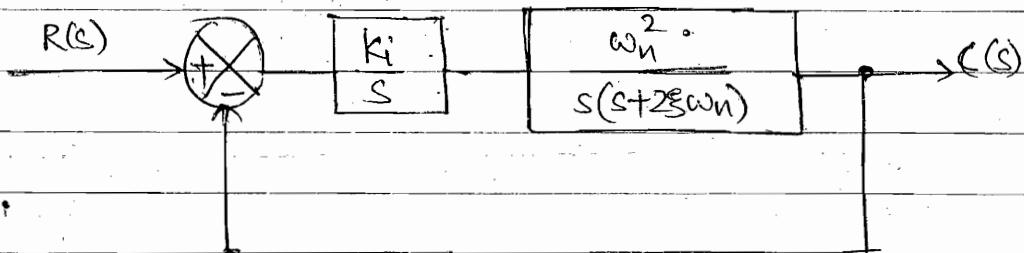
∴ For $r(t) = A \cdot u(t)$, $R(s) = A/s$,

$$\therefore C(s) = \frac{(A \cdot k_i / \omega)}{s(s^2 + k_i/\omega)} \quad \therefore C(t) = A \left[1 - \cos \sqrt{\frac{k_i}{\omega}} t \right] \quad (*)$$

$$e(t) = A \cdot \cos \left(\sqrt{\frac{k_i}{\omega}} t \right) \quad (*)$$



Now, applying integral controller to second order system:



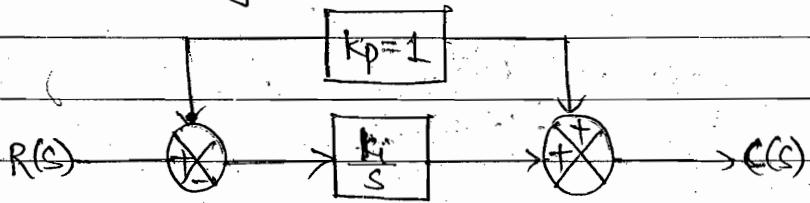
$$G(s) = \frac{k_i \omega_n^2}{s^2(s + 2\zeta\omega_n)}$$

$$\therefore g(s) = s^3 + 2\zeta\omega_n^2 s + k_i \cdot \omega_n^2 = 0. \Rightarrow \text{Making system Unstable.}$$

** Here, we will not apply integral controller directly into second order system because integral controller will convert a stable IInd order system into unstable IIIrd order system.

* As seen from $g(s)$, s^1 is missing which represents that atleast one pole will locate in the right-half side and system will be unstable. To overcome this, PI controller is used.

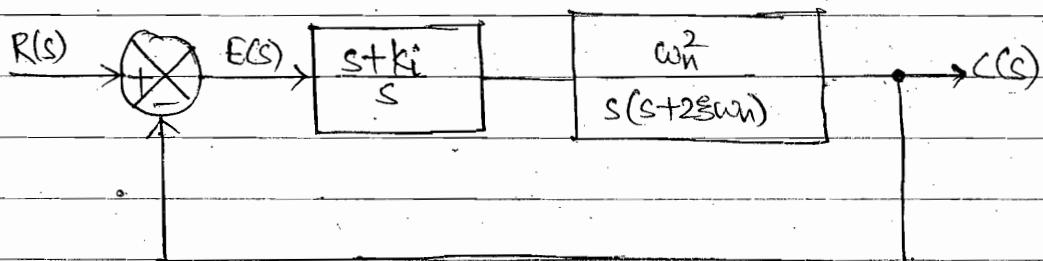
3, Proportional Integral (PI) controller:



$$\therefore \frac{C(s)}{R(s)} = k_p + \frac{k_i}{s} = \frac{s k_p + k_i}{s}$$

For $k_p = 1$, $\frac{C(s)}{R(s)} = \left(\frac{k_i s}{s} \right)$.

- PI will add pole at origin as well as one zero at location other than zero.



$$\therefore \frac{C(s)}{R(s)} = \frac{(s+k_i) \cdot w_n^2}{s^3 + 2s_w n s^2 + w_n^2 s + k_i w_n^2}$$

$$\therefore q(s) = s^3 + 2s_w n s^2 + w_n^2 s + k_i w_n^2 = 0$$

* For stable system, condition is :- $2s_w n > k_i$

- Using Routh-Hurwitz criteria:

| | | |
|-------|------------------------|-------------|
| s^3 | 1 | w_n^2 |
| s^2 | $2s_w n$ | $k_i w_n^2$ |
| s^1 | $(2s_w n - k_i) w_n^2$ | |
| s^0 | $k_i w_n^2$ | |

- For always Stable system, $2\zeta\omega_n - k_i > 0$

$$2\zeta\omega_n > k_i \quad *$$

Put $k_i = 0$ now,

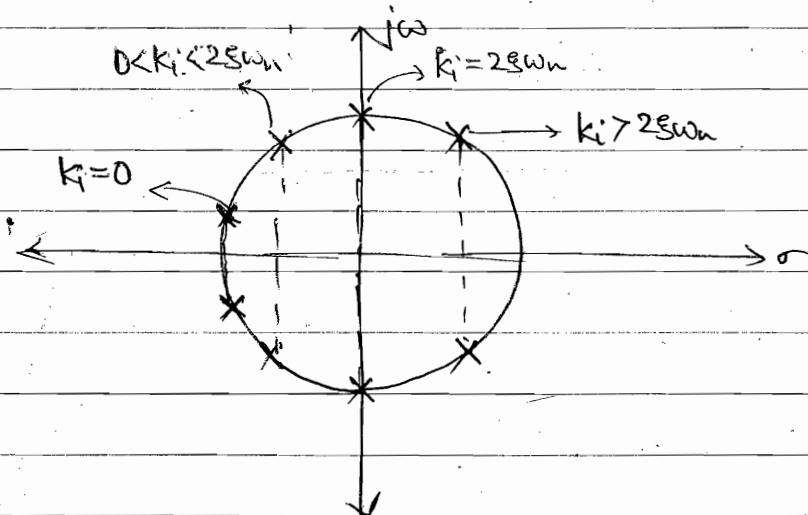
$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} \quad [\text{Second order system}]$$

Now, if $0 < k_i < 2\zeta\omega_n$, Poles will shift towards Right side.

For $k_i = 2\zeta\omega_n$, Poles will lie on Imaginary axis now.

For $k_i > 2\zeta\omega_n$, Poles will shift finally on Right-half.

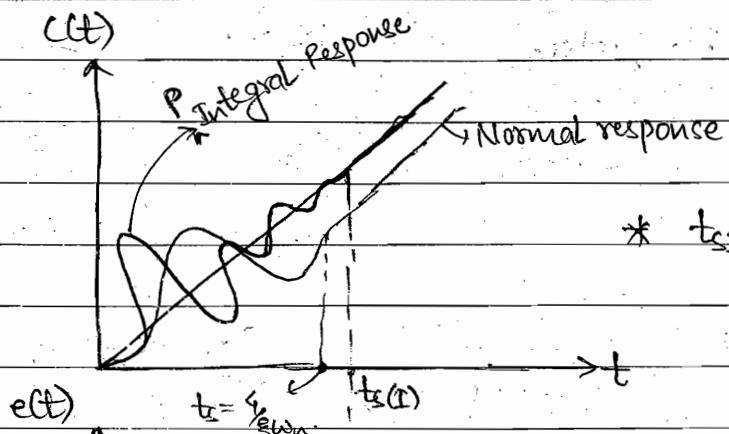
As $(2\zeta\omega_n - k_i) < 0$, so both poles will go on Right-half of s -plane making system unstable.



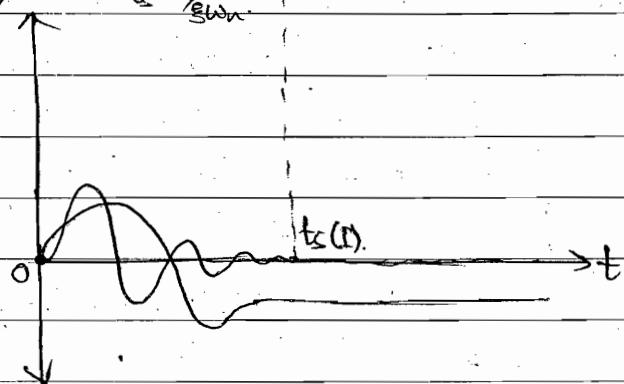
Now, e_{ss} is : $k_a = \lim_{s \rightarrow 0} s^2 \cdot \frac{(s+k_i) \cdot \omega_n^2}{s^2(s+2\zeta\omega_n)} \Rightarrow k_a = \frac{k_i \cdot \omega_n}{2\zeta} \quad *$

$$e_{ss} = \frac{2\zeta \cdot A}{k_i \omega_n} \quad * \quad [\text{For Parabolic input}]$$

$$e_{ss} = 0 \quad * \quad [\text{for Ramp input}]$$

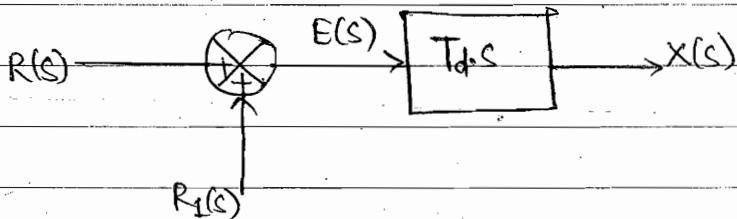


* $t_s(1)$ increases, No. of cycles increase, stability decreases.



* Stability of system reduces as poles will shift towards Imaginary axis, as a result, % Mp will increase, t_s will also increase. But, it decreases t_s .

↳ Derivative controller :

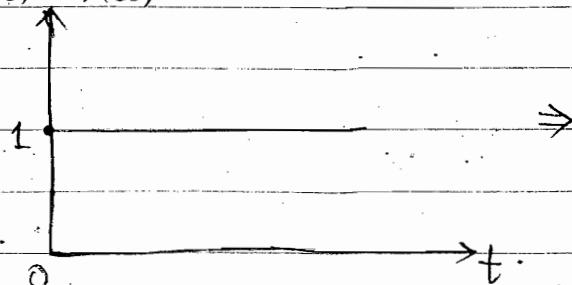


$$X(s) = T_d \cdot s \quad \text{where, } T_d = \text{Derivative Time Constant.}$$

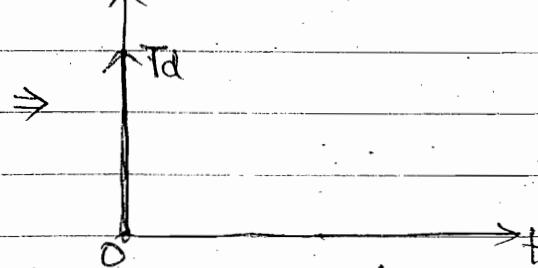
$$\therefore X(s) = T_d \cdot s \cdot E(s).$$

or
$$X(t) = -T_d \cdot \frac{d}{dt} e(t)$$

$$e(t) = 1 \cdot u(t)$$

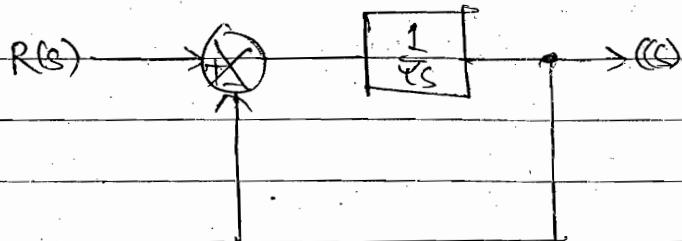


$$x(t) = T_d \cdot \delta(t)$$



- Derivative controller will decrease t_r of system but it will increase ϵ_{ss} as it decreases type of system by introducing zero at Origin.
- Stability will also increase in this case.

* Consider a 1st order system ↴



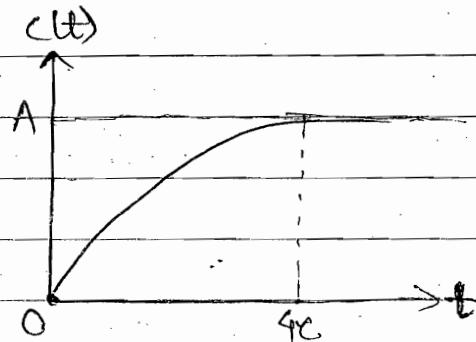
$$\frac{C(s)}{R(s)} = \frac{1}{s + \tau_C}$$

$$\text{For } x(t) = A \cdot u(t), R(s) = A/s$$

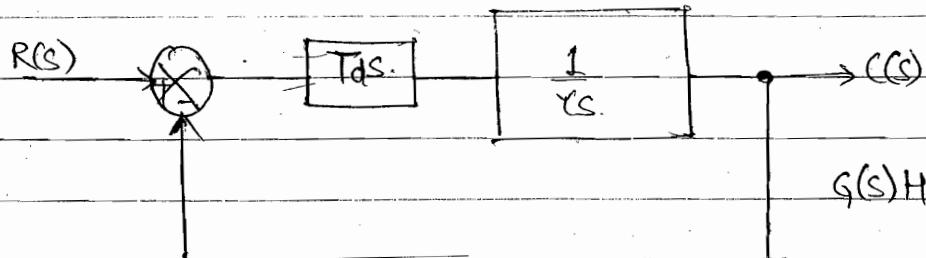
$$\therefore C(s) = (A/\tau_C)$$

$$\cdot s(s + \tau_C)$$

$$C(t) = A \left[1 - e^{-\frac{t}{\tau_C}} \right] *$$



- If we apply Derivative controller to 1st order system, then

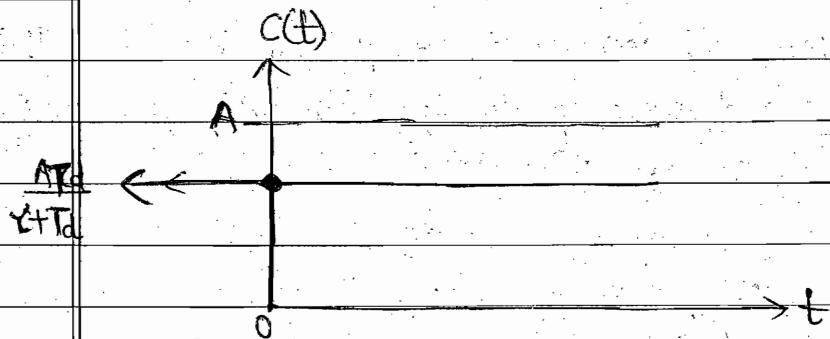


$$G(s)H(s) = \frac{Td}{s}$$

$$\therefore \frac{C(s)}{R(s)} = \frac{Td}{s + Td}$$

$$\text{for } R(s) = A/s, \quad C(s) = \frac{A \cdot Td}{s(s + Td)}$$

$$\therefore C(t) = \frac{A Td \cdot u(t)}{s + Td} *$$

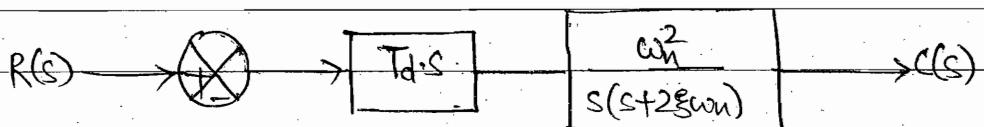


$$(T_d) < 1 \text{ always},$$

so, $c(t)$ will remain less than desired input of A.

Here, $t_r = 0$ but ϵ_{ss} has increased and become constant.

* Similarly, for 2nd Order system:

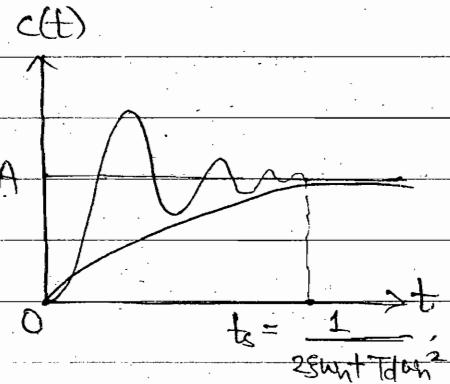


$$G(s) \cdot H(s) = \frac{T_d \cdot w_n^2}{(s + 2\zeta w_n)}$$

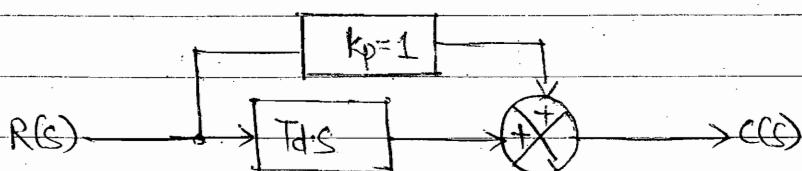
$$\therefore \frac{C(s)}{R(s)} = \frac{T_d \cdot w_n^2}{s + (2\zeta w_n + T_d \cdot w_n^2)}$$

For $r(t) = A \cdot u(t)$, $R(s) = A/s$.

$$\therefore C(s) = \frac{\frac{A}{s} T_d \cdot w_n^2}{s + (2\zeta w_n + T_d \cdot w_n^2)}$$



5) Proportional Derivative Controller (PD):

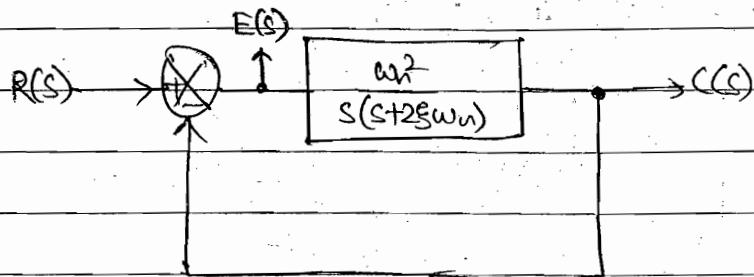


$$\frac{C(s)}{R(s)} = k_p + T_d \cdot s$$

$$\therefore \boxed{\frac{C(s)}{R(s)} = 1 + T_d \cdot s} *$$

- This will locate zero other than origin.

Now, for second order system;



$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

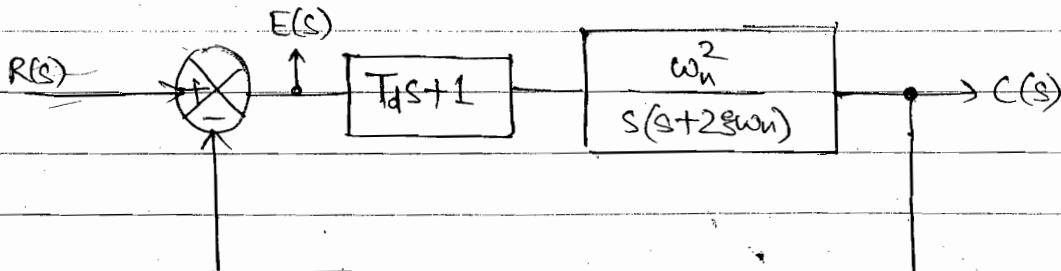
$$\therefore s_{1,2} = -\xi\omega_n \pm j\omega_n \sqrt{1-\xi^2} ; t_s = \frac{1}{\xi\omega_n}$$

$$G(s) H(s) = \frac{\omega_n^2}{s(s+2\xi\omega_n)}$$

$$\therefore K_V = \frac{\omega_n}{2\xi}, \quad e_{ss} = \frac{2\xi \cdot A}{\omega_n} \quad * \text{ [For Ramp Input].}$$

$$e_{ss} = \infty \quad * \text{ [For Parabolic Input].}$$

* Now, if PD controller is applied, then :



$$G(s) = \frac{(T_d s + 1) \omega_n^2}{s(s+2\xi\omega_n)}$$

$$\text{or } \frac{C(s)}{R(s)} = \frac{(T_d s + 1) \cdot \omega_n^2}{s^2 + 2\xi\omega_n s + T_d s \cdot \omega_n^2 + \omega_n^2}$$

$$\text{or } \frac{C(s)}{R(s)} = \frac{(T_d s + 1) \omega_n^2}{s^2 + (2\xi\omega_n + T_d) s + \omega_n^2}$$

$$\therefore s^2 + (2\xi\omega_n + T_d \cdot \omega_n^2)s + \omega_n^2 = 0.$$

converting it into standard form;

$$s^2 + 2\xi'\omega_n' + (\omega_n')^2 = 0.$$

$$\therefore \boxed{\omega_n' = \omega_n} *$$

$$\text{and } T_d \cdot \omega_n^2 + 2\xi\omega_n = 2\xi'\omega_n'$$

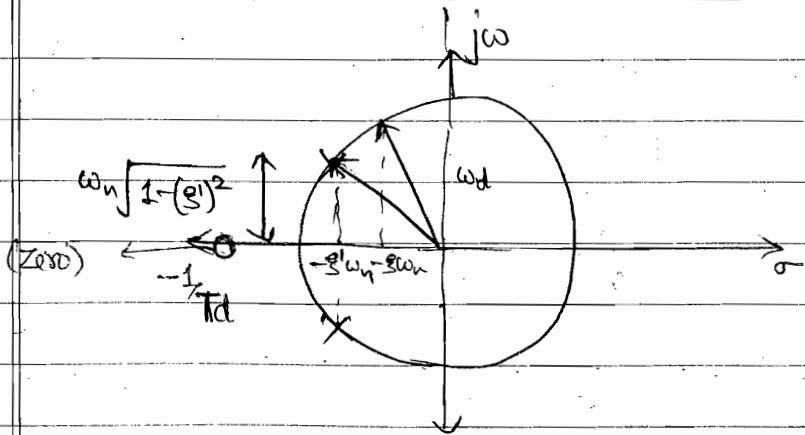
$$\Rightarrow T_d \cdot \omega_n^2 + 2\xi\omega_n = 2\xi'\omega_n.$$

$$\Rightarrow \boxed{\xi' = \xi + \frac{T_d \cdot \omega_n}{2}} *$$

$$\therefore \boxed{s_{1,2} = -\xi'\omega_n \pm j\omega_n \sqrt{1 - (\xi')^2}} *$$

* As $\xi' > \xi \Rightarrow \xi'\omega_n > \xi\omega_n$

. ∵ Real part of pole increases and Imaginary term decreases, so poles will shift left making system more stable than earlier.



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$$\text{As } \frac{C(s)}{R(s)} = \frac{(T_d s + 1) \cdot \omega_n^2}{s^2 + 2\zeta \omega_n s + \omega_n^2}$$

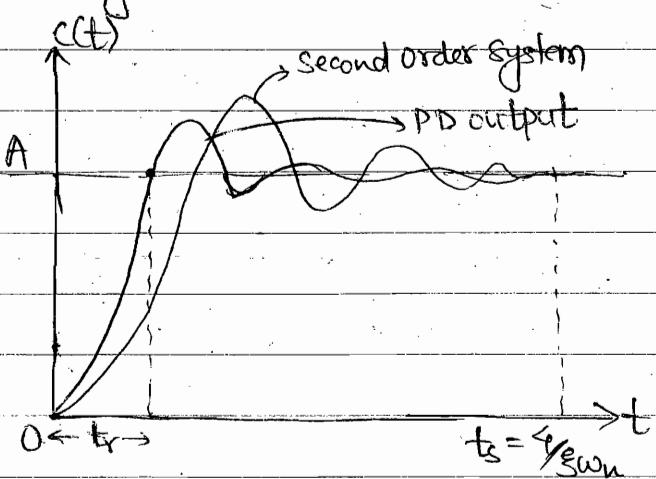
For $R(s) = A/s$

$$C(s) = \left[\frac{\omega_n^2 \cdot (A/s)}{s^2 + 2\zeta \omega_n s + \omega_n^2} \right] + \left[s \left[\frac{\omega_n^2 \cdot (A/s)}{s^2 + 2\zeta \omega_n s + \omega_n^2} \right] \right] T_d.$$

$$\therefore C(t) = A \left[1 - \frac{e^{-\zeta \omega_n t}}{\sqrt{1-(\zeta')^2}} \sin(\omega_n' t + \phi') \right] + T_d \left[\frac{d}{dt} A \left[1 - \frac{e^{-\zeta \omega_n t}}{\sqrt{1-(\zeta')^2}} \sin(\omega_n' t + \phi') \right] \right]$$

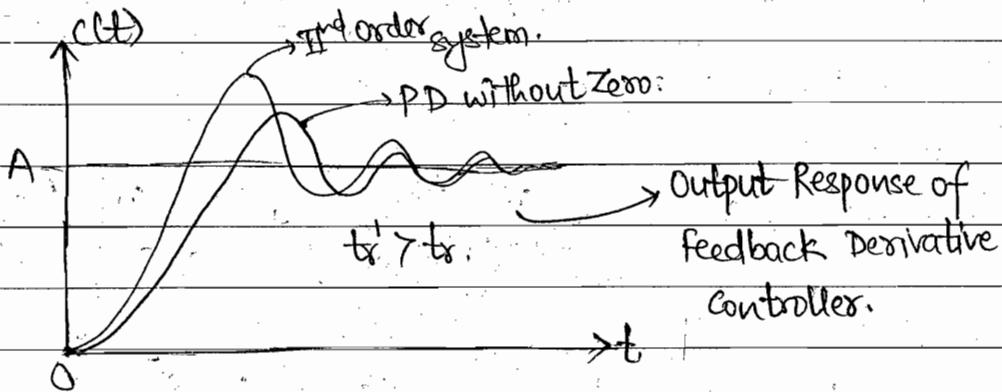
where, $\phi' = \tan^{-1} \left(\frac{1-(\zeta')^2}{\zeta'} \right)$.

\therefore PD will introduce a new derivative term in the output, so which will help to reduce transients or compress the transient region.



- The effect of PD controller is that :
 - * It will introduce one zero in transfer function and due to that zero, a derivative term will exist in the output response and that derivative term will compress the transient region. So, t_r will decrease.
 - * ζ will increase, hence $\% M_p$ will decrease.
 - * Poles shift away from the Imaginary axis, hence stability of system increases.

- If Z_{0D} were not included, then t_r would have increased.



- formulae for t_r, M_p, t_s, t_p of PD controller will be different from t_r, M_p, t_s, t_p of Second order system.

* With application of PD controller :-

- t_r will decrease, ∵ M_p decreases and stability increases and t_s will decrease.

Now, e_{ss} will be :-

$$G(s) H(s) = \frac{(T_d s + k_p) \cdot \omega_n^2}{s(s + 2\zeta \omega_n)}$$

$$\therefore K_v = \lim_{s \rightarrow 0} s \times \frac{(T_d s + k_p) \omega_n^2}{s(s + 2\zeta \omega_n)} \Rightarrow K_v = \frac{k_p \cdot \omega_n}{2\zeta}$$

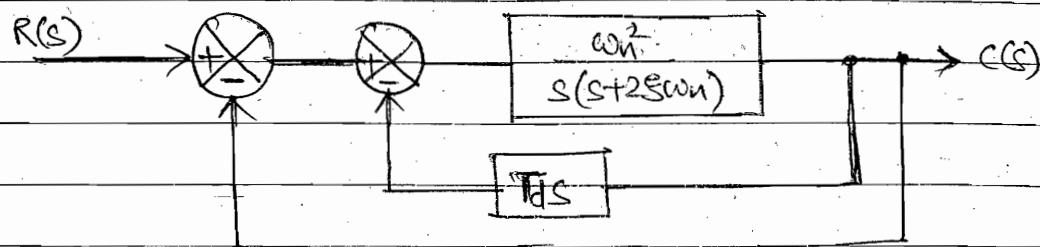
$$\therefore e_{ss} = \frac{2\zeta \cdot A}{K_v \cdot \omega_n}$$

- T_d will not have effect on e_{ss}, as T_ds will be 0 when limit s → 0.
- so, e_{ss} will get affected only due to k_p.

* On e_{ss}, T_d will not effect because when we will apply limit of s → 0, T_ds term will always become zero(0).

So, whatever the changes in e_{ss} are taking place, it is just due to k_p and if k_p = 1, then e_{ss} will remain same.

6) Feedback Derivative controller



$$G(s) = \frac{\omega_n^2}{s[s + (2\zeta\omega_n + T_d\omega_n^2)]}$$

$$\therefore \frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + (2\zeta\omega_n + T_d\omega_n^2)s + \omega_n^2}$$

$$\therefore q(s) = s^2 + (2\zeta\omega_n + T_d\omega_n^2)s + \omega_n^2 = 0.$$

$$\boxed{\omega'_n = \omega_n} \quad *, \quad \boxed{\xi' = \xi + \frac{T_d\omega_n}{2}} \quad *$$

$$s_{1,2} = -\xi'\omega_n \pm j\omega_n \sqrt{1-(\xi')^2}$$

$$\therefore C(s) = \frac{\omega_n^2 (A/s)}{s^2 + 2\xi'\omega_n s + \omega_n^2}$$

$$\therefore c(t) = A \left[1 - e^{-\frac{\xi' n t}{\omega_n}} \sin(\omega_n' t + \phi') \right]; \quad \phi' = \tan^{-1} \left(\frac{\sqrt{1-(\xi')^2}}{\xi'} \right)$$

Now, all formulae will be applicable,

$$t_x' = \frac{\pi - \phi'}{\omega_n \sqrt{1-(\xi')^2}} \quad (t_x' > t_r)$$

$$t_p' = \frac{\pi}{\omega_n \sqrt{1-(\xi')^2}} \quad (t_p' > t_p)$$

$$\% M_p' = e^{-\pi \xi' / \sqrt{1-\xi'^2}} \times 100\% \quad (M_p' < M_p).$$

$$t_s' = \frac{4}{\xi' \omega_n} \quad (t_s' < t_s)$$

- With application of Feedback Derivative controller:
 - ξ will increase and as a result, %Mp will decrease.
 - T_d will increase, T_c will decrease and stability of system will increase.

* For e_{ss} :

$$k_v = \lim_{s \rightarrow 0} s x \frac{\omega_n^2}{s[s + (2\xi\omega_n + T_d\omega_n^2)]}$$

$$\Rightarrow k_v = \frac{\omega_n}{2\xi + T_d\omega_n} *$$

$$e_{ss} = \frac{(2\xi + T_d\omega_n)A}{\omega_n} * [\text{For Ramp Input}].$$

* $\therefore e_{ss}$ will increase by $(T_d A)$ factor with applying feedback Derivative controller.

Here, e_{ss} will depend on T_d here.

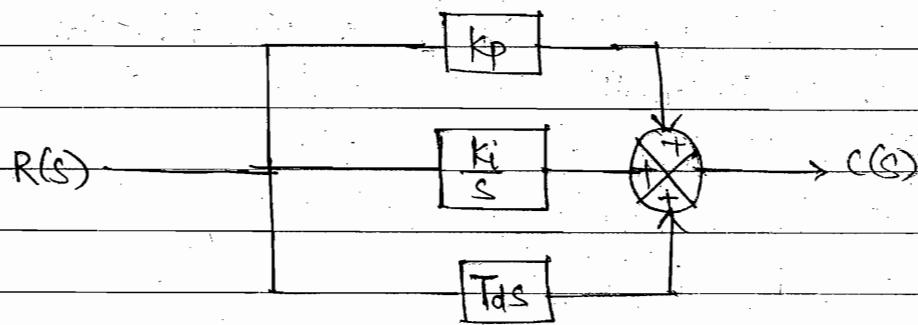
* It is used rarely. Example: Servomotors.

* Proportional Integral Derivative (PID) Controller :

We know, for pure IInd order system,

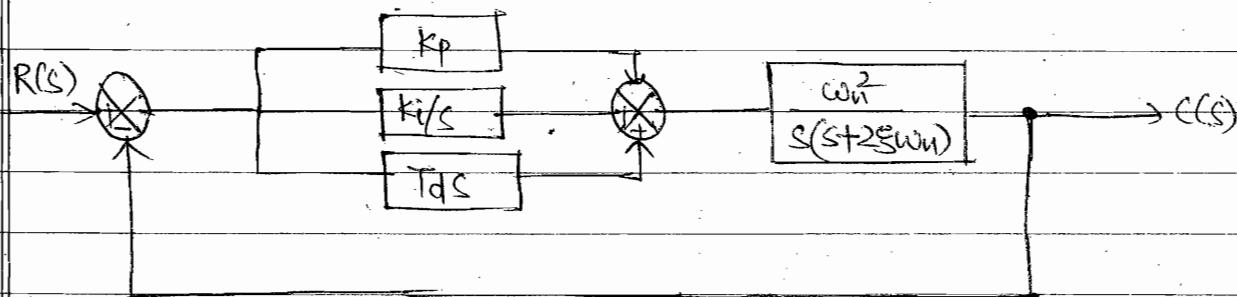
$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2} ; e_{ss} = \frac{2\xi}{\omega_n} (\text{for Ramp Input}).$$

Now, when PID controller is applied :)



$$\frac{C(s)}{R(s)} = T_d s + K_p + \frac{K_i}{s}$$

$$\Rightarrow \frac{C(s)}{R(s)} = \frac{T_d s^2 + K_p s + K_i}{s}$$



$$G(s) = \frac{(T_d s^2 + K_p s + K_i) \omega_n^2}{s^2 (s + 2\zeta \omega_n)}$$

$$\text{and } \frac{C(s)}{R(s)} = \frac{(T_d s^2 + K_p s + K_i) \omega_n^2}{s^3 + (2\zeta \omega_n + T_d \omega_n^2) s^2 + K_p \omega_n^2 s + K_i \omega_n^2}$$

| | | |
|-------|--|------------------------|
| s^3 | 1 | $K_p \cdot \omega_n^2$ |
| s^2 | $2\zeta \omega_n + T_d \omega_n^2$ | $K_i \omega_n^2$ |
| s^1 | $(2\zeta \omega_n + T_d \omega_n^2) K_p \omega_n^2 - K_i \omega_n^2$ $(2\zeta \omega_n + T_d \omega_n^2)$ | |
| s^0 | $K_i \omega_n^2$ | |

$$(2\zeta \omega_n + T_d \omega_n^2) K_p \cdot \omega_n^2 > K_i \omega_n^2$$

$$\therefore (2\zeta\omega_n + T_d\omega_n^2)K_p > K_i$$

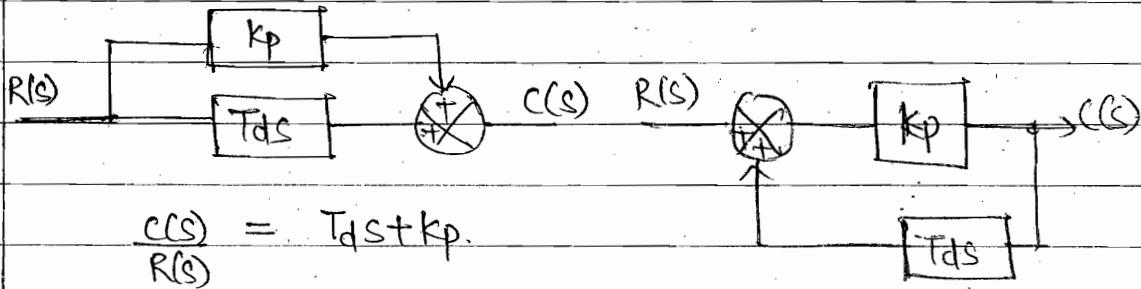
** For more positive, T_d and K_p should be large and K_i should be small.

Numericals

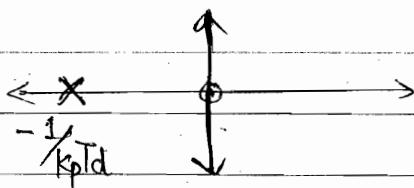
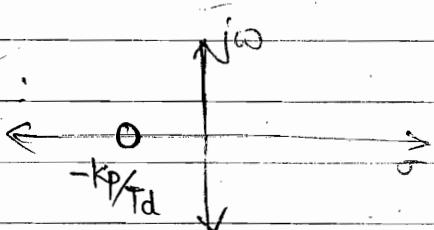
Ques:- ① To design phase-lead compensator, which controller will be used:

- (a) PD and feedback derivative controller
- (b) Integral and derivative controller.
- (c) Proportional and feedback derivative controller.
- (d) Derivative and PI controller

Ans: (1)



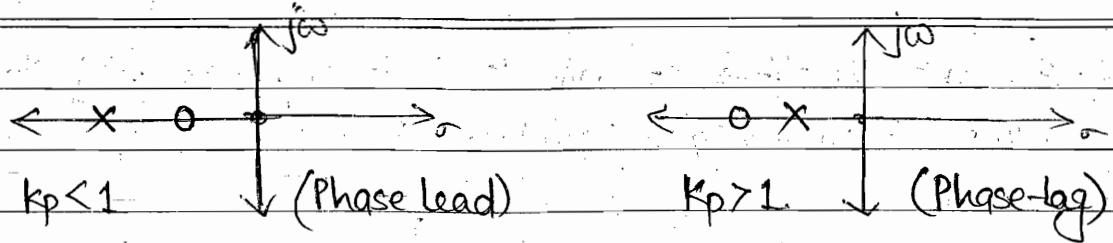
$$\frac{C(s)}{R(s)} = \frac{K_p}{K_p T_d s + 1}$$



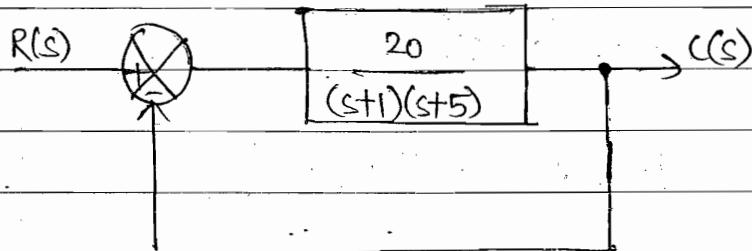
- To form Phase-lead compensator, both PD and feedback Derivative controller will be cascaded.
- To make zero closer to imaginary axis,

$$\frac{K_p}{T_d} < \frac{1}{K_p T_d} \Rightarrow K_p < 1 \quad * \text{ (For Phase-lead)}$$

$$K_p > 1 \quad * \text{ (For phase-lag).}$$



Ques:- ② For the given closed loop system, calculate its % M_p , ξ , ω_n , ω_d , first t_{po} , first t_{pu} , M_{pu1} , t_s and number of cycles upto t_s .



Ans:- ② The closed loop Transfer function can be obtained as;

$$\frac{C(s)}{R(s)} = \frac{20}{s^2 + 6s + 25}$$

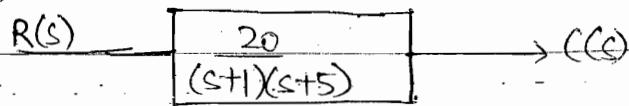
Here, characteristics Equation is : $s^2 + 6s + 25 = 0$.

Comparing with standard equation : $s^2 + 2\xi\omega_n s + \omega_n^2 = 0$

$$\boxed{\omega_n = 5 \text{ rad/sec}} * \quad 2\xi \times 5 = 6 \Rightarrow \boxed{\xi = 0.6} *$$

$$\text{As } \omega_d = \omega_n \sqrt{1 - \xi^2} \Rightarrow \boxed{\omega_d = 4 \text{ rad/sec}} *$$

- To understand this numerical better, first find its Open Loop Transfer Function,



$$\frac{C(s)}{R(s)} = \frac{20}{s^2 + 6s + 25} = \frac{4 \times 5}{s^2 + 6s + 25}$$

$K=4$ here.

(Gain).

• It means Amplifier of Gain $K=4$ is connected with Closed loop TF to make it Open Loop TF as:

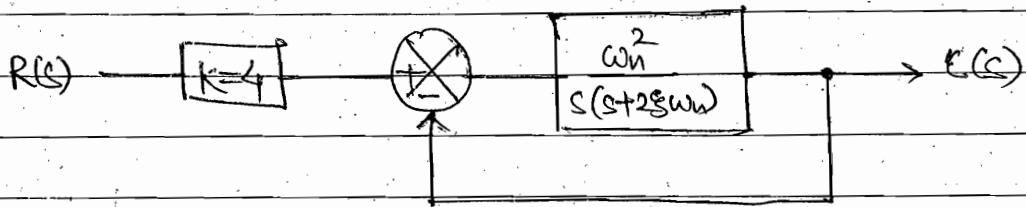
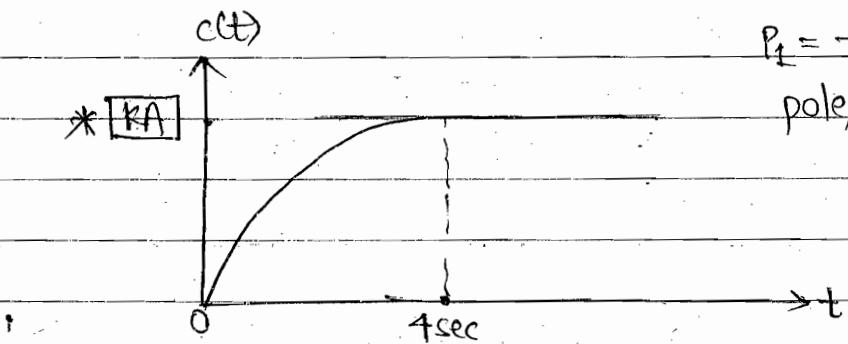


Fig: Open Loop Transfer Function.

$$\text{Here, } q(s) = s^2 + 6s + 5 = 0.$$

$$\omega_n = \sqrt{5} \text{ rad/s}, \xi = \frac{3}{\sqrt{5}} = 1.3$$

as $\xi > 1$, system is over-damped.



$P_1 = -1$ is dominant pole, so, t_s will be $\frac{4}{1} \Rightarrow t_s = 4 \text{ sec.}$

• For DC Gain ($K \neq 0$), Response will settle at [DC Gain \times Input].

* Now, analyzing given closed loop system,

$$\therefore \frac{C(s)}{R(s)} = \frac{20}{s^2 + 6s + 25} = \frac{0.8 \times 25}{s^2 + 6s + 25}$$

$$K = 0.8 *$$

∴ with increase in feedback, DC Gain reduces.

$$\therefore \omega_n = 5 \text{ rad/s}, \xi = 0.6, \xi \omega_n = 3.$$

• Here, as $\xi < 1$, so overdamped system changes to Under-damped system.

$$\Rightarrow \omega_d = 4 \text{ rad/s.}$$

* Pole location, $s_{1,2} = -3 \pm j4$.

* Time constant, $\tau = \frac{1}{\zeta \omega_n} \Rightarrow \tau = \frac{1}{3}$ seconds.

* t_s (for 2% error-band) = $\frac{4}{\zeta \omega_n} = 1.33$ seconds.

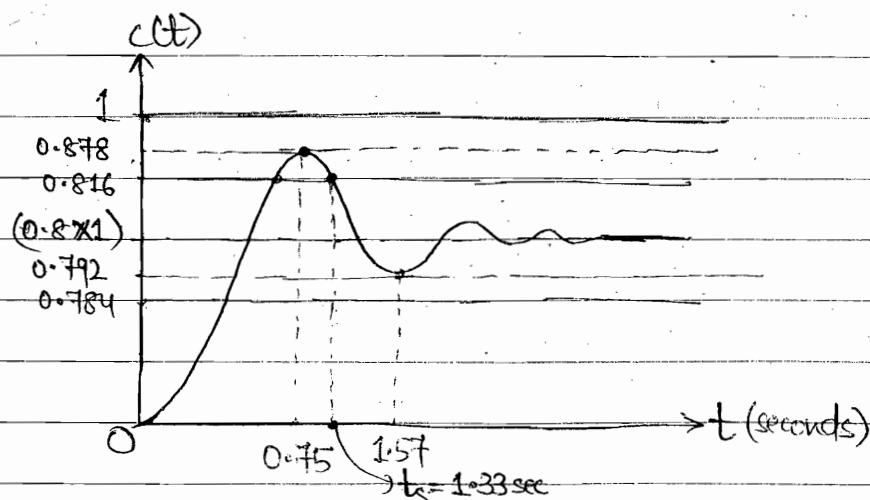
* $t_{p01} = \frac{\pi}{\omega_d} = \frac{3 \cdot K_p}{4} \Rightarrow t_{p01} = 0.785$ seconds.

* $t_{pu1} = \frac{2\pi}{\omega_d} = T_d = \frac{6.28}{4} = 1.57$ seconds. = T_d .

Note: *** As $T_d > t_s$, so output will settle before T_d without completing one-full cycle.

* % $M_{p01} = e^{-\frac{t}{\tau}} = 9.8\%$

* % $M_{pu1} = e^{-\frac{2\pi t}{\omega_d}} = 0.89\%$.



Now, % $M_p = \frac{c(t)|_{max} - c(t)|_{desired}}{c(t)|_{desired}} \times 100\%$.

% $M_p = \frac{0.878 - 0.8}{0.8} = 9.8\%$

$$\therefore \boxed{C(t)|_{\max} = 0.878} *$$

Similarly, $\% M_u = \frac{C(t)|_{\text{desired}} - C(t)|_{\min}}{C(t)|_{\text{desired}}} \times 100\%$.

$$\therefore 0.89\% = \frac{0.8 - C(t)|_{\min}}{0.8} \times 100\%$$

$$\therefore \boxed{C(t)|_{\min} = 0.792} *$$

* Number of cycles, $n = \frac{t_s}{T_d} = \frac{1.33}{1.5}$

$$\therefore \boxed{n = 0.8} *$$

* As $e_{ss} \propto \frac{1}{K}$ and Error-coefficients = DC Gain

Error-coefficients

$$\therefore \boxed{e_{ss} \propto \frac{1}{K}} *$$

, so, as feedback increases, K decreases and e_{ss} increases.

* When feedback is increased in 2^{nd} order underdamped system, t_s will remain same. In under-damped, ω_n remains constant, only ω_d changes.

Ques: (3) The OLTF is $G(s)H(s) = \frac{K}{s(Ts+1)} [u-f]$. Determine by what value

K should be changed so that % overshoot decreases from 60% to 20%.

Ans: (3) K = Variable here.

$$\therefore \frac{C(s)}{R(s)} = \frac{K}{Ts^2 + sT + K} = \frac{(K/T)}{s^2 + \frac{s}{T} + \frac{K}{T}}$$

: Comparing with standard equation,

$$K^l = k_T, \quad 2\xi\omega_n = \zeta_T, \quad k_T = \omega_n^2$$

$$\therefore \omega_n = \sqrt{k_T}, \quad 2\xi \times \sqrt{k_T} = \zeta_T$$

$$\Rightarrow \xi = \frac{1}{2\sqrt{k_T}}$$

as k is only variable,

$$\xi \propto \frac{1}{\sqrt{k}} *$$

$$\text{As } e^{-\frac{\pi\xi_1}{\sqrt{1-\xi_1^2}}} \times 100 = 60\% \Rightarrow e^{-\frac{\pi\xi_1}{\sqrt{1-\xi_1^2}}} = 0.6.$$

$$\Rightarrow -\frac{\pi\xi_1}{\sqrt{1-\xi_1^2}} = -0.5 \Rightarrow \boxed{\xi_1 = 0.45} *$$

$$\text{Similarly, } e^{-\frac{\pi\xi_2}{\sqrt{1-\xi_2^2}}} \times 100 = 20\% \Rightarrow -\frac{\pi\xi_2}{\sqrt{1-\xi_2^2}} = \ln(0.2) = -1.39$$

$$\Rightarrow \boxed{\xi_2 = 0.16} *$$

$$\therefore \left(\frac{0.45}{0.16}\right) = \frac{\xi_1}{\xi_2} = \sqrt{\frac{k_2}{k_1}} \Rightarrow \frac{k_2}{k_1} = \left(\frac{0.45}{0.16}\right)^2 = \frac{1}{8}$$

$$\therefore \boxed{k_2 = \frac{1}{8} k_1} * \Rightarrow k \text{ should be decreased by factor of 8.}$$

Ques:- ④ The OLTF of a unity feedback system, $G(s)H(s) = \frac{10(s+5)}{s^2(s+2)(s+10)}$.

Determine steady state error if input $r(t) = 5t$.

$$\text{Ans:- ④ } k_V = \lim_{s \rightarrow 0} sG(s)H(s) = \lim_{s \rightarrow 0} \frac{s \times 10(s+5)}{s^2(s+2)(s+10)} \Rightarrow k_V = \infty$$

$$\therefore \boxed{e_{ss} = 0} *$$

Ques:- ⑤ The open loop TF of a u.f.b system is: $\frac{10(s+5)}{s^2(s+2)(s+10)}$ if

input is $2u(t) + 5t + 10t^2$. Determine steady state error.

Aus:- ⑤

$$\text{As } e_{ss} = \lim_{s \rightarrow 0} \frac{sR(s)}{1+G(s)H(s)}$$

$$\text{Input is: } 2u(t) + 5t + \frac{20}{2}t^2$$

$$K_a = \lim_{s \rightarrow 0} s^2 \times \frac{10(s+5)}{s^2(s+2)(s+10)} = \frac{5}{2}$$

$$\therefore e_{ss} = \frac{20}{5} \times 2$$

$$e_{ss} = 8 *$$

Ques:- ⑥ The open loop TF of a u.f.b is: $G(s)H(s) = \frac{K(s+2)}{s^2(s+5)(s+20)}$ if input

given is: $1u(t) + 2t + 5t^2$. Determine value of K to limit
e_{ss} at 8?

$$K_a = \lim_{s \rightarrow 0} s^2 \frac{K(s+2)}{s^2(s+5)(s+20)} = \frac{2K}{100} = k_{50}$$

$$e_{ss} = \frac{10 \times 50}{K}$$

$$8 = \frac{500}{K} \Rightarrow K = \frac{5 \times 100}{8 \times 2}$$

$$K = 62.5 *$$

Ques:- ⑦ The forward gain of a system is: $\frac{10(s+5)}{s(s+2)(s+10)}$; $H(s) = \frac{1}{s}$.

Input to this system $r(t) = 5u(t) + 10t$. Determine e_{ss}.

Aus:- ⑦

$$\frac{C(s)}{R(s)} = \frac{G(s)}{1+G(s)H(s)-G(s)} = \frac{\frac{10(s+5)}{s}}{1+\frac{10(s+5)}{s^2(s+2)(s+10)} + \frac{10(s+5)}{s(s+2)(s+10)}}$$

$$G'(s) = \frac{10s(s+5)}{s^2(s+2)(s+10) + 10(s+5) - 10s(s+5)}$$

Type = 0

$$\therefore k_p = \lim_{s \rightarrow 0} \frac{10s(s+5)}{s^2(s+2)(s+10) + 10(s+5) - 10s(s+5)} = 0.$$

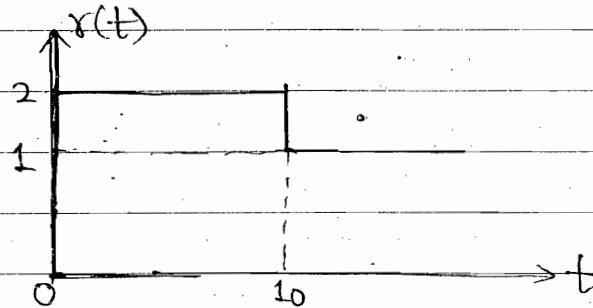
$$[e_{ss} = \infty] *$$

$$e_{ss} = \frac{A}{1+k_p} = \frac{5}{1+0}$$

$$[e_{ss} = 5] *$$

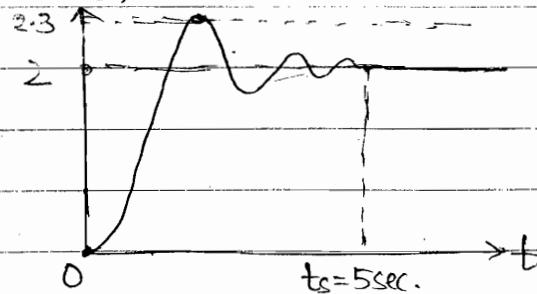
Ques:- (8) A second order under-damped system having $\% M_p = 15\%$, $t_s = 5$ sec, if input to this time is: $r(t) = 2u(t) - 1u(t-10)$. Obtain its output response. Also plot its output graph.

Ans:- (8)



∴ Response when $r(t) = 2u(t)$. $r(t) = 2u(t)$

$$\text{Now, } \frac{c(t)|_{\max} - c(t)|_{\text{des}}}{c(t)|_{\text{des}}} \times 100 = 15\%$$

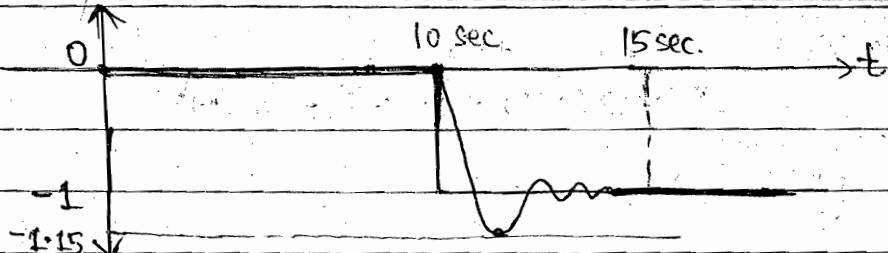


$$\Rightarrow c(t)|_{\max} = 2.3$$

$$\therefore c(t) = 2 \left[1 - \frac{e^{-\zeta \omega t}}{\sqrt{1-\zeta^2}} \sin(\omega_n t + \phi) \right]$$

Now, when second input $r(t) = -1u(t-10)$ is applied, then

$$r(t) = -u(t-10)$$

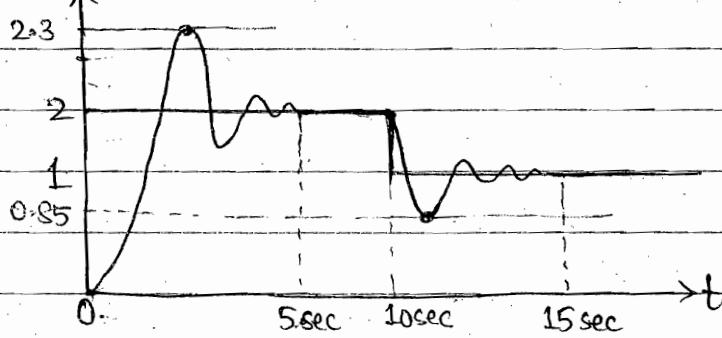


Total output,

$$c(t) = 2 \left[1 - e^{-\frac{\zeta \pi}{\sqrt{1-\xi^2}}} \sin(\omega_n t + \phi) \right] - (1) \left[1 - e^{-\frac{\zeta \pi}{\sqrt{1-\xi^2}}} \sin(\omega_n(t-10) + \phi) \right]$$

∴ Final output will be:

$$r(t) = 2u(t) - u(t-10)$$



$$\text{As } M_p \% = 15 \% \Rightarrow e^{-\frac{\zeta \pi}{\sqrt{1-\xi^2}}} = 0.15$$

$$\Rightarrow \xi = 0.5 \quad *$$

$$\text{As } t_s = \frac{4}{\xi \omega_n} \Rightarrow \omega_n = \frac{40}{0.5 \times 5} \Rightarrow \omega_n = 1.6 \text{ rad/sec} \quad *$$

$$\therefore \omega_d = \omega_n \sqrt{1-\xi^2} = 1.6 \sqrt{1-(0.5)^2}$$

$$\omega_d = 1.38 \text{ rad/sec} \quad *$$

$$\text{As } \phi = \cos^{-1}(\xi) = \cos^{-1}(0.5), \phi = 60^\circ$$

$$\therefore c(t) = 2 \left[1 - e^{-\frac{4t}{0.75}} \sin\left(1.38t + \frac{\pi}{3}\right) \right] u(t) - 1 \left[1 - e^{-\frac{4(t-10)}{0.75}} \sin\left(1.38(t-10) + \frac{\pi}{3}\right) \right] u(t-10)$$

$$\text{At } t_0, C(5) = 2 \left[1 - e^{-\frac{4}{\sqrt{0.75}}} \sin\left(1.38 \times 5 + \frac{\pi}{3}\right) \right] + 0.$$

$$C(5) = 2 * \text{ (For 2% Error-band).}$$

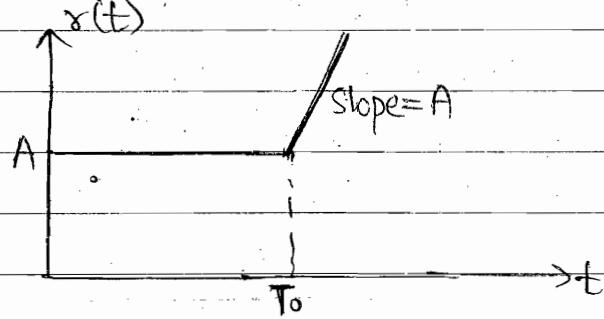
$$\text{At } t=15, C(15) = 2 \left[1 - e^{-\frac{4 \times 15}{\sqrt{0.75}}} \sin\left(1.38 \times 15 + \frac{\pi}{3}\right) \right] u(t) - 1 \left[1 - e^{-\frac{4 \times 5}{\sqrt{0.75}}} \sin\left(1.38 \times 5 + \frac{\pi}{3}\right) \right] u(t-10)$$

$$\Rightarrow C(15) = 2 - 1$$

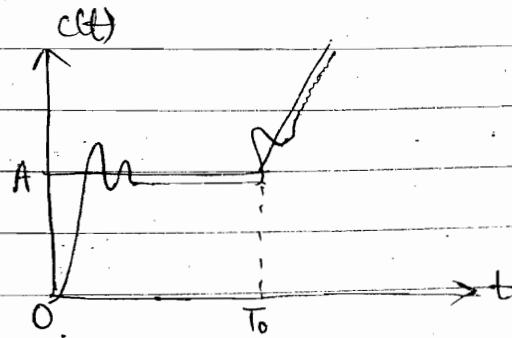
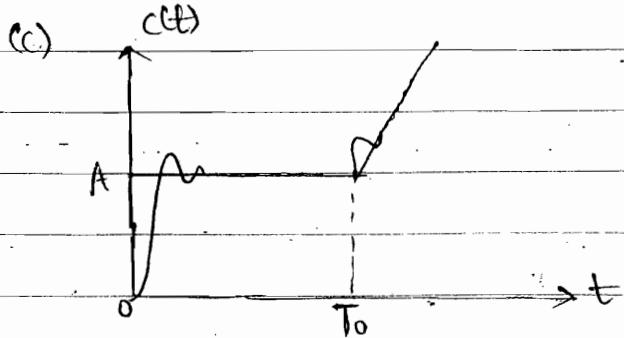
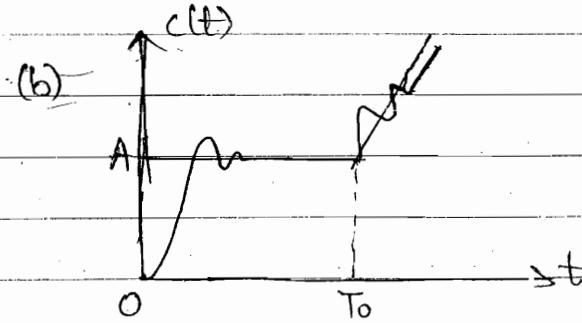
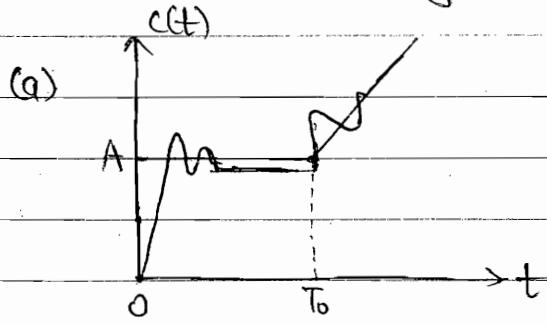
$$C(15) = 1 * \text{ [For 2% error-band].}$$

Ques-9) The OLT of a u-f.b second order underdamped system is:

$$G(s)H(s) = \frac{k}{s(T_0 s + 1)} \cdot \text{if input to this system is:}$$



Which of the following will be its output response?



Ans:- (9) output will be:-

$$c(t) = A \left[1 - e^{-\frac{\zeta \omega_n t}{\sqrt{1-\zeta^2}}} \sin(\omega_n t + \phi) \right] u(t) + A \left[(t-t_0) - \frac{2\zeta}{\omega_n} + e^{-\frac{\zeta \omega_n t}{\sqrt{1-\zeta^2}}} \sin(\omega_n t + \phi) \right]$$

$$\phi = \tan^{-1} \left(\frac{\sqrt{1-\zeta^2}}{\zeta} \right)$$

$$\phi' = \tan^{-1} \left(\frac{2\zeta \sqrt{1-\zeta^2}}{2\zeta^2 - 1} \right).$$

Ans (b)

As type is 1, for unit step, $e_{ss} = 0$

For Ramp, e_{ss} = finite.

Ques:- (10) For closed loop TF of a unity feedback system, $\frac{C(s)}{R(s)} = \frac{k(s+\alpha)}{s^2 + \alpha s + \beta}$

Determine e_{ss} for unit step input.

$$\text{OLTF} = \frac{k(s+\alpha)}{s^2 + \alpha s + \beta - ks - \alpha k} = \frac{k(s+\alpha)}{s^2 + s(\alpha-k) + (\beta-\alpha k)}$$

$$\therefore K_p = \lim_{s \rightarrow 0} \frac{k(s+\alpha)}{s^2 + s(\alpha-k) + (\beta-\alpha k)}$$

$$\Rightarrow K_p = \frac{k\alpha}{(\beta - \alpha k)}$$

$$\therefore e_{ss} = \frac{1}{1+K_p} = \frac{(\beta - \alpha k)}{\beta - \alpha k + k\alpha}$$

$$\therefore e_{ss} = \frac{\beta - \alpha k}{\beta} *$$

Ques:- (11) The error response of a servomotor for step-input is:

$$e(t) = 1.67 e^{-\frac{\zeta \omega_n t}{\sqrt{1-\zeta^2}}} \sin \left(\omega_n t + 37^\circ \right). \text{ Determine}$$

$\zeta, \omega_n, \omega_d, t_{p01}, \% M_{p01}$ and t_s for 5% error-band.

Ans:- (11) For $r(t) = Au(t)$.

$$\therefore c(t) = A \left[1 - e^{-\frac{\zeta \omega_n t}{\sqrt{1-\zeta^2}}} \sin(\omega_n t + \phi) \right] u(t).$$

$$\text{and } e(t) = r(t) - c(t) = A u(t) - c(t).$$

$$\therefore e(t) = \frac{A}{\sqrt{1-\xi^2}} e^{-\xi \omega_n t} \sin(\omega_n t + \phi) \quad \text{--- (1)}$$

Comparing given $e(t)$ with equation (1),

$$\therefore 1.67 = \frac{A}{\sqrt{1-\xi^2}}, \quad \xi \omega_n = 8.$$

$$\text{Also, } \omega_d = 6 \Rightarrow \omega_n \sqrt{1-\xi^2} = 6.$$

$$\omega_n = 6 \times 1.67 \Rightarrow [\omega_n \approx 10 \text{ rad/sec}] *$$

$$\therefore \xi \approx 0.8 * \quad \omega_d = 6 \text{ rad/sec} *$$

$$\text{Now, } t_{p01} = \frac{\pi}{\omega_d} = \frac{3.14}{6} \Rightarrow [t_{p01} = 0.52 \text{ sec}] *$$

$$t_{p41} = \frac{2\pi}{\omega_d} = 1.04 \text{ seconds} = T_d.$$

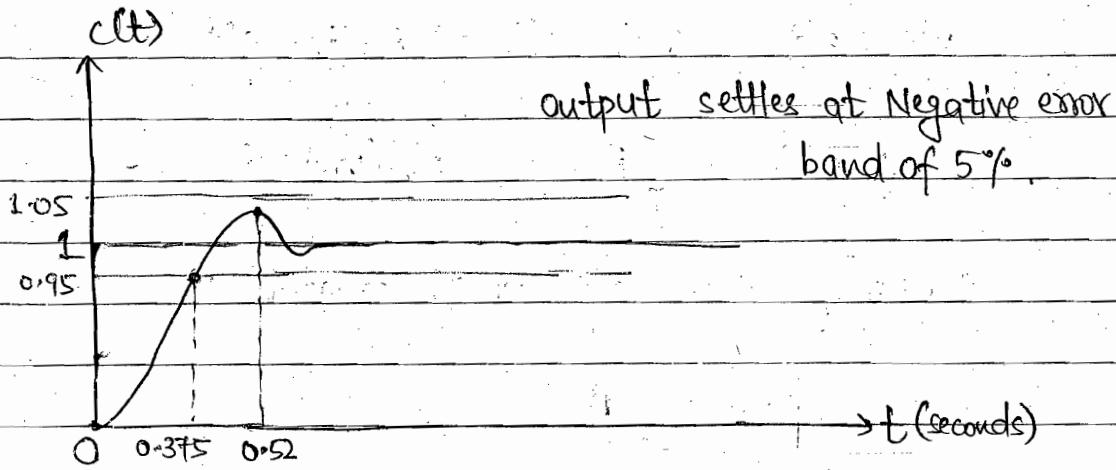
$$t_s = 3\tau = \frac{3}{\xi \omega_n} \Rightarrow t_s = \frac{3}{8}$$

$$[t_s = 0.375 \text{ sec}] *$$

$$\% M_{p01} = e^{\frac{-\xi \pi / \sqrt{1-\xi^2}}{T_d}} = e^{-0.8 \times 3.14 \times 1.67} \quad [\% M_{p01} = 1.5 \%] *$$

$$\therefore \frac{A}{\sqrt{1-\xi^2}} = 1.67 \Rightarrow [A \approx 1] *$$

As $t_s < T_d$, so output will settle before half-cycle is completed.



output settles at Negative error band of 5%.

Ques:-12, The OLTF of u/f/b is: $G(s)H(s) = \frac{k(s+2)}{s^3 + \beta s^2 + 4s + 1}$. Determine the

value of k and β so that ξ will be maintained at 0.2 and ω_n at 3 rad/sec.

Ans:- (12)

$$\begin{aligned} \text{Now, } \frac{C(s)}{R(s)} &= \frac{k(s+2)}{s^3 + \beta s^2 + s(4+K) + (1+2K)} = \frac{k(s+2)}{s^3 + \beta s^2 + s(k+4) + (1+2K)} \\ \therefore Q(s) &= 1 + G(s) H(s) = 0 \\ \Rightarrow s^3 + \beta s^2 + s(4+K) + (1+2K) &= 0. \end{aligned}$$

This third order system has been made from one 1st order and one 2nd order under-damped system.

$$\therefore (s + \xi \omega_n + j\omega_n \sqrt{1-\xi^2})(s + \xi \omega_n - j\omega_n \sqrt{1-\xi^2})(s+p) = 0.$$

$$\Rightarrow (s^2 + 2\xi\omega_n s + \omega_n^2)(s+p) = 0$$

$$\Rightarrow s^3 + ps^2 + 2\xi\omega_n s^2 + 2\xi\omega_n p s + \omega_n^2 s + \omega_n^2 p = 0.$$

$$\Rightarrow s^3 + s^2(p + 2\xi\omega_n) + s(\omega_n^2 + 2\xi\omega_n p) + \omega_n^2 p = 0.$$

$$\Rightarrow p + 2\xi\omega_n = \beta ; 4+K = \omega_n^2 + 2\xi\omega_n p , 1+2K = \omega_n^2 p.$$

$$\text{or } p + 1.2 = \beta ; 1.2p + 9 = 4+K ; 1+2K = 9p.$$

$$\therefore p = 1.66; \quad K = 7; \quad B = 2.85.$$

• As. p is positive here (we consider p as left-half pole), so system, here, is stable.

If, by chance, p is negative, then system will be unstable.

Ques:- (13) The OLTF of a u-f-b is: $G(s)H(s) = \frac{20}{s(s+2)}$. If input $r(t) = a_0 + a_1 t + a_0 \frac{t^2}{2}$, Determine Dynamic error as well as ess.

Ans:- (13) Type = 1.

$$\frac{E(s)}{R(s)} = \frac{1}{1+G(s)H(s)} = \frac{2s+s^2}{20+2s+s^2}.$$

$$\text{Using Long Division: } \frac{2s+s^2}{20+2s+s^2} \left| \begin{array}{r} 2s+s^2 \\ 2s+s^2+s^3 \\ \hline 5 \end{array} \right. \left(0 + s \frac{1}{10} + s^2 \frac{1}{25} \right)$$

$$\therefore \frac{E(s)}{R(s)} = \frac{s}{10} + \frac{s^2}{25} = G_0 + G_1 s + G_2 s^2$$

$$\text{or } E(s) = \frac{s R(s)}{10} + \frac{s^2 R(s)}{25}, \quad (1) \quad \left(\begin{array}{c} s^2 - s^3 \\ \hline s \\ s^2 + \frac{2s^3}{25} + \frac{s^4}{25} \end{array} \right) \quad (\text{Neglect Remainder}).$$

$$\therefore C_0 = 0; \quad K_p = \infty$$

$$C_1 = \frac{1}{10}, \quad C_2 = \frac{1}{25}$$

$$K_V = 10, \quad K_a = 25.$$

$$\therefore \text{From eq-(1), } e(t) = \frac{d}{dt} \frac{(r(t))}{10} + \frac{d^2}{dt^2} \frac{r(t)}{25}.$$

$$e(t) = \frac{(a_1 + a_2 t)}{10} + \left(\frac{a_2}{25} \right). \quad *$$

$$e_{ss} = \lim_{t \rightarrow \infty} e(t) \Rightarrow e_{ss} = \infty \quad *$$

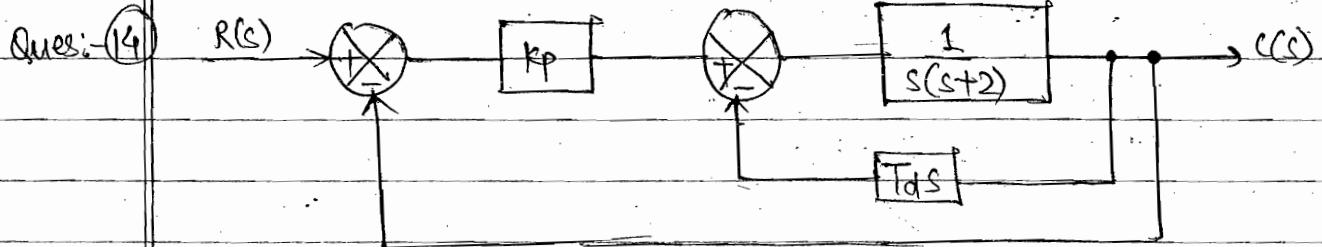
* If, initially, parabolic input is not applied, then $a_2=0$.

$$\therefore e_{ss} = \lim_{t \rightarrow \infty} (a_1 \frac{t}{10}) \Rightarrow e_{ss} = \frac{a_1}{10} *$$

* e_{ss} can also be found by :

$$K_V = \lim_{s \rightarrow 0} \frac{s \times 20}{s(s+2)} = 10.$$

$$e_{ss} = \frac{1}{10} * \text{ or } e_{ss} = \frac{a_1}{10} *$$



For the given block, determine the values of K_p and T_d so that ξ will be maintained at 0.7 and e_{ss} at 0.2.

Ans:- 14 \Rightarrow Inside block $\Rightarrow \frac{\frac{1}{s(s+2)}}{1 + \frac{T_d \cdot s}{s(s+2)}}$

$$\Rightarrow \frac{1}{s^2 + 2s + T_d s} = \frac{1}{s^2 + s(T_d + 2)}$$

$$\therefore \frac{C(s)}{R(s)} = \frac{K_p}{s^2 + s(2 + T_d) + (K_p)}$$

$$\therefore q(s) = s^2 + s(2 + T_d) + K_p = 0.$$

$$\omega_n = \sqrt{K_p} \quad \text{and} \quad 2 + T_d = 2(0.7)\sqrt{K_p}.$$

$$\therefore 2 + T_d = 1.4\sqrt{K_p}.$$

Also, $e_{ss} = \lim_{s \rightarrow 0} \frac{K_p}{s^2 + s(2+T_d)}$

$$\Rightarrow K_v = \lim_{s \rightarrow 0} s \times \frac{K_p}{s(s+2+T_d)} = \frac{K_p}{2+T_d}$$

$$\therefore e_{ss} = \frac{2+T_d}{K_p} \Rightarrow 0 \cdot 2 = \frac{2+T_d}{K_p}$$

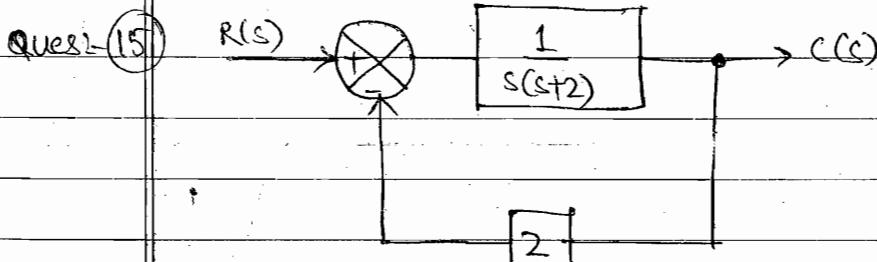
$$\Rightarrow 0 \cdot 2 K_p = 2 + T_d$$

$$\therefore 0 \cdot 2 K_p = 1.4 \sqrt{K_p} \Rightarrow 0.2 \sqrt{K_p} = 1.4 \quad ?$$

$$\boxed{K_p = 49} *$$

and $2+T_d = 0 \cdot 2 K_p \Rightarrow 2+T_d = 0 \cdot 2 \times 49$

$$T_d = 9.8 - 2 \quad \therefore \boxed{T_d = 7.8} * \text{(seconds)}$$



for the given block, calculate e_{ss} for unit step and unit Ramp input.

Also calculate e_{ss} for its unity feedback system for unit step input.

Ans: 15 $G(s)H(s) = \frac{2}{s(s+2)} ; \text{Type} = 1$

$$\text{So, } K_v = \lim_{s \rightarrow 0} s \times \frac{2}{s(s+2)} \Rightarrow K_v = 1.$$

$$\therefore \boxed{e_{ss} = 1} * \text{(For Ramp Input)}$$

For step input, $\boxed{e_{ss} = 0} *$

Converting it into unity feedback system;

$$\frac{C(s)}{R(s)} = \frac{s(s+2)}{s^2 + 2s + 2}$$

$$\therefore OLT F = \frac{1}{s^2 + 2s + 1}$$

$$\therefore K_p = \lim_{s \rightarrow 0} \frac{1}{s^2 + 2s + 1} = \frac{1}{1}$$

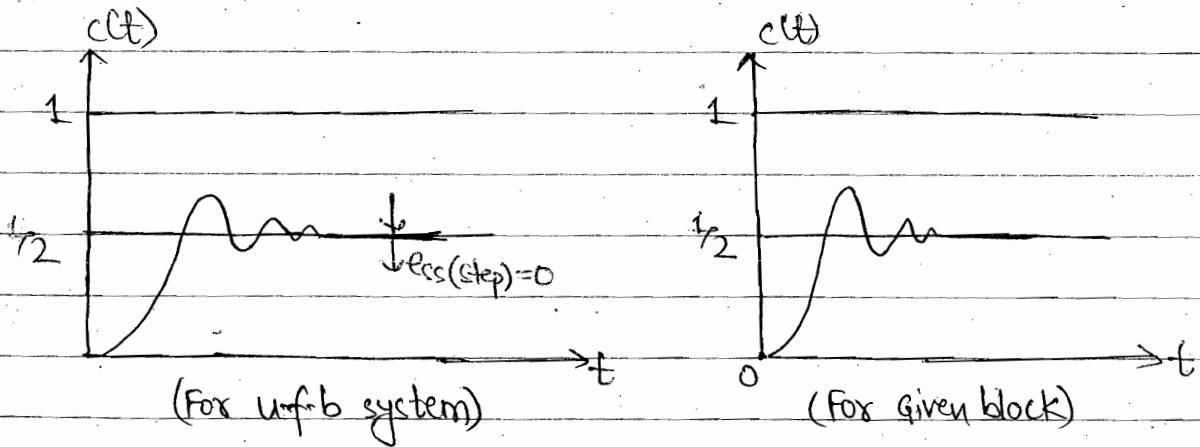
$$e_{ss} = 0.5 * (\text{For unit step}).$$

$$e_{ss} = \infty * (\text{For unit Ramp}).$$

$$\text{Now, } \frac{C(s)}{R(s)} = \frac{1}{s^2 + 2s + 2}$$

Comparing with standard II^{nd} order system; $K = \frac{1}{2}$.

- And For given block, $\frac{C(s)}{R(s)} = \frac{1}{s^2 + 2s + 2}$, here also DC gain (K) = $\frac{1}{2}$.



Chapter:-4SENSITIVITY

- * Sensitivity is defined with respect to two parameters.
- * Sensitivity in terms of input and for better performance of a system, it should be as large as possible; and second with respect to variation of parameters and it should be as small as possible.
 - * If Sensitivity wrt input is Large, then that system will detect smallest input possible and if sensitivity wrt variation in parameter is small, then effect on output due to variation of parameter will be small.
 - * It is represented by: S_K^T .

$$S_K^T = \frac{(\frac{dT}{T})}{(\frac{dk}{k})} = \frac{k \cdot \frac{dT}{dT}}{\frac{T}{dk}} \quad * \quad T = \text{Transfer Function}$$

$k = \text{Any parameter.}$

$\frac{dT}{dT}$ = Limiting error in transfer function.

$\frac{dk}{k}$ = Limiting error of any parameter.

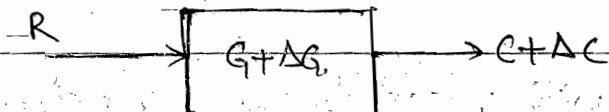
$$\text{Limiting Error (e)} = \frac{\text{Measured value} - \text{True value}}{\text{True Value}} \times 100 \% \quad *$$

• For transfer function, $\epsilon_T = \frac{T_m - T}{T} = \frac{dT}{T}$.

• For Parameter, $\epsilon_k = \frac{k_m - k}{k} = \frac{dk}{k}$.

$$S_K^T = \frac{\epsilon_T}{\epsilon_k} = \frac{k \cdot \frac{dT}{dT}}{\frac{T}{dk}} \quad *$$

→ Sensitivity of Open Loop System due to variation in Forward Gain:



$$\text{Earlier, } \frac{C}{R} = G = T$$

$$\text{Now, } C + \Delta C = (G + \Delta G)R = GR + (\Delta G)R.$$

$$C + \Delta C = C + R(\Delta G).$$

$$\Delta C = R(\Delta G).$$

$$\text{or } \left(\frac{\Delta C}{R} \right) = \Delta G = \Delta T$$

$$\therefore \left(\frac{\Delta T}{T} \right) = 1 \cdot \left(\frac{\Delta G}{G} \right).$$

$$\therefore S_G^T = \frac{\Delta T/T}{\Delta G/G}$$

$$\therefore \boxed{S_G^T = 1} *$$

$$\text{As, } \Delta T = \frac{\Delta C}{R} \text{ and } T = S_R.$$

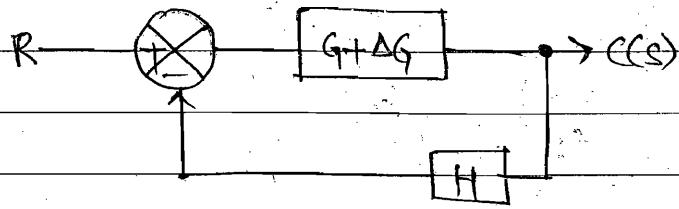
$$\therefore \boxed{\frac{\Delta T}{T} = \frac{\Delta C}{C}} * \text{(Valid only if input } R(s) \text{ is constant).}$$

- Some can be obtained by using formula,

$$S_G^T = \frac{G}{T} \cdot \frac{dG}{dG} \Rightarrow \boxed{S_G^T = 1} * \text{ (} T = G \text{ here).}$$

* In case of Open Loop System, S_G^T (Forward Gain) = 1, it means both transfer function and Forward Gain will change with same percentage and hence, output will also change by same percentage.

* Sensitivity of closed loop system due to variation of parameter
forward gain:



$$\frac{C}{R} = T = \frac{G}{1+GH}$$

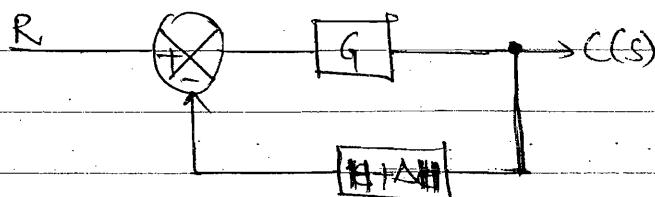
$$\frac{dT}{dG} = \frac{(1+GH) - GH}{(1+GH)^2} = \frac{1}{(1+GH)^2}$$

$$\therefore S_G^T = \frac{G}{T} \cdot \frac{dT}{dG} = \frac{G}{T} \cdot \frac{1}{(GH+1)^2} = \frac{G(1+GH) \times 1}{G(1+GH)^2}$$

$$\therefore S_G^T = \frac{1}{1+GH} *$$

- Sensitivity of closed loop system due to variation in Forward Gain is $(1+GH)$ times less than the sensitivity of Open Loop system due to variations in Forward Gain, hence Performance of Closed loop systems due to variation in Parameter is better than that of open loop systems.

* Sensitivity of closed loop system due to variation in feedback gain:



$$\text{Now, } T = \frac{C}{R} = \frac{G}{1+GH}$$

$$\text{and } \frac{dT}{dH} = \frac{(1+GH)(0) - G^2}{(1+GH)^2} = \frac{-G^2}{(1+GH)^2}$$

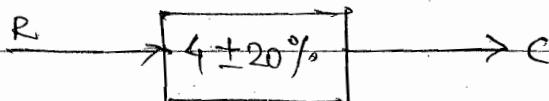
$$\therefore ST_H = \frac{H \times (1+GH)}{G} \times \frac{(-G^2)}{(1+GH)^2}$$

$$\Rightarrow ST_H = \frac{-GH}{(1+GH)} *$$

• sensitivity of closed loop system due to variations in feedback
 Gain is $(-GH)$ times greater than sensitivity of closed loop system due to variation of Forward Gain. So,
 In feedback gain, proper shielding is required.

* Negative sign in ST_H represents that effect will be opposite in nature. If T increases, H will decrease and vice-versa.

Ques:- ①



For the given block, calculate % change in output of Open loop system and Closed Loop system with unity feedback condition.

$$\text{Ans:- } ① \quad \frac{dG}{G} \times 100 = 20\%$$

$$\therefore \frac{dG}{G} = 0.2 \Rightarrow dG = \pm 0.2G$$

$$\therefore dG = \pm (0.2 \times 4) \Rightarrow dG = \pm 0.8$$

So, Gain will change between 3.2 to 4.8.

$$\text{Now, } ST_G = \frac{G}{T} \cdot \frac{dT}{dG} = 1$$

$$\Rightarrow \frac{dT}{dG} = 1 \times \frac{dG}{G} \Rightarrow \frac{dC}{C} = 1 \times \frac{dG}{G}$$

or

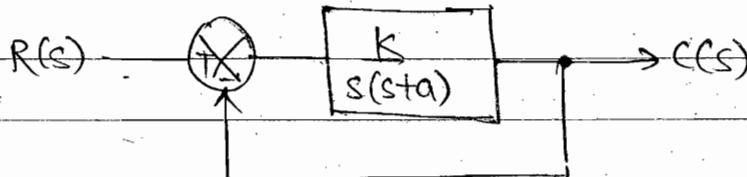
$$\boxed{\frac{dc}{c} = 20\%} *$$

- For closed loop system with u-f-b:

$$S_g^T = \frac{1}{1+GH} = \frac{1}{1+4 \times 1} = \frac{1}{5}$$

$$\therefore \frac{dc}{c} = \frac{1}{5} \times 20\% \Rightarrow \boxed{\frac{dc}{c} = 4\%} *$$

Ques: ② for the given block, calculate sensitivity of e_{ss} due to variation of K and a .



Ans: ② $G(s)H(s) = \frac{K}{s(sta)}$

$$\therefore K_v = \lim_{s \rightarrow 0} s \times \frac{K}{s(sta)} \Rightarrow K_v = \frac{K}{a}$$

$$e_{ss} = (a/K)$$

Now, $S_K^{ess} = \frac{K \times K \times (-a/K)}{(a)} = -1$

$$\boxed{S_K^{ess} = -1} *$$

$$\boxed{\frac{de_{ss}}{e_{ss}} = -\frac{dk}{k}} *$$

Also, $S_a^{ess} = \frac{a \times K \times 1/K}{a} = 1$

$$\boxed{S_a^{ess} = 1} *$$

or $\boxed{\frac{de_{ss}}{e_{ss}} = \frac{da}{a}} *$

e_{ss} and a will change proportionally

Chapter-5

STABILITY AND ROUTH-HURWITZ STABILITY CRITERIA

* Stability is defined in terms of two parameters i.e.

- (i) Absolute Stability
- (ii) Relative Stability.

(i) Absolute stability :

- * It is defined in terms of location of pole and for closed loop system to be stable, all poles should lie in the left half plane.

Routh-Hurwitz Criteria, Root Locus, Nyquist Plot define
Absolute stability.

(ii) Relative stability :

- * It is defined in terms of Damping Ratio, Gain Margin and Phase Margin. If open loop system is Non-minimum phase system, then for closed loop system to be stable, Gain Margin and Phase Margin should be Negative.

* If open loop system is Minimum Phase system, then for closed loop system to be stable, then Gain Margin and Phase Margin should be Positive.

* In 2^{nd} order system, Relative stability is defined by ξ .
For 2^{nd} order system to be stable, ξ will be positive.

- * In R-H criterion for stability, :

* R-H table gives information about poles lying in right-half of s-plane. It will not give any information about poles lying on left-half of s-plane.

* Non-Minimum Phase System :

- It is a system which contains atleast one pole or zero on right-half of s-plane.

* Minimum Phase System :

- It is a system which does not contain any pole or zero in the right-half of s-plane.

* Properties of Routh Table :

- i) R-H criterion is applicable only for Closed Loop Systems because in information for Routh table, we use characteristics equation and characteristics equation is defined for closed loop systems.
- ii) For closed loop system to be stable, all elements in first column of Routh-table must be of same sign ; either positive or Negative.
No. of times change in sign represents the number of poles lying on Right-half of s-plane, thus system will be unstable.
- iii) In characteristics equation, if any power of s is missing, that represents the presence of atleast one pole on Right-half and closed loop system will be unstable.
- iv) If characteristics equation contains either even power of s or odd power of s, then there will be possibility that poles can locate on Imaginary axis.
- v) In characteristics equation, the co-efficient of s should be Real, it should not be either Imaginary, complex or sinusoidal.

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Example: $g(s) = 1 + G(s)H(s) = a_6s^6 + a_5s^5 + a_4s^4 + a_3s^3 + a_2s^2 + a_1s + a_0 = 0.$

Solution:

| | | | | |
|-------|-------------------------|-------------------------|-------|-------|
| s^6 | a_6 | a_4 | a_2 | a_0 |
| s^5 | a_5 | a_3 | a_1 | |
| s^4 | $(a_5a_4 - a_6a_3)/a_5$ | $(a_5a_2 - a_6a_1)/a_5$ | 0 | |
| s^3 | $(b_1a_3 - b_2a_5)/b_1$ | $(b_1a_1 - a_5a_2)/b_1$ | 0 | |
| s^2 | $(c_1b_2 - b_1c_2)/c_1$ | a_0 | | |
| s^1 | $(d_1c_2 - c_1a_0)/d_1$ | 0 | | |
| s^0 | a_0 | | | |

where, $b_1 = \frac{a_5a_4 - a_6a_3}{a_5}; b_2 = \frac{a_5a_2 - a_6a_1}{a_5}$

$$c_1 = \frac{b_1a_3 - b_2a_5}{b_1} \quad c_2 = \frac{(b_1a_1 - a_5a_2)}{b_1}$$

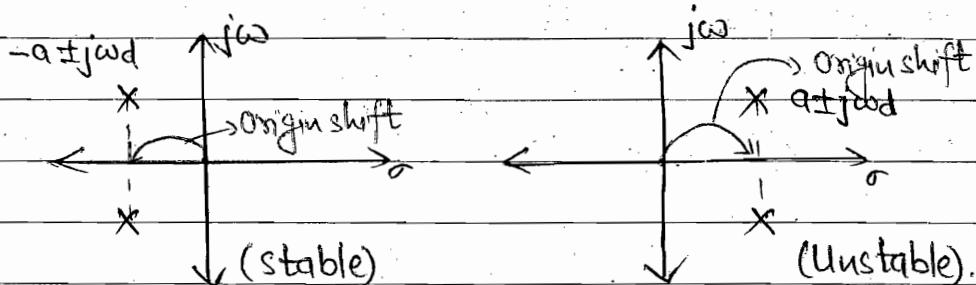
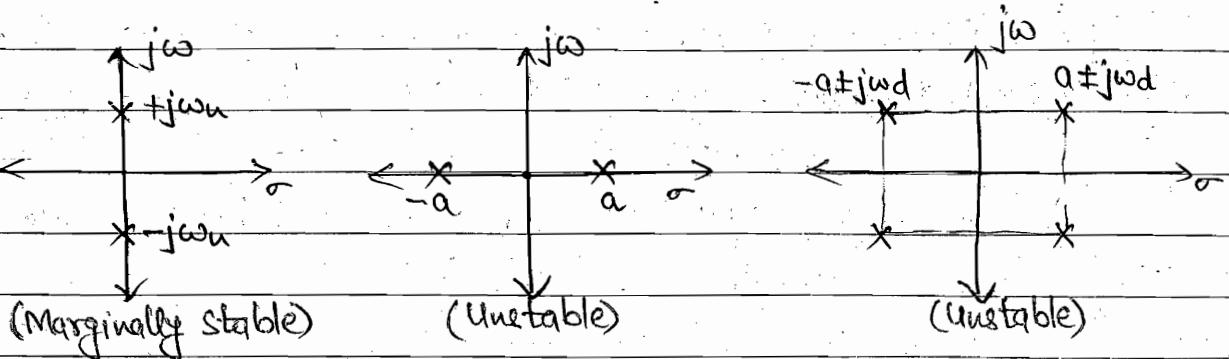
$$d_1 = \frac{(c_1b_2 - b_1c_2)}{c_1} \quad d_2 = \frac{(d_1c_2 - c_1a_0)}{d_1}$$

→ Case-I : If Any element of first column becomes Zero(0).

- If any element of first column becomes 0, in that case, all elements of Next row will become ∞ and R-H table will terminate at that row. To extend R-H table, we will replace 0 with some variable, after that we will complete our Routh table and after completion of Routh table, again we will replace that variable with 0 in entire Routh table.

→ Case-II : If All elements of any odd row becomes Zero(0).

- If all elements of any odd row becomes 0, then Auxillary characteristics equation of even^{row} just above that odd row will be purely divisible with main characteristics equation and main characteristics equation will contain all poles of Auxillary characteristics equation and poles of Auxillary equation will locate at Image location about either x or y-axis.



In normal case, Routh-table gives only information about poles but for these cases, Routh-table gives the location of poles.

* The auxiliary characteristics equation will give exact location of Image pole.

* If more than one time, odd row is becoming zero(0), then that represents the existence of more than one pair of pole at common Image location and system will be unstable.

Numericals

Ques:- ① The characteristic equation of a system is : $s^5 + s^4 + 2s^3 + 2s^2 + 3s + 5 = 0$
Determine total number of poles lying in the right-half of s-plane.

Ans:- ①

| | | | | |
|-------|---|----|---|--|
| s^5 | 1 | 2 | 3 | |
| s^4 | 1 | 2 | 5 | |
| s^3 | 0 - d - | -2 | | |
| s^2 | $(2d+2)/d = \infty$ | 5 | | |
| s^1 | $\left[\frac{(-4d-4)-5d}{d} \right] / \left(\frac{2d+2}{d} \right)$ | | | |
| s^0 | 5 | | | |

$\frac{-2-5d^2}{(2d+2)} = -2$ (as $d=0$)

∴ Two times sign changes, so, Right-pole = 2.

- In this case, 2 times sign changes. It represents out of total 5 poles,

$$RHP = 2$$

LHP = 3, and system will be Unstable.

Ques:- (2) The characteristic equation of a system is :

$$s^6 + 3s^5 + 4s^4 + 6s^3 + 5s^2 + 3s + 2 = 0$$

Comment on the stability of system. Also, determine total poles lying on jw axis and calculate undamped Natural frequency.

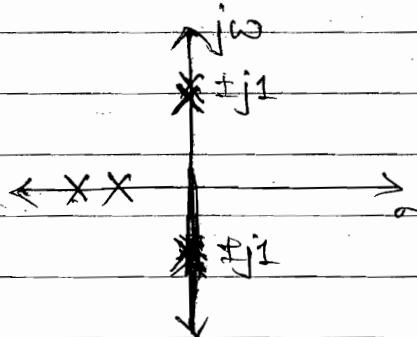
Ans:- (2)

| | | | | | |
|-----------------------------|--------------|--------------|---|---|--|
| s^6 | 1 | 4 | 5 | 2 | |
| s^5 | 3 | 6 | 3 | | |
| s^4 | 2 | 4 | 2 | | |
| s^3 | $0^{+}8$ | $0^{+}8$ | | | $\frac{5 \times 6 - 16}{2}$ |
| s^2 | 2 | 2 | | | $\frac{5}{2}$ |
| s^1 | 0 | 4 | | | $\Rightarrow \frac{30 - 32}{5} = -\frac{2}{5}$ |
| s^0 | 2 | | | | |

Symmetric Poles

$$\therefore A(s) = 2s^4 + 4s^2 + 2 = 0$$

$$\frac{dA(s)}{ds} = 8s^3 + 8s^1$$



\therefore Finding solutions of $A(s)$.

$$\therefore 2(s^2 + 1)(s^2 + 1) = 0 \Rightarrow s = \pm j1, \pm j1$$

\therefore Imaginary Poles = 4

$$LHP = 2$$

$$RHS = 0.$$

Conventionally, To find remaining poles, divide $q(s)$ with $\Lambda(s)$.

$$\begin{array}{r} 2s^4 + 4s^2 + 2 \\ \times s^6 + 3s^5 + 4s^4 + 6s^3 + 5s^2 + 3s + 2 \\ \hline 3s^8 + 2s^7 + 6s^6 + 4s^5 + 3s^4 + 2 \\ \times s^5 + 6s^3 + 3s \\ \hline 2s^4 + 4s^2 + 2 \\ 2s^4 + 4s^2 + 2 \\ \hline \times \times \times \end{array}$$

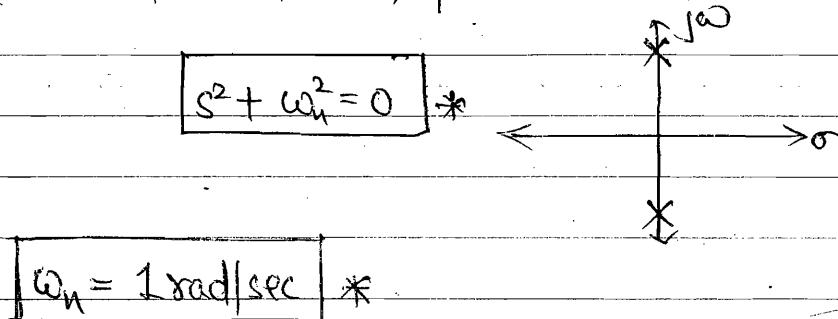
$$\therefore 2s^4 + 4s^2 + 2 = 0 \quad \text{and} \quad s^2 + 3s + 2 = 0.$$

$$s = \pm j1, \pm j1 \quad (s+1)(s+2) = 0$$

$$s = -1, -2.$$

∴ Two poles lie on left-half of s-plane.

$$\therefore s^2 + 2\xi\omega_n s + \omega_n^2 = 0, \text{ for } \xi = 0.$$

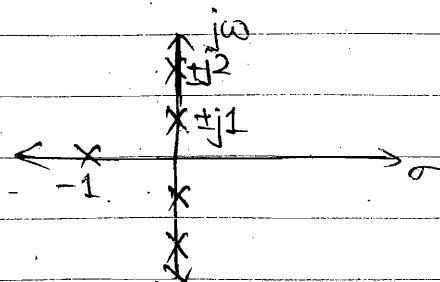


System will be Unstable.

Ans

** For Example:-

(1)



$$(s+1)(s^2+4)(s^2+1) = 0.$$

$$\therefore q(s) = s^5 + s^4 + 5s^3 + 5s^2 + 4s + 4 = 0.$$

* Here the 5th order system is made up of 2 2nd order systems having ω_n of 1 rad/sec and 2 rad/sec.

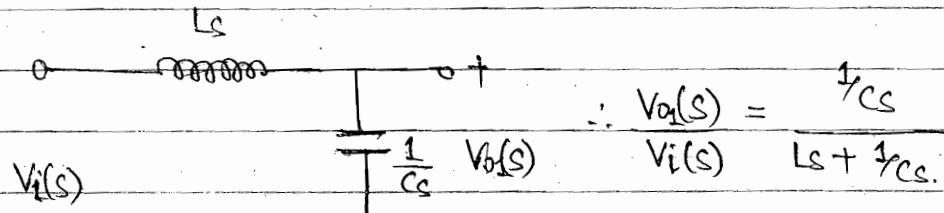
Using Routh-Hurwitz criterion,

| | | | | |
|-------|-------------------|--------------------|---|-----------------------------|
| s^5 | 1 | 5 | 4 | |
| s^4 | 1 | 5 | 4 | $A(s) = s^4 + 5s^2 + 4 = 0$ |
| s^3 | $0 \rightarrow 4$ | $0 \rightarrow 10$ | | $dA(s) = 4s^3 + 10s$ |
| s^2 | 2.5 | 4 | | dt |
| s^1 | 3.6 | | | |
| s^0 | 4 | | | |

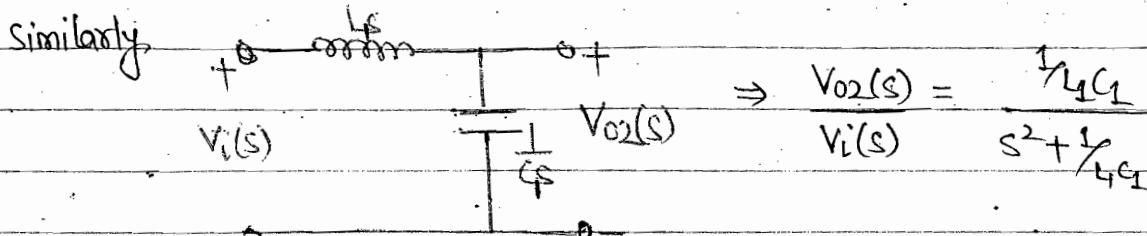
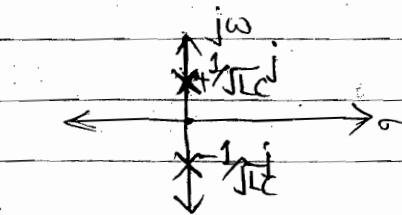
* $s^1 \neq 0$ here because $A_1(s) = 2.5s^2 + 4 = 0$ is not divisible with $q(s)$.

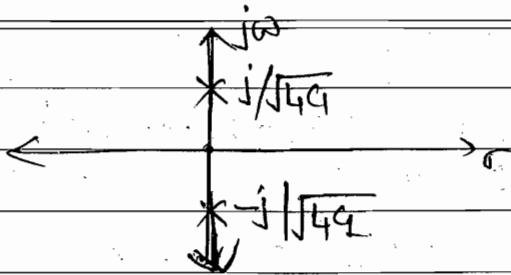
* If $q(s)$ is divisible by $A_1(s)$, then odd row will become 0.

* In 2nd order systems, Marginally Stable conditions come for L-C circuit.

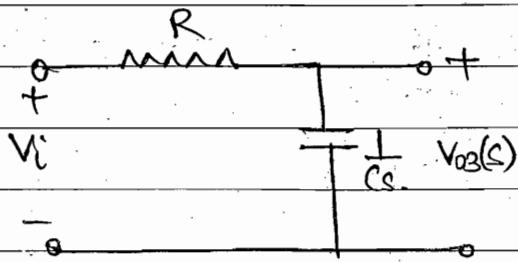


$$\text{or } \frac{V_{o1}(s)}{V_i(s)} = \frac{\frac{1}{j\omega}}{\frac{1}{C_s} + \frac{1}{j\omega}}$$



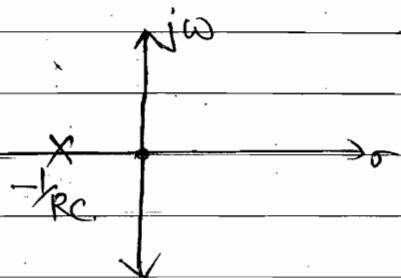


Again,

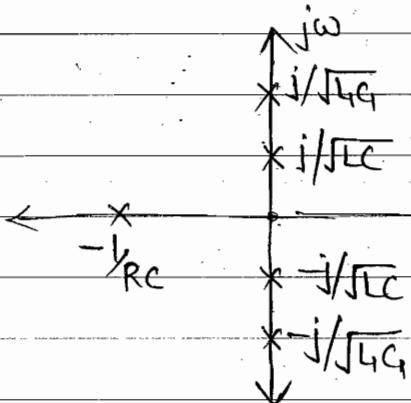


$$\frac{V_{o3}(s)}{V_i(s)} = \frac{1/R}{s + 1/(RC)}$$

* Cascading all the three networks,



$$\frac{V_o(s)}{V_i(s)} = \frac{1}{(LCs^2+1)(4G_s^2+1)(RCs+1)}$$



It looks same as our taken example.
[Take $L=C=1$,
 $G_1=G_2=\frac{1}{2}$, $R=C=1$.]

Ques:- 3) The ORIE of a system is : $G(s)H(s) = \frac{K}{s(Ts+1)}$

Determine value of K and T so that all poles lie on left half side of line $s = -a$.

Ans:- 3) $g(s) = 1 + \frac{K}{Ts+1} = Ts^2 + s + k = 0$.

or $s^2 + \frac{s}{T} + \frac{k}{T} = 0$.

$$s+a=0$$

$$z = sa,$$

| | | | |
|--------|---------------|-------|---------------|
| s^2 | 1 | k/T | $ s = z-a >$ |
| $-s^1$ | $\frac{1}{T}$ | | |
| s^0 | $\frac{k}{T}$ | | |

Replace ' s ' with ' $s-a$ ' ;

$$g(s-a) = (s-a)^2 + \frac{(s-a)}{T} + \frac{k}{T} = 0.$$

$$\Rightarrow T[s^2 + a^2 - 2as] + (s-a) + k = 0$$

$$\text{or } g(s-a) = Ts^2 + (1-2aT)s + (k-a+a^2T) = 0$$

| | | |
|-------|------------|------------|
| s^2 | T | $k-a+a^2T$ |
| s^1 | $(1-2aT)$ | 0. |
| s^0 | $k-a+a^2T$ | |

$$\therefore 1-2aT > 0 \Rightarrow T < \frac{1}{2a}$$

\therefore For system to be stable; $0 < T < \frac{1}{2a}$ *

$$\text{Also, } k-a+a^2T > 0 \Rightarrow k > a-a^2T$$

$$\therefore k > a-a^2T *$$

• For Marginally stable, $T = \frac{1}{2a}$ *

* Checking boundary conditions:

For $T = \frac{1}{2a}, 0$

| | | |
|-------|---|-----------|
| s^2 | 0 | $(k-a)$ |
| s^1 | 1 | |
| s^0 | | $(k-a)$. |

$$\therefore k > a *$$

for $T = \frac{1}{2a},$

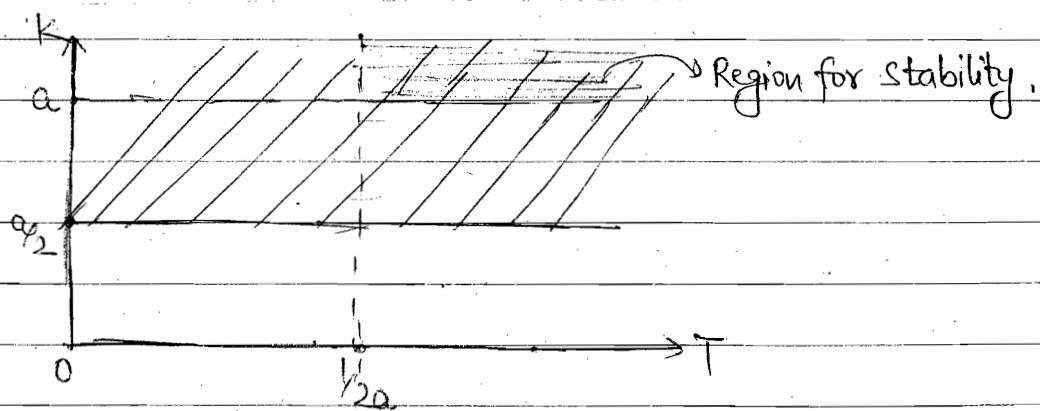
| | | |
|-------|----------------|-----------|
| s^2 | $\frac{1}{2a}$ | $k - a/2$ |
| s^1 | 0 | |
| s^0 | | $k - a/2$ |

$$\therefore k > a/2 *$$

$$\therefore Ts^2 + s + k = 0 \Rightarrow \frac{1}{2a}s^2 + s + k = 0.$$

$$\Rightarrow s^2 + 2as + 2ak = 0.$$

$$\therefore s = \sqrt{\frac{a}{2k}} *$$



* For overall stability: $0 < T < \frac{1}{2a}, k > 0.$

Ques-④ The $q(s) = 1 + G(s)H(s) = s^4 + 5s^3 + 2s^2 + 5s + K = 0$. Determine the range of K for system to be stable.

Ans:- 4)

| | | | |
|-------|-------------------|---|-----|
| s^4 | 1 | 2 | K |
| s^3 | 5 | 5 | |
| s^2 | 1 | | K |
| s^1 | $\frac{(5-K)}{1}$ | | |
| s^0 | K | | |

• For stable system,

$$0 < K < 1 *$$

• At $K=0$; $s^4 \quad 1 \quad 2 \quad 0$

| | | |
|-------|---|---|
| s^3 | 5 | 5 |
| s^2 | 1 | 0 |
| s^1 | 5 | |
| s^0 | 0 | |

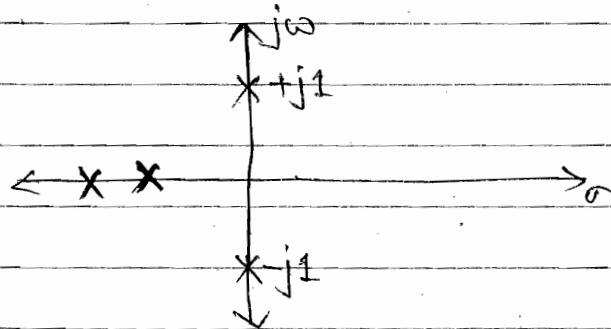
For $K=0$ also,
system is stable.

• At $K=1$;

| | | | |
|-------|---|---|---|
| s^4 | 1 | 2 | 1 |
| s^3 | 5 | 5 | |
| s^2 | 1 | 1 | |
| s^1 | 0 | | |
| s^0 | 1 | | |

Poles are at Image location
for $K=1$, system is Marginally stable.

$$A(s) = s^2 + 1 = 0 \Rightarrow s = \pm j1 *$$



Ques:- 5) The OLF of a system is: $G(s)H(s) = \frac{k(s+1)}{s^3 + bs^2 + 3s + 1}$

Determine the value of k and b , so that system oscillates at the frequency of 2 rad/sec.

Ans:- 5)

$$q(s) = 1 + G(s)H(s) = s^3 + bs^2 + 3s + 1 + ks + K = 0.$$

| | | |
|-------|------------------------|---------|
| s^3 | 1 | $(k+3)$ |
| s^2 | b | $(k+1)$ |
| s^1 | $\frac{b(k+3)-k-1}{b}$ | |
| s^0 | $k+1$ | |

\therefore For poles at Image location, $s^1 = 0$.

$$\therefore b(k+3) = k+1$$

$$\boxed{b = \frac{k+1}{k+3}} *$$

$$\text{Now, } A(s) = bs^2 + (k+1) = 0.$$

$$\text{or } s^2 = -\frac{(k+1)}{b} = -\frac{(k+1)}{(k+1)} \times \frac{(k+3)}{(k+1)}$$

$$\text{or } s = \pm j\sqrt{(k+3)}$$

$$\text{As } \omega_n = 2 \text{ rad/sec} \Rightarrow 2 = \sqrt{k+3}$$

$$\text{or } k+3 = 4 \Rightarrow \boxed{k=1} * \boxed{b=\frac{1}{2}} *$$

Ques:- (6) The OLTF of a system is: $G(s)H(s) = \frac{k}{s(s+1)(s+3)}$. Determine the value

of K so that settling time of 2^{nd} order underdamped system will be 12 seconds.

$$\text{Ans:- (6)} \quad q(s) = 1 + G(s)H(s) = s[s^2 + 4s + 3] + k = 0$$

$$\text{or } q(s) = s^3 + 4s^2 + 3s + k = 0$$

| | | |
|-------|------------------|-----|
| s^3 | 1 | 3 |
| s^2 | 4 | k |
| s^1 | $\frac{12-k}{4}$ | |
| s^0 | k | |

$$\text{As } t_s = \frac{4}{\xi \omega_n} = 12 \Rightarrow \xi \omega_n = \left(\frac{1}{3}\right).$$

$$\therefore (s^2 + 2\xi \omega_n s + \omega_n^2)(s+p) = 0.$$

$$\Rightarrow s^3 + (2\xi \omega_n s^2) + \omega_n^2 s + ps^2 + 2\xi \omega_n ps + \omega_n^2 p = 0$$

$$\Rightarrow s^3 + (2\xi \omega_n + p)s^2 + s(\omega_n^2 + 2\xi \omega_n p) + \omega_n^2 p = 0. \quad (1)$$

Comparing eq-(1) with $q(s)$:

$$2\xi \omega_n + p = 4, \quad \omega_n^2 + 2\xi \omega_n p = 3; \quad \omega_n^2 p = k$$

$$\Rightarrow \frac{2}{3} + p = 4, \quad \omega_n^2 + \frac{2p}{3} = 3; \quad \omega_n^2 p = k$$

$$\text{By solving this, } p = 4 - 2\frac{1}{3} = 10\frac{1}{3}.$$

$$\omega_n^2 = 3 - 2\frac{1}{9} = \frac{7}{9}, \quad \Rightarrow \omega_n = \frac{\sqrt{7}}{3}.$$

$$\therefore K = \frac{7}{9} \times 10\frac{1}{3} = \frac{70}{27}$$

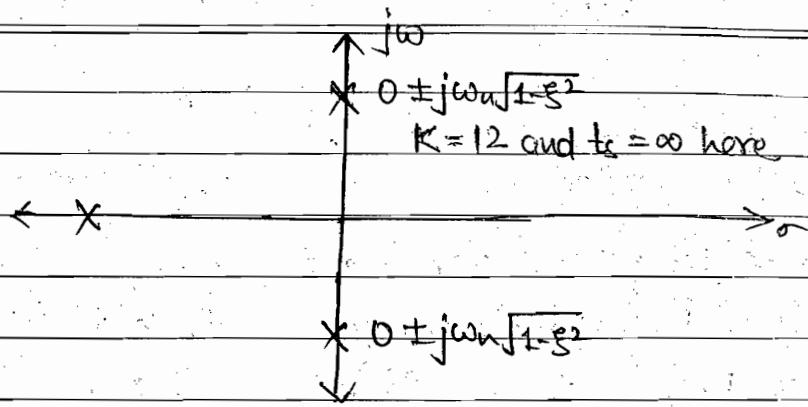
$$\therefore \boxed{K = \frac{70}{27}} *$$

$$\text{And } \omega_d = \omega_n \sqrt{1-\xi^2} = \sqrt{\frac{2}{3}}.$$

$$* \text{ From Routh-table, } s^1 = 0 \Rightarrow K = 12.$$

$$\text{and } s = \pm j\sqrt{3} \quad \therefore \omega_n = \sqrt{3} \text{ rad/sec.}$$

$$\text{As } t_s = \frac{4}{\xi \omega_n} \Rightarrow \xi \omega_n = \frac{1}{3} \Rightarrow \xi = \frac{1}{3\sqrt{3}}$$



- For $t_c \neq 0$, Real part must exist. So, origin must be shifted to $-k_3$.

$$\therefore q(s-k_3) = (s-k_3)^2 + 4(s-k_3)^2 + 3(s-k_3) + K = 0.$$

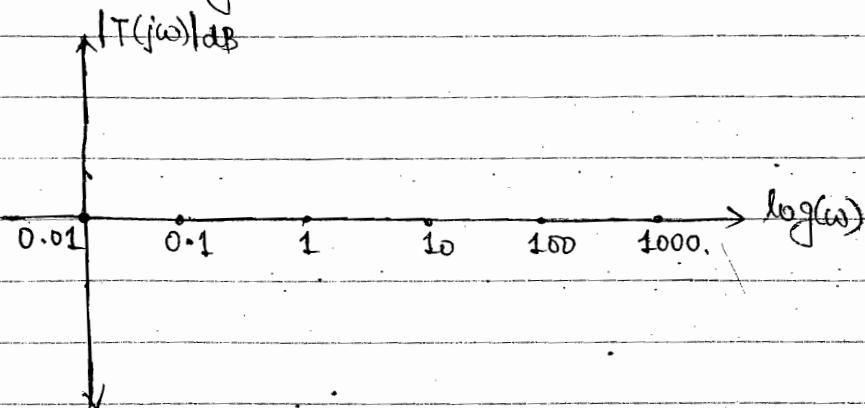
so, $K = \frac{T_0}{27}$ will be got after solving above equation.

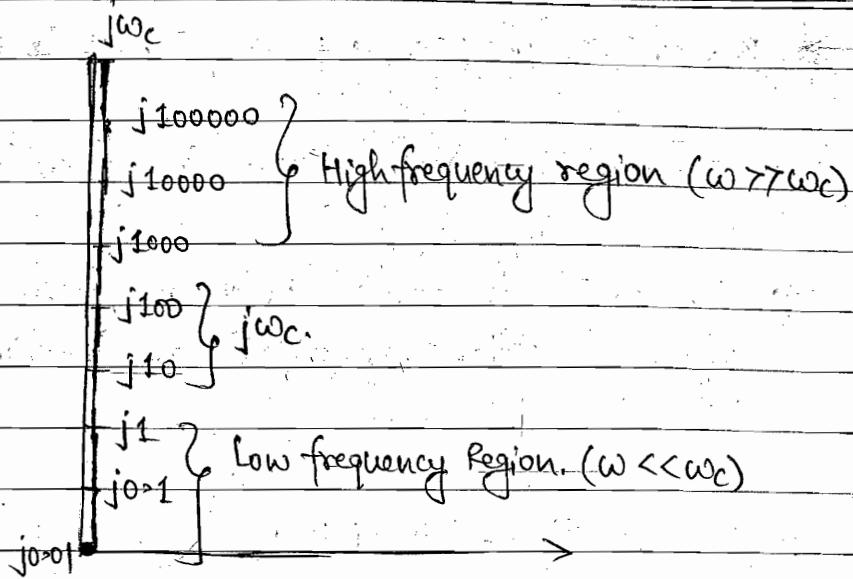
and $s = \pm j\sqrt{2}k_3$, this $\sqrt{2}k_3$ must be ω_d .

Chapter-6

BODE PLOT

- * In case of Bode plot, variable is Positive frequency line of s-plane. For each frequency, we will calculate Magnitude as well as Phase Angle and then we will connect Locus of all points and that plot will be known as Bode Plot.
- * In Bode Plot, Magnitude plot is Logarithmic plot and it is in dB and Phase angle plot is in degrees.
- * As Magnitude plot is logarithmic plot, so its abscissa, is in terms of $\log(\omega)$ and as we know that $\log(0)$ is invalid quantity, so it is not possible to calculate Magnitude at $\omega=0$. Hence, origin of Bode plot will never be 0, it will be 0.1, 0.001 ... however, Phase angle plot is in terms of ω and $\omega=0$ is a valid quantity but in Bode Plot, for each frequency, we calculate Magnitude as well as Phase Angle. If Magnitude is undefined at $\omega=0$, then phase angle will also be undefined at $\omega=0$.
- *
- * Bode Plot defines Relative Stability i-e stability will be defined in terms of Gain Margin and Phase Margin. As we know that Bode Plot is valid only for Minimum phase system and for closed loop system to be stable, both Gain Margin and Phase Margin should be positive.



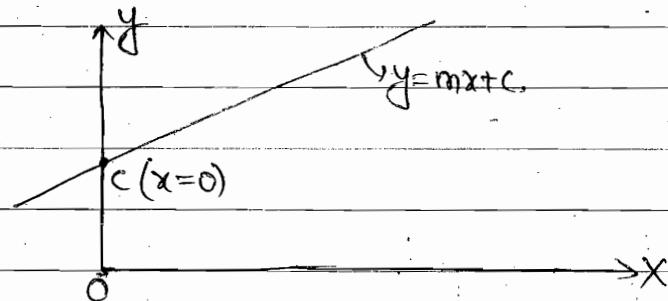


Now, $\left(\frac{P_o}{P_i}\right)_{dB} = 20 \log_{10} \left(\frac{V_o}{V_i} \right)^2 = 20 \log_{10} \left(\frac{V_o}{V_i} \right) = 20 \log_{10} \left(\frac{I_o}{I_i} \right) = 20 \log_{10} [T(jw)]$

$\left(\frac{P_o}{P_i}\right)_{\text{octave}} = 3 \log_2 \left[\frac{P_o}{P_i} \right] = 3 \log_2 \left[\frac{P_o}{P_i} \right]^2 = 6 \log_2 \left(\frac{V_o}{V_i} \right) = 6 \log_2 [T(jw)]$

- In case of Bode Plot, we use equation of line: $y = mx + c$, where m = slope and c = y -intercept or intercept at $(\omega=1)$.

* This intercept itself represents DC gain of the system.



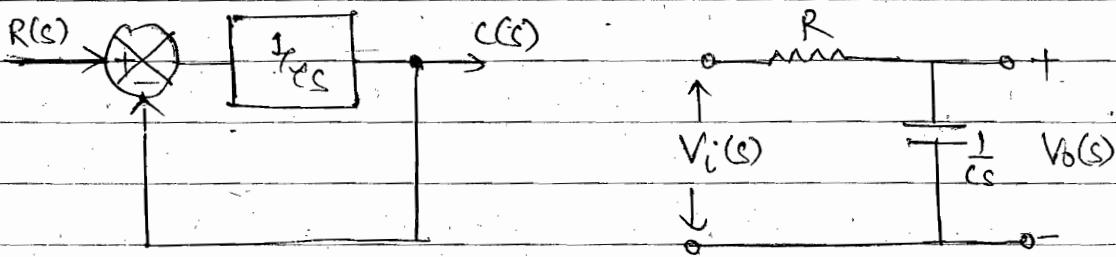
$$\therefore |T(j\omega)|_{dB} = m \log(\omega) + c \quad *$$

At $\omega=1$,

$$k = |T(j1)| = c = \text{DC Gain} \quad *$$

* Bandwidth of open loop and closed loop systems:

- * Bandwidth is not defined for system whose pole lies on origin.
- * Bandwidth is defined only for system whose poles lie on any point other than origin and location of dominant pole itself is Bandwidth.
- * Bandwidth of Closed Loop system > Bandwidth of Open Loop System.



$$C(s) = \frac{1}{RC} = \frac{1}{s+1/R}$$

$$V_o(s) = \frac{1}{RC} = \frac{1}{s+1/R}$$

Put $s = j\omega$ *

$$\frac{V_o(j\omega)}{V_i(j\omega)} = \frac{1}{s+1/R} = \frac{1}{j\omega + 1/R}$$

$$\text{or } \left| \frac{V_o(j\omega)}{V_i(j\omega)} \right| = \frac{1}{\sqrt{1+\omega^2 R^2 C^2}}$$

Now, * For $\omega \ll \omega_c$, $\therefore \frac{V_o}{V_i} = 1 \Rightarrow V_o = V_i$
ie $\omega \rightarrow 0$

or $P_o = P_i$ *. i.e Power dissipation across
Resistor (P_R) = 0.

* For $\omega \gg \omega_c$, $\frac{V_o}{V_i} = 0 \Rightarrow V_o = 0 \Rightarrow P_c = 0$ *.
ie $\omega \rightarrow \infty$.

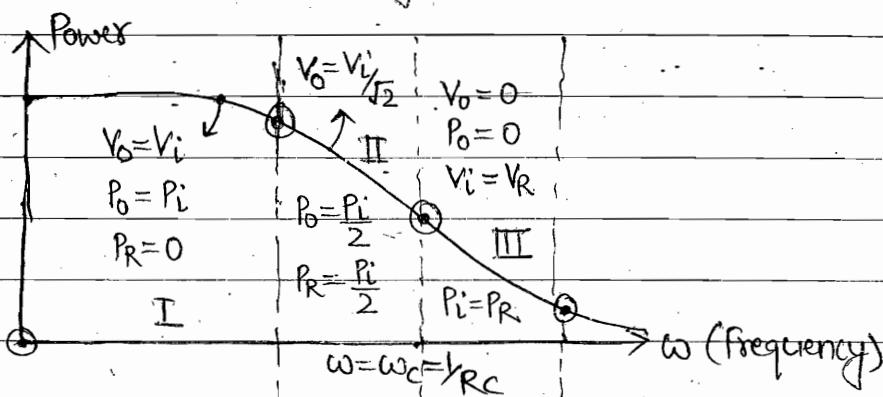
$\therefore P_i = P_R$ * All power is dissipated by Resistor.

$$\text{For } \omega = \frac{1}{RC}, \quad \frac{V_o}{V_i} = \frac{1}{\sqrt{2}} \Rightarrow V'_i = \sqrt{2} V_o \quad *$$

$$P_o = \frac{1}{2} P_i \quad * \quad P_R = \frac{1}{2} P_i \quad *$$

so, half power is stored by capacitor and half power is being dissipated by Resistor.

* Graph of Power vs Frequency:



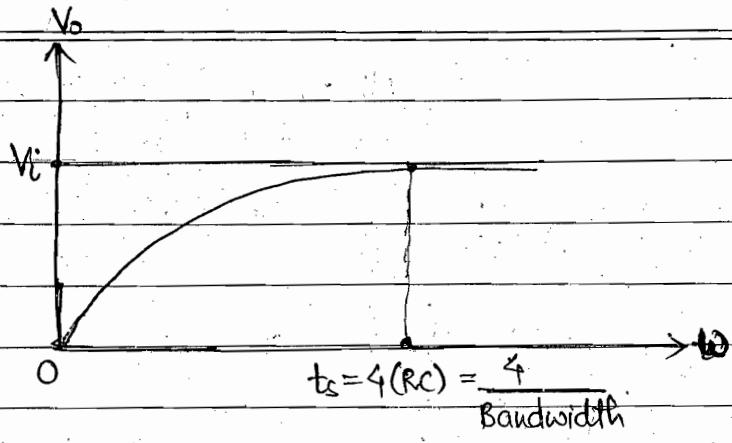
- * In Region II, in comparison to region 1, P_o is decreasing and P_R is increasing.
- * Again, in Region III, P_o further decreases to 0 and $P_i = P_R$ here.
- * At the most, we can select frequencies upto 0 to ω_c because after ω_c , power reduces by more than $\frac{1}{2}$.

$$\therefore \text{Bandwidth} = \omega_H - \omega_L \Rightarrow \Delta\omega = \omega_c - 0$$

$$\therefore \text{Bandwidth} (\Delta\omega) = \omega_c = \frac{1}{RC} = \text{location of Pole} \quad *$$

Now, as $\left| \frac{V_o(j\omega)}{V_i(j\omega)} \right| = \frac{1}{\sqrt{2}}$, converting it into dB,

$$\left| \frac{V_o(j\omega)}{V_i(j\omega)} \right|_{\text{dB}} = 20 \log_{10} \left(\frac{1}{\sqrt{2}} \right) \Rightarrow \left| \frac{V_o(j\omega)}{V_i(j\omega)} \right|_{\text{dB}} = 3 \text{ dB} \quad *$$



- Higher the bandwidth, faster will be the response of the system.
- * Bandwidth of system with pole at origin :-

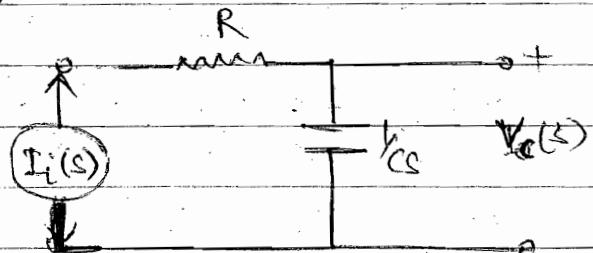
$$R(s) \quad \boxed{\frac{1}{s}} \quad C(s) \quad : \quad \frac{C(s)}{R(s)} = \frac{(1/s)}{s} \quad \textcircled{1}$$

for Step Input : $R(s) = A/s$

$$\therefore c(t) = A \cdot t$$

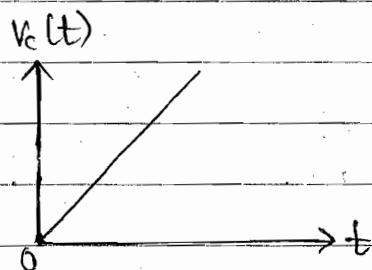
Now, this is equivalent to :-

$$\frac{V_c(s)}{I_i(s)} = \frac{(1/c)}{s}$$



For Step current, $I_i(s) = I_0/s$.

$$\therefore V_c(t) = \frac{I_0 \cdot t}{c}$$

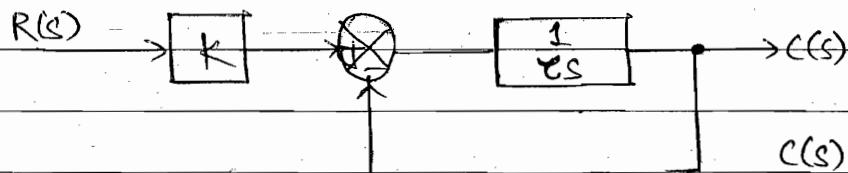


- Here, P_R and P_C are independent of Frequency, so as they are constant, so bandwidth is not defined.

From eq. (1), As $\tau = \frac{1}{\omega_c}$

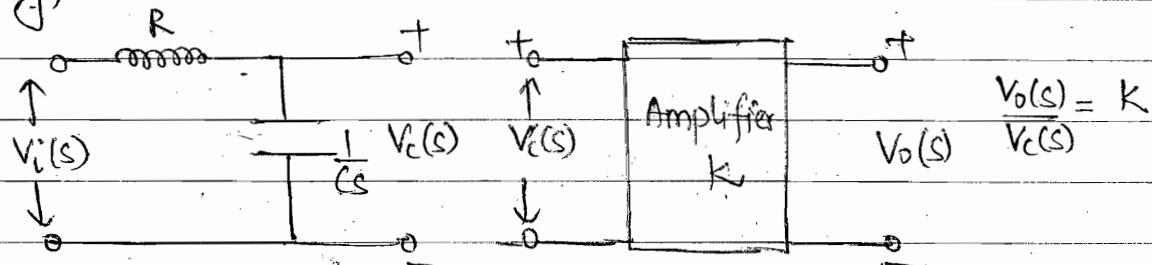
$$\therefore \frac{C(s)}{R(s)} = \frac{1}{(s/\omega_c + 1)}, \quad \omega_c \rightarrow \text{corner frequency of Pole.}$$

* Making closed loop system an open loop ↴



$$C(s) = \frac{(K\tau_c)}{R(s)} = \frac{K}{(s + k_c)} = \frac{K}{\tau_c s + 1}$$

Similarly,



∴ Cascading above two systems,

$$\frac{V_c(s)}{V_i(s)} = \frac{1/R_C}{(s + 1/R_C)}$$

$$\Rightarrow \frac{V_c(s)}{V_i(s)} \times \frac{V_o(s)}{V_c(s)} = \frac{K/R_C}{s + 1/R_C}$$

$$\therefore \boxed{\frac{V_o(s)}{V_i(s)} = \frac{(K\tau_c)}{(s + 1\tau_c)}} \quad *$$

⇒ Applying step input: $v(t) = A \cdot u(t) = A \delta_s$.

$$C(s) = \frac{(K\tau_c) \cdot A}{s(s + 1\tau_c)} = \frac{K \cdot A}{s} - \frac{(K \cdot A)}{(s + 1\tau_c)}$$

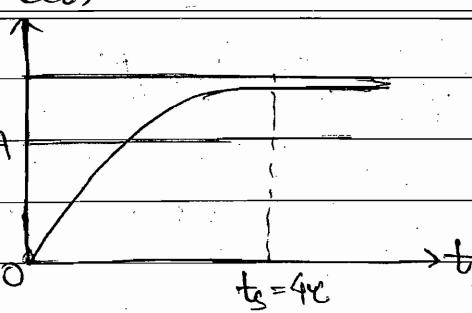
$$\boxed{c(t) = K \cdot A [1 - e^{-t/\tau_c}]} \quad *$$

$$\therefore \text{At } C(t_s = 4\tau) = K \cdot A. \quad (\text{KA})$$

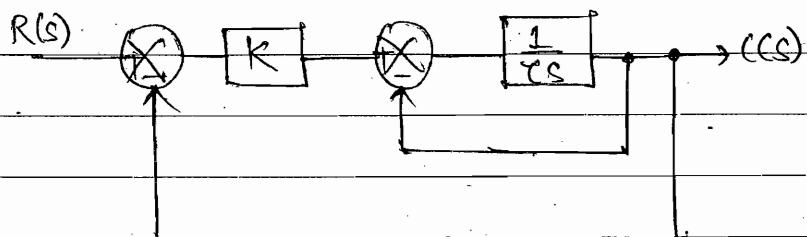
Here, DC Gain = K

Time Constant = τ

Bandwidth = $K\tau$.



Now, Making this open loop a closed loop system by providing unity feedback:



$$\therefore \frac{C(s)}{R(s)} = \frac{K}{\tau s + 1 + K} = \frac{(K\tau)}{s + (1 + K\tau)}$$

$$\text{So, Bandwidth} = \left(\frac{1+K\tau}{\tau}\right)^{\frac{1}{2}} = (1+K\tau)^{\frac{1}{2}}. \quad (> \text{open loop system's})$$

* For step input, $R(s) = A/s$

$$\therefore C(s) = \frac{(K_{K+1})A}{s} - \frac{(K_{K+1})A}{s + (1 + K\tau)}$$

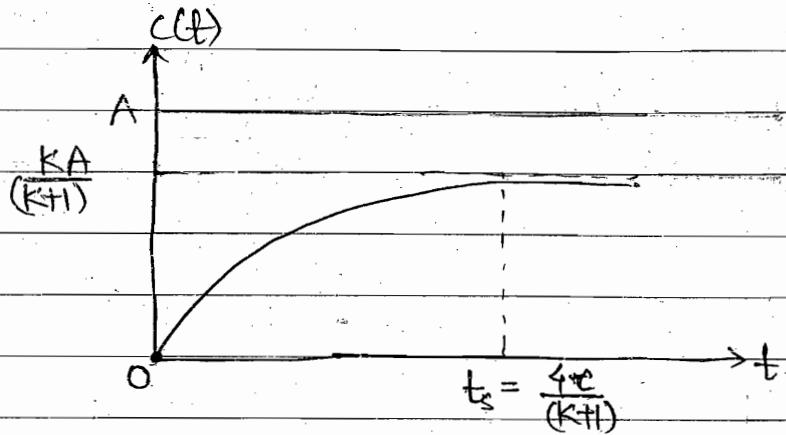
$$\therefore c(t) = \frac{K \cdot A}{(K+1)} \left[1 - e^{-\frac{(K+1)t}{\tau}} \right].$$

$$\therefore \text{At } t = t_s = 4\tau, \quad c(4\tau) = \frac{K \cdot A}{(K+1)}.$$

$$\text{Here, DC Gain} = \frac{K}{K+1} \quad (\downarrow \text{res})$$

$$\text{Time Constant} = \frac{\tau}{K+1} \quad (\downarrow \text{res})$$

$$\text{Bandwidth} = \frac{(K+1)}{\tau}. \quad (\uparrow \text{res})$$



* So, conclusions are :

- (i) Bandwidth of closed loop $>$ Bandwidth of Open Loop system.
- (ii) with increasing the feedback, DC gain decreases, t_s decreases, Bandwidth increases.
- (iii) Closed loop systems have more speed or faster response than Open loop systems.

* How to Plot Bode Plot :

$$T(s) = K$$

$$\Rightarrow T(j\omega) = K + j0 \Rightarrow |T(j\omega)| = \sqrt{K^2} = K$$

$$\text{or } |T(j\omega)|_{dB} = 20 \log K$$

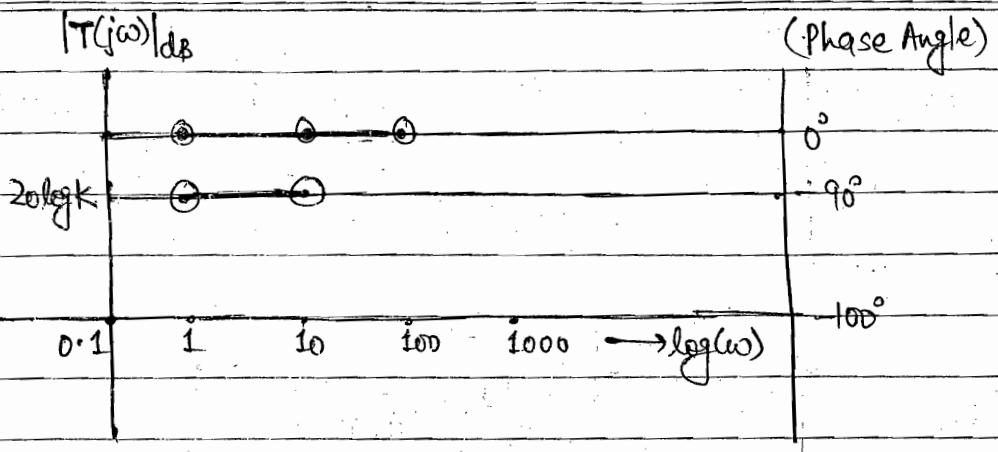
$$|T(j\omega)|_{dB} = 20 \log(K) *$$

$$\angle T(j\omega) = 0^\circ *$$

$$\text{Now, } |T(j0.1)| = 20 \log(K), \quad \angle T(j0.1) = 0^\circ$$

$$|T(j1)| = 20 \log(K)$$

$$\angle T(j0.01) = 0^\circ$$



$$\Rightarrow T(s) = \frac{1}{s}$$

$$\Rightarrow T(j\omega) = \frac{1}{j\omega}$$

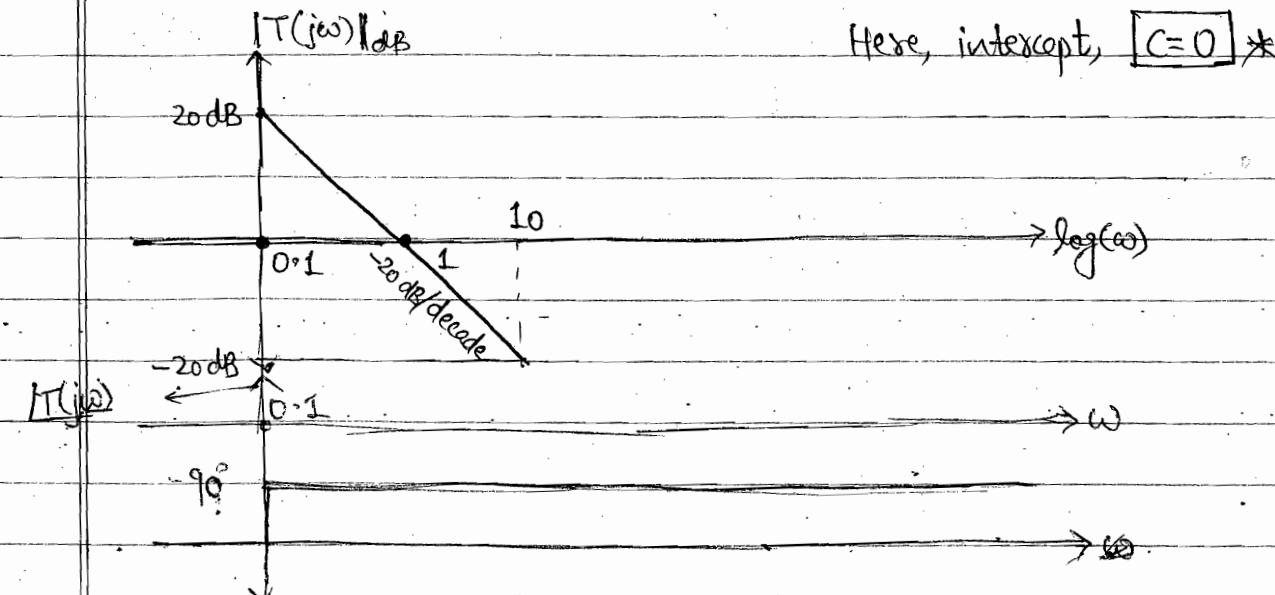
$$|T(j\omega)| = \frac{1}{\omega}, \quad |T(j\omega)| = -90^\circ.$$

$$\therefore \boxed{|T(j\omega)|_{dB} = -20\log(\omega)} * \boxed{|T(j\omega)| = -90^\circ} *$$

$$|T(j0.1)| = -20\log(0.1) = 20 \text{ dB.} \quad ; \quad |T(j0.1)| = -90^\circ$$

$$|T(j1)| = 0 \text{ dB} \quad ; \quad |T(j1)| = -90^\circ$$

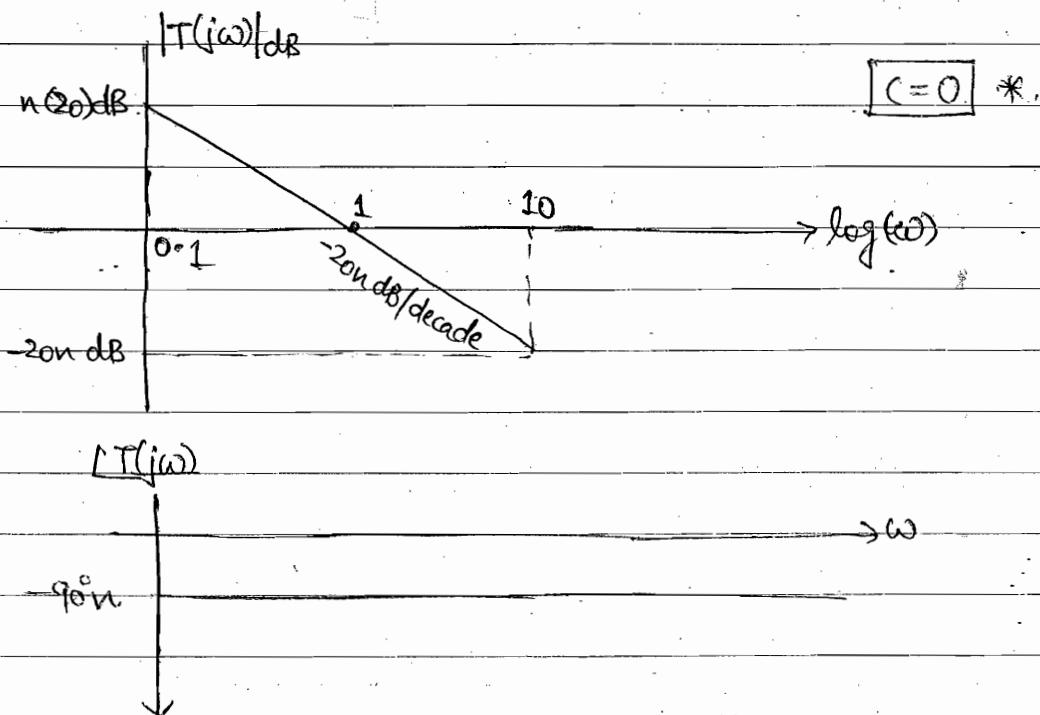
$$|T(j10)| = -20 \text{ dB.} \quad ; \quad |T(j10)| = -90^\circ.$$



$$3) T(s) = \frac{1}{s^n}$$

$$\Rightarrow T(j\omega) = \frac{1}{(j\omega)^n} \Rightarrow |T(j\omega)| = \frac{1}{\omega^n}$$

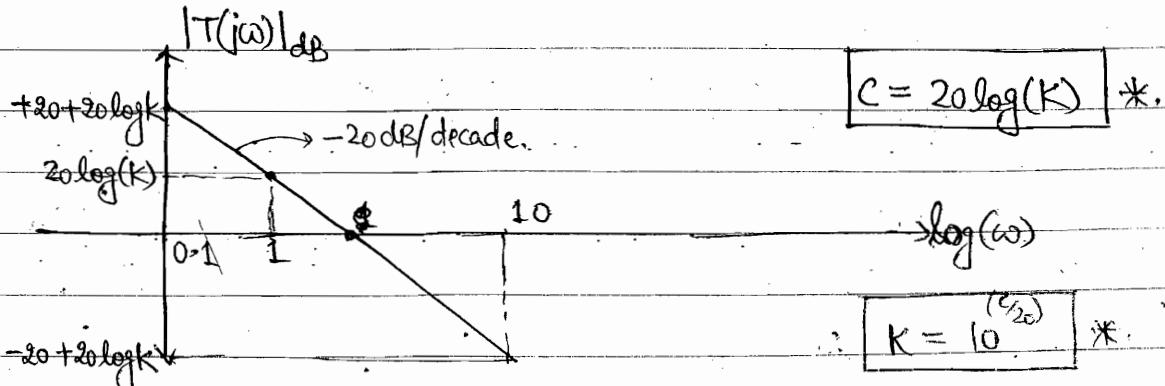
$$\therefore |T(j\omega)|_{dB} = (-20) \log(\omega) \quad * \quad |T(j\omega)| = -90^\circ n \quad *$$



$$4) T(s) = \frac{K}{s}$$

$$\Rightarrow T(j\omega) = \frac{K}{j\omega} \Rightarrow |T(j\omega)| = \frac{K}{\omega}$$

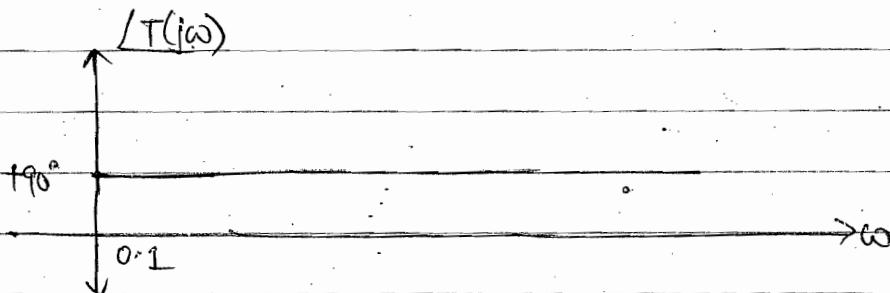
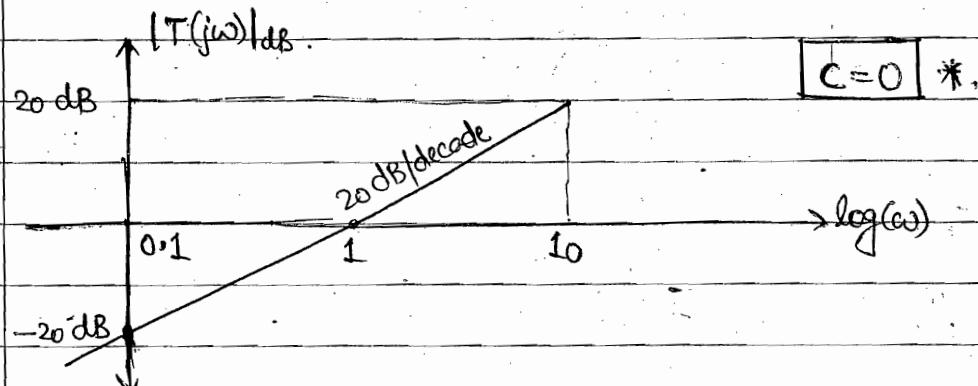
$$\therefore |T(j\omega)|_{dB} = 20 \log(K) - 20 \log(\omega) \quad * \quad |T(j\omega)| = -90^\circ \quad *$$



$$5, \quad T(s) = s.$$

$$\Rightarrow T(j\omega) = j\omega.$$

$$|T(j\omega)|_{dB} = 20 \log(\omega) \quad * \quad |T(j\omega)| = 90^\circ \quad *$$



$$6, \quad T(s) = s^n$$

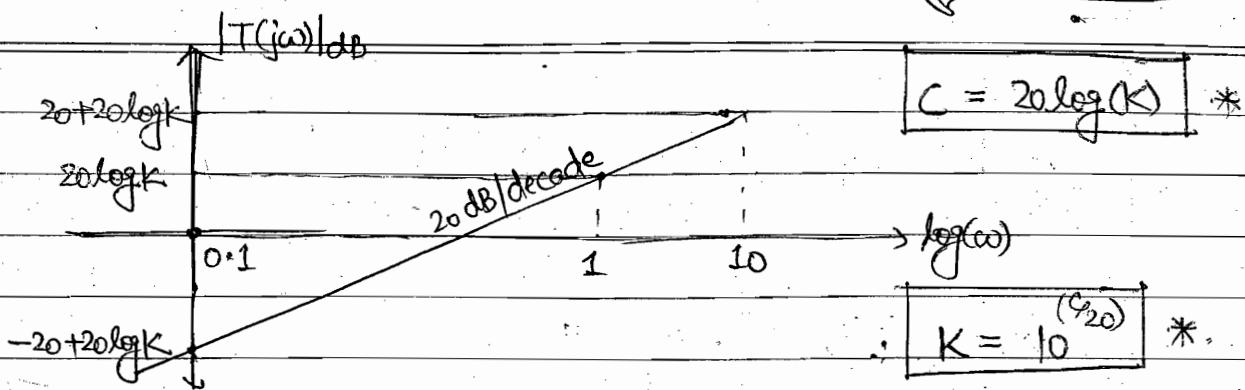
$$\Rightarrow T(j\omega) = (j\omega)^n \Rightarrow |T(j\omega)| = \omega^n.$$

$$|T(j\omega)|_{dB} = (20n) \log(\omega) \quad * \quad |T(j\omega)| = 90^\circ n \quad *$$

$$\Rightarrow T(s) = ks^n.$$

$$\Rightarrow T(j\omega) = k(j\omega)^n \Rightarrow |T(j\omega)| = k\omega^n.$$

$$\therefore |T(j\omega)|_{dB} = 20 \log(k) + 20 \log(\omega) \quad * \quad |T(j\omega)| = 90^\circ \quad *$$



* Gain (K) will only affect Magnitude but not phase.

8. $T(s) = K s^n$

$$\Rightarrow T(j\omega) = K (j\omega)^n \Rightarrow |T(j\omega)| = K \omega^n$$

$$\therefore |T(j\omega)|_{dB} = (20n) \log(\omega) + 20 \log K *$$

9. $T(s) = \frac{1}{(s/\omega_c + 1)}$

$$\Rightarrow T(j\omega) = \frac{1}{(\frac{j\omega}{\omega_c} + 1)} \Rightarrow |T(j\omega)| = \frac{1}{\sqrt{1 + (\frac{\omega}{\omega_c})^2}}$$

$$|T(j\omega)|_{dB} = -20 \log \left(\sqrt{1 + \frac{\omega^2}{\omega_c^2}} \right) \therefore |T(j\omega)| = -\tan^{-1} \left(\frac{\omega}{\omega_c} \right)$$

* So, For low frequency region, $\omega \ll \omega_c \Rightarrow \frac{\omega^2}{\omega_c^2} \rightarrow 0$.

$$\therefore |T(j\omega)|_{dB} = 0 * \quad |T(j\omega)| = 0^\circ *$$

* For $\omega = \omega_c$, $\frac{\omega}{\omega_c} = 1$

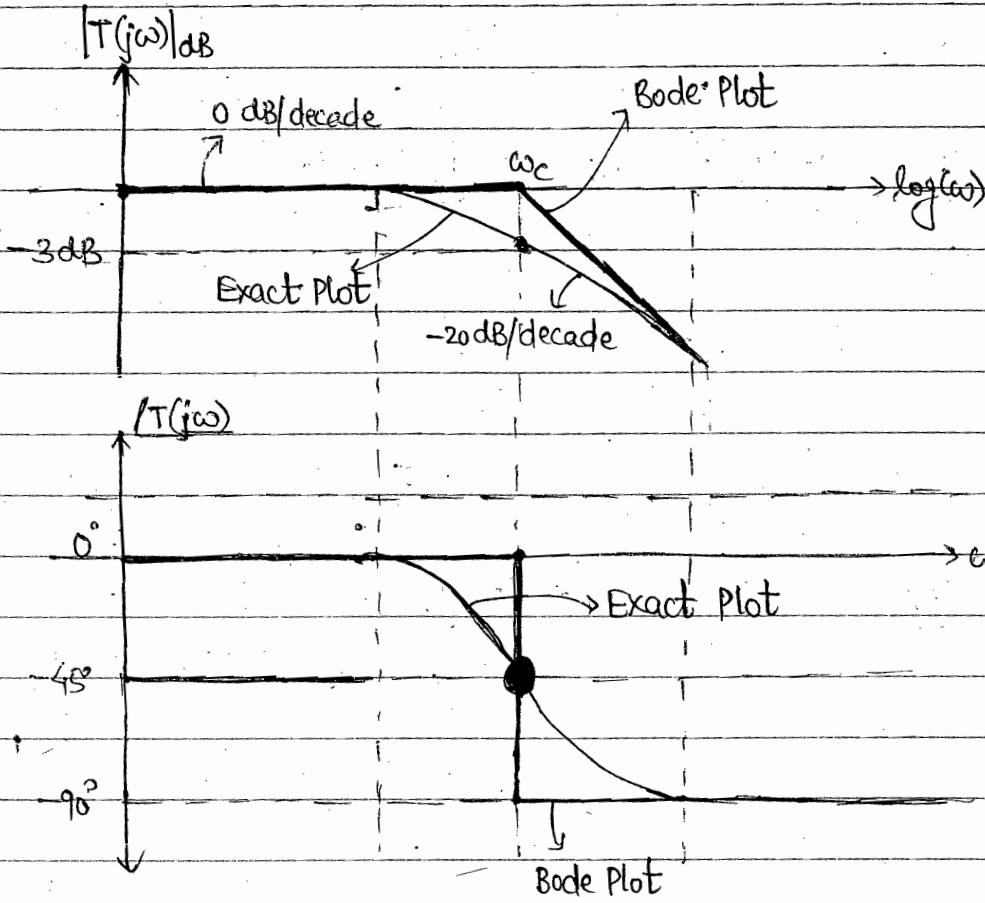
$$\therefore |T(j\omega)|_{dB} = -3 \text{ dB} * \quad |T(j\omega)| = -45^\circ *$$

* For Higher frequency region, $\omega \gg \omega_c$ or $\frac{\omega^2}{\omega_c^2} \gg 1 \approx \infty$.

$$|T(j\omega)|_{dB} = -20 \log(\omega) + 20 \log(\omega_c) \quad * \quad C = 20 \log(\omega_c)$$

Also, $|T(j\omega)| \approx -90^\circ$ *

* Exact Plot ↴



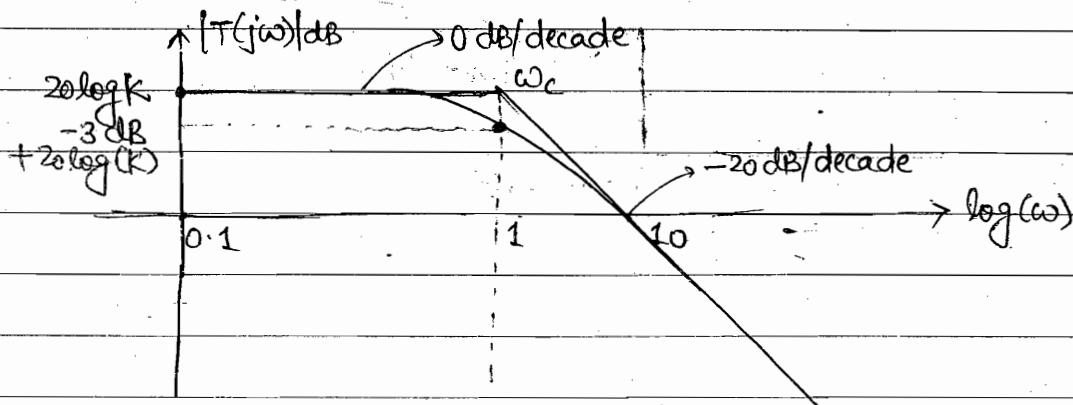
$$10) \quad T(s) = K \cdot \frac{(s)}{(\frac{s}{\omega_c} + 1)}$$

$$\Rightarrow T(j\omega) = \frac{K}{(\frac{j\omega}{\omega_c} + 1)} \Rightarrow |T(j\omega)| = \frac{K}{\sqrt{1 + (\omega/\omega_c)^2}}$$

$$|T(j\omega)|_{dB} = 20 \log(K) - 20 \log\left(\sqrt{1 + (\omega/\omega_c)^2}\right)$$

- $\omega \ll \omega_c$, $|T(j\omega)| = 20 \log(K) *$
- $\omega = \omega_c$, $|T(j\omega)| = -3 + 20 \log(K)$
- $\omega \gg \omega_c$, $|T(j\omega)| = 20 \log(k \cdot \omega_c) - 20 \log(\omega)$, * $C = 20 \log(\omega_c K)$

* Phase Angle plot will remain same.



$$\text{Q11} \quad T(s) = \left(\frac{s}{\omega_c} + 1 \right)$$

$$\Rightarrow T(j\omega) = \left[\frac{j\omega}{\omega_c} + 1 \right] \Rightarrow |T(j\omega)| = \sqrt{1 + (\frac{\omega}{\omega_c})^2}$$

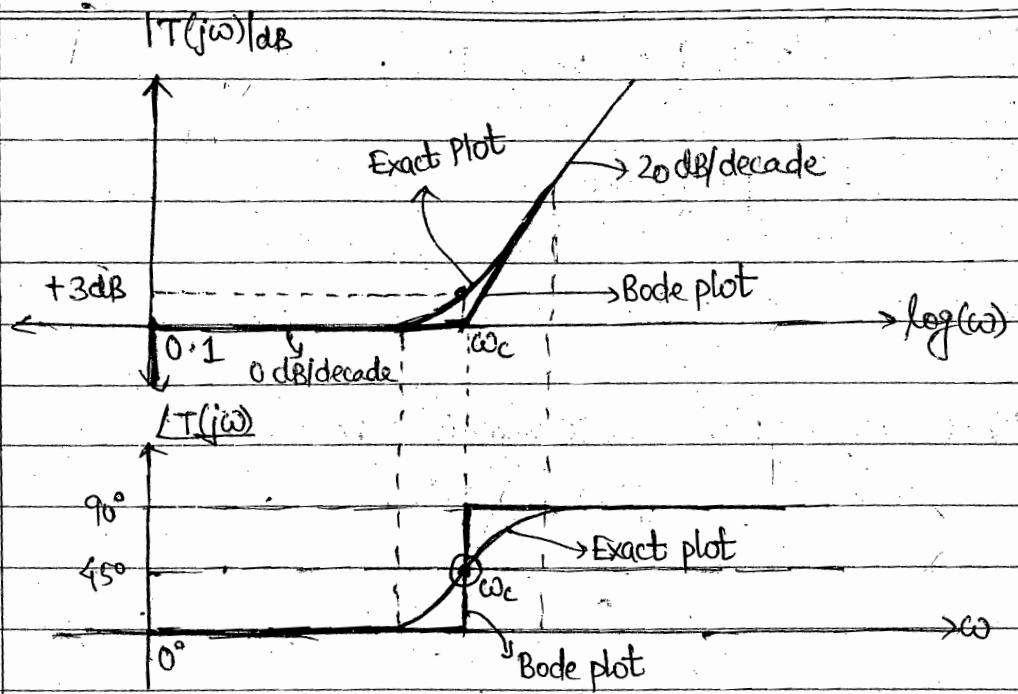
$$\therefore |T(j\omega)|_{\text{dB}} = 20 \log \left(\sqrt{1 + \left(\frac{\omega}{\omega_c} \right)^2} \right); \quad |T(j\omega)| = \tan^{-1} \left(\frac{\omega}{\omega_c} \right).$$

$$(i) \quad \omega \ll \omega_c, \quad |T(j\omega)|_{\text{dB}} = 0 \text{ dB}; \quad |T(j\omega)| = 0^\circ$$

$$(ii) \quad \omega = \omega_c, \quad |T(j\omega)|_{\text{dB}} = +3 \text{ dB}; \quad |T(j\omega)| = 45^\circ$$

$$(iii) \quad \omega \gg \omega_c; \quad |T(j\omega)|_{\text{dB}} = 20 \log(\omega) - 20 \log(\omega_c) \quad * \quad |T(j\omega)| = 90^\circ$$

$$C = -20 \log(\omega_c) *$$



$$12, \quad T(s) = K \left(\frac{s}{\omega_c} + 1 \right).$$

$$\Rightarrow T(j\omega) = K \left(\frac{j\omega}{\omega_c} + 1 \right) \Rightarrow |T(j\omega)| = K \sqrt{1 + (\omega/\omega_c)^2}$$

$$|T(j\omega)|_{dB} = 20 \log(K) + 20 \log(\sqrt{1 + (\omega/\omega_c)^2})$$

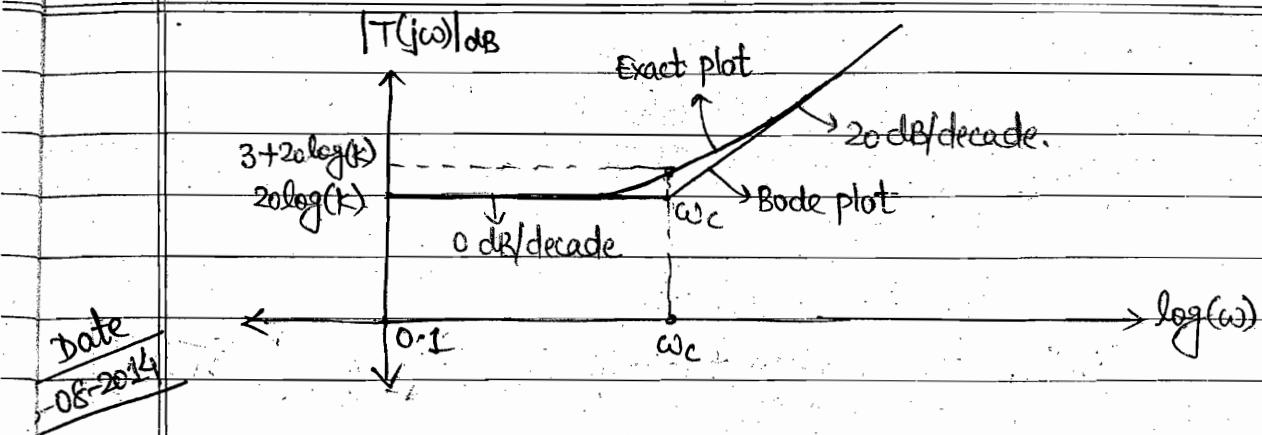
$$(i) \quad \omega \ll \omega_c ; \quad |T(j\omega)|_{dB} = 20 \log(K).$$

$$(ii) \quad \omega = \omega_c ; \quad |T(j\omega)|_{dB} = 3 \text{ dB} + 20 \log(K).$$

$$(iii) \quad \omega \gg \omega_c ; \quad |T(j\omega)|_{dB} = 20 \log(\omega) + 20 \log(K/\omega_c)$$

$$C = 20 \log(K/\omega_c)$$

** Phase Angle plot will remain same.



* Determination of DC Gain from Bode Plot :

$$T(s) = \frac{1}{s^2}$$

$$T(j\omega) = \frac{1}{-\omega^2} \Rightarrow |T(j\omega)| = \frac{1}{\omega^2}$$

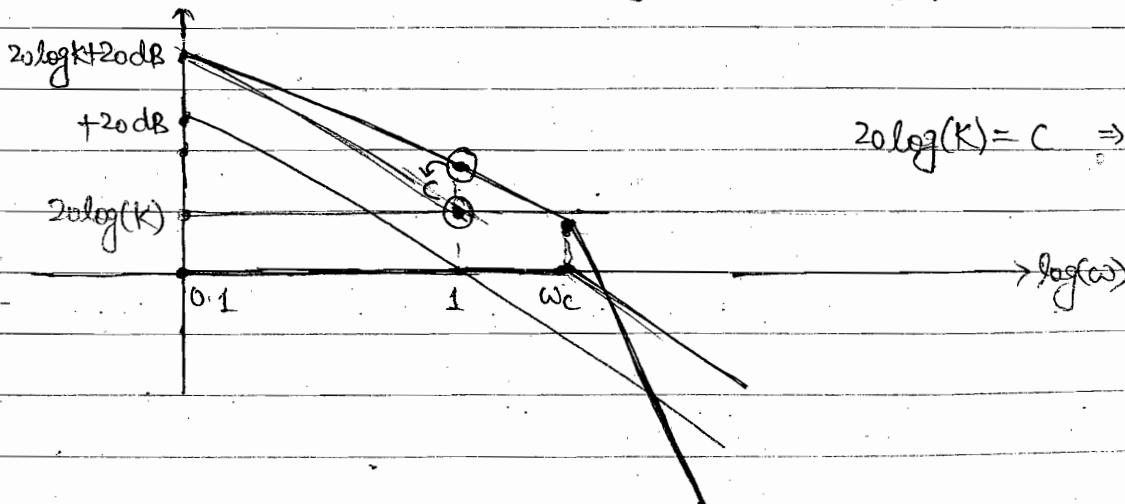
$$\boxed{|T(j\omega)|_{dB} = -20 \log(\omega)} *$$

Case-I When first corner frequency (ω_c) > 1 rad/sec. :

$$T(s) = \frac{k}{s[s/\omega_c + 1]}$$

$$T(j\omega) = \frac{k}{j\omega[j\omega/\omega_c + 1]} \Rightarrow |T(j\omega)| = \frac{k}{\omega \sqrt{1 + (\omega/\omega_c)^2}}$$

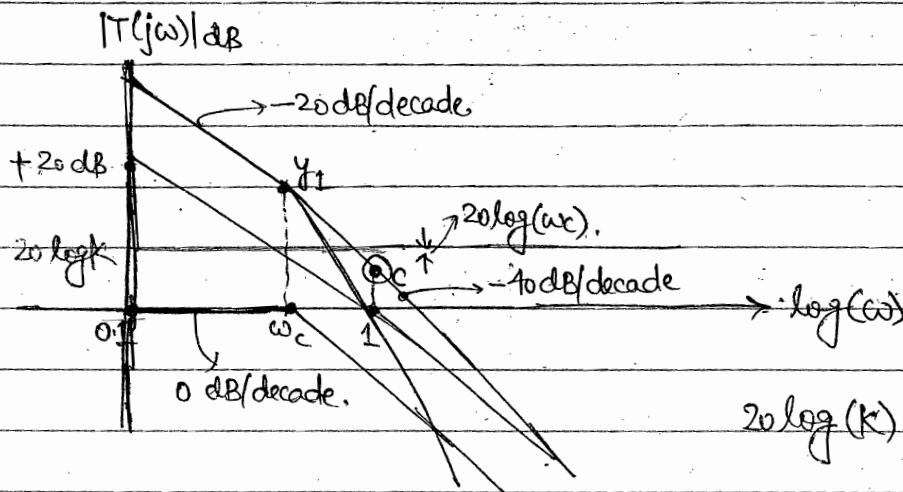
$$|T(j\omega)|_{dB} = 20 \log(k) + (-20 \log(\omega)) + [-20 \log \sqrt{1 + (\omega/\omega_c)^2}]$$



Case I-III: If corner frequency (ω_c) $< 1 \text{ rad/sec}$

$$T(s) = \frac{K}{s[s/\omega_c + 1]}$$

$$|T(j\omega)|_{dB} = 20\log(K) + (-20\log\omega) + [-20\log[\sqrt{1+(\omega/\omega_c)^2}]]$$



$$20\log(K) = e^{-[20\log\omega_c]}$$

$$K = (10)^{\frac{(-20\log\omega_c)}{20}}$$

Using equation of line,

$$\begin{aligned} \frac{20 + 20\log(K) - Y_1}{\log(0.1) - \log(\omega_c)} &= -20 \\ \Rightarrow 20 + 20\log(K) - Y_1 &= -20\log(0.1) + 20\log(\omega_c). \end{aligned}$$

$$\Rightarrow 20 + 20\log(K) - Y_1 = 20 + 20\log(\omega_c)$$

$$\Rightarrow Y_1 = 20\log\left(\frac{K}{\omega_c}\right). \quad (*)$$

$$\text{Again, } C - [20\log(K) - 20\log(\omega_c)] = -40[\log 1 - \log \omega_c]$$

$$\Rightarrow C = 40\log(\omega_c) + 20\log(\omega_c) + 20\log(K)$$

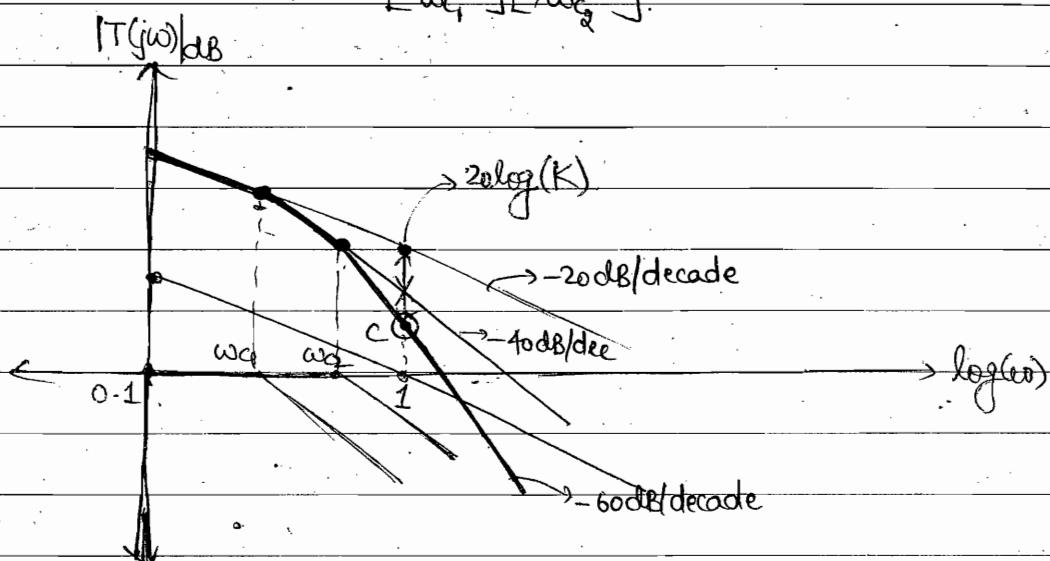
$$\therefore C = 20\log(\omega_c) + 20\log(K).$$

$$\therefore \Delta C = 20\log(K) - c$$

$$\boxed{\Delta C = -20\log(\omega_c)} * \quad (-ve \text{ is because } \omega_c < 1)$$

Case III: When more than one corner frequencies are there.

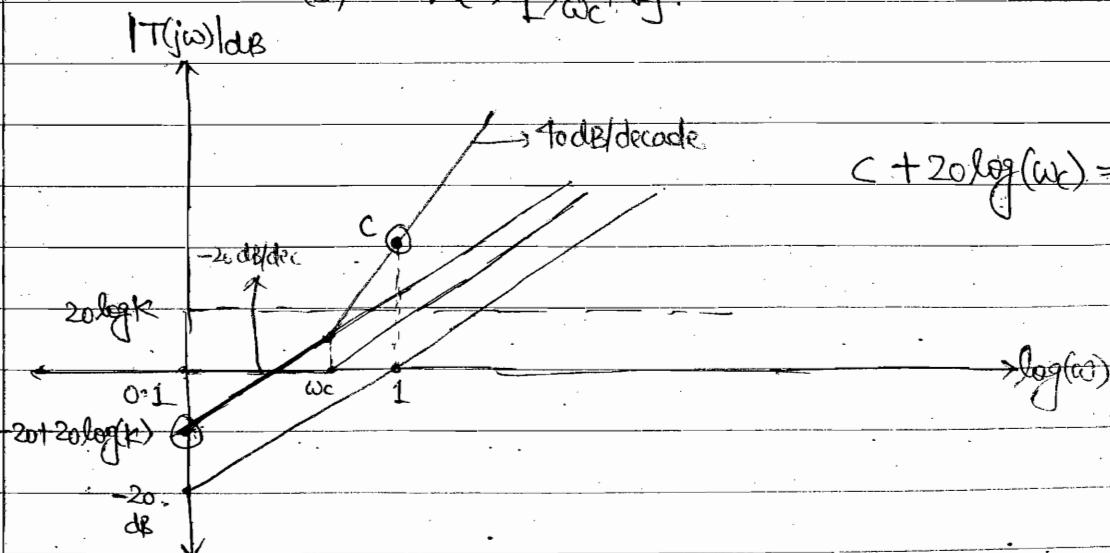
$$T(s) = \frac{K}{s[s_{w_1}+1][s_{w_2}+1]}$$



$$\therefore 20\log(K) = c - [20\log(\omega_1)] - [20\log(\omega_2)]$$

Case IV: When zero is also present in system T .

$$T(s) = K(s) \cdot [s_{w_c} + 1]$$



GAIN MARGIN AND PHASE MARGIN ↴

* Gain Margin ↴

- Gain Margin defines the stability of closed loop transfer function from its Open Loop Plot. In Ratio, Gain Margin is inverse of Magnitude of Open Loop Transfer function at Phase Crossover Frequency.
- Phase crossover frequency is that frequency where phase angle of OLTF becomes -180° .

* g_u , dB, Gain Margin is negative of Magnitude at phase crossover frequency.

* If Open loop system is Minimum phase system, for closed loop system to be stable, Gain Margin should be positive,

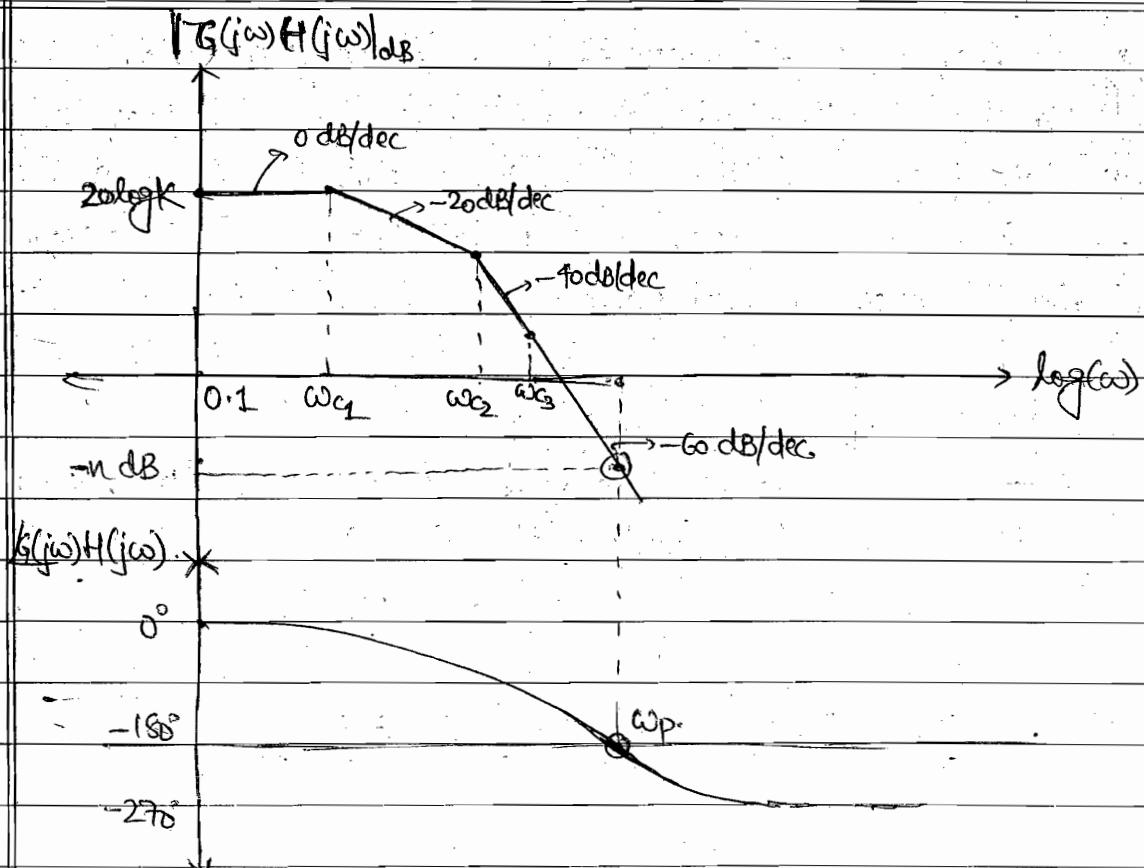
$$G(s)H(s) = \frac{K}{(s/\omega_1 + 1)(s/\omega_2 + 1)(s/\omega_3 + 1)}$$

$$|G(j\omega)H(j\omega)| = 20 \log |G(j\omega)H(j\omega)|.$$

$$= 20 \log(K) - 20 \log \left(\sqrt{1 - (\omega/\omega_1)^2} \right) - 20 \log \left(\sqrt{1 - (\omega/\omega_2)^2} \right) - 20 \log \left(\sqrt{1 - (\omega/\omega_3)^2} \right).$$

$$\underline{|G(j\omega)H(j\omega)|} = -\tan^{-1}(\omega/\omega_1) - \tan^{-1}(\omega/\omega_2) - \tan^{-1}(\omega/\omega_3).$$

* From Bode Plot, Phase Margin cannot be calculated. So, we draw always Exact plot of Phase Angle plot, and this will give range of ω_p where $\omega_p = -180^\circ$
i.e. $\omega_2 < \omega_p < \omega_3$ (In above case).



$$\text{Gain Margin} = \frac{1}{|G(j\omega)H(j\omega)|_{\omega=\omega_p}}$$

$$\boxed{\text{Gain Margin} = -20 \log |G(j\omega_p)H(j\omega_p)| = +n \text{ dB}} *$$

* Now, to shift the Bode plot downwards,

$$\therefore 20 \log(k_1) = \text{Final point} - \text{Initial point}$$

$$20 \log(k_1) = [-n] - [-n] = n - n_1.$$

$$k_1 = (10)^{\frac{(n-n_1)}{20}} \quad [k_1 < 1 \text{ as } (n-n_1) = -\text{ve.}]$$

$$\text{or } \boxed{k \cdot k_1 < 1} *$$

So, $20 \log(k_1)$ will get added to every Magnitude [Note: $k < 1$].

$$\text{So, here } GM = +n_1 \text{ dB.}$$

- Gain Margin is a unique characteristic of particular DC Gain. No two different DC gain will have same Gain Margin.
- * Gain Margin obtained from Bode plot is not exact Gain Margin. It is approximated Gain Margin as Bode Magnitude plot is approximated plot.

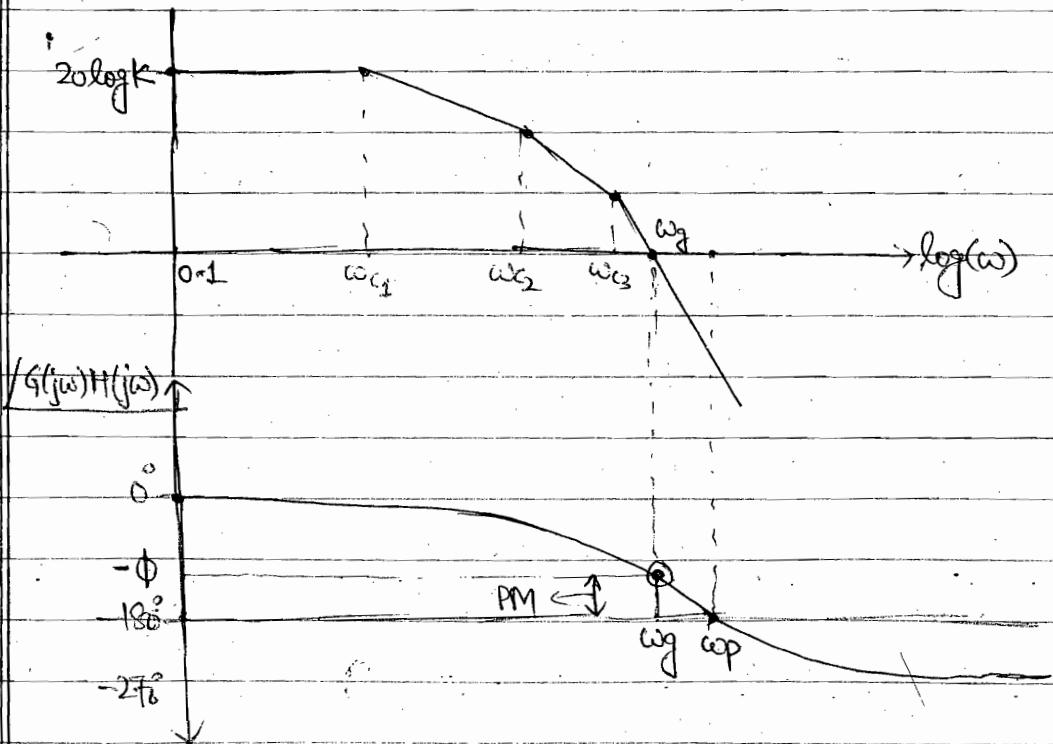
Phase Margin :

Phase Margin defines the stability of closed loop transfer function from its open loop plot and for closed loop system to be stable, Phase Margin should be positive.

$$\text{Phase Margin} = 180^\circ + \left| G(j\omega)H(j\omega) \right|_{\omega=\omega_g}$$

$\omega_g \rightarrow$ Gain crossover frequency.

- Gain Crossover Frequency is a frequency at which Gain of open loop transfer function, in ratio, becomes equal to 1 and in dB, becomes 0 dB.

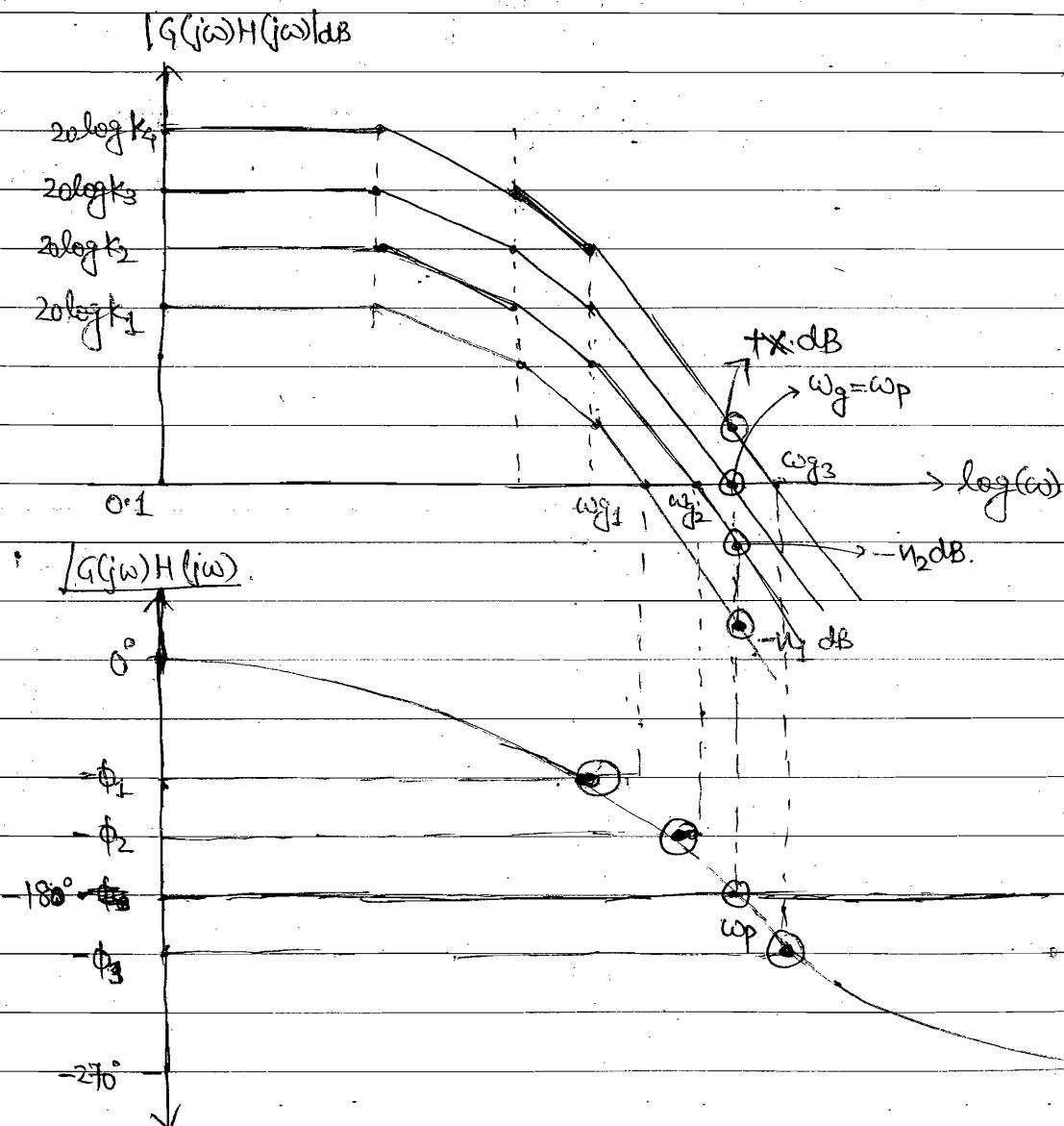


$$|G(j\omega)H(j\omega)| = -\tan(\omega/\omega_1) - \tan(\omega/\omega_2) - \tan(\omega/\omega_3) = -\phi.$$

$$\text{Phase Margin} = 180^\circ + |G(j\omega)H(j\omega)| \Big|_{\omega=\omega_g}.$$

$$\therefore \text{Phase Margin} = 180^\circ - \phi.$$

- * ω_g can be changed by increasing or decreasing DC gain.
- * As K decreases, PM and GM increases and vice-versa.
- * Gain Margin follows Phase Margin and vice-versa.



$$T(s) = \frac{G(s)}{1+G(s)H(s)} = \frac{K}{(s/\omega_1 + 1)(s/\omega_2 + 1)(s/\omega_3 + 1) + K}$$

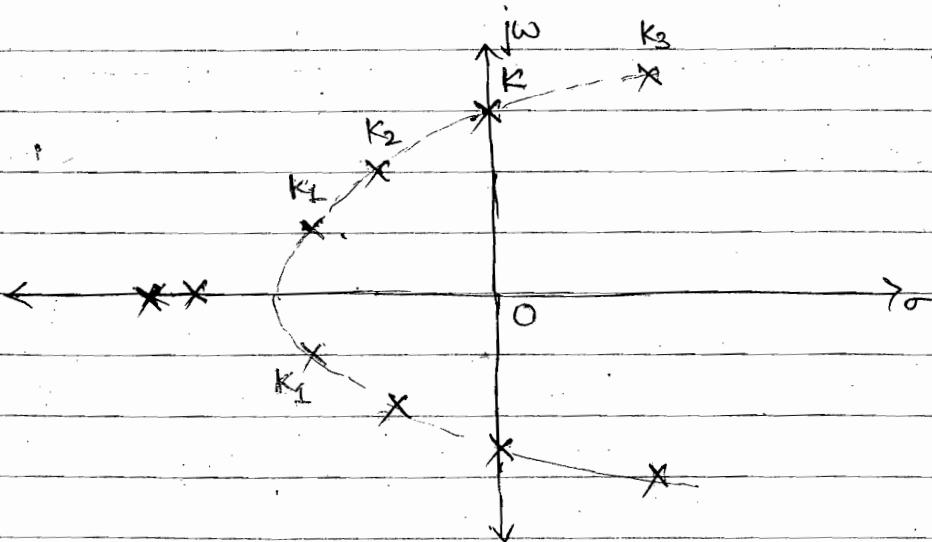
$$\Rightarrow 1+G(s)H(s) = (s/\omega_1 + 1)(s/\omega_2 + 1)(s/\omega_3 + 1) + K = 0$$

$$\therefore GM = -|G(j\omega_p)H(j\omega_p)|$$

$$PM = 180^\circ + |G(j\omega_p)H(j\omega_p)|.$$

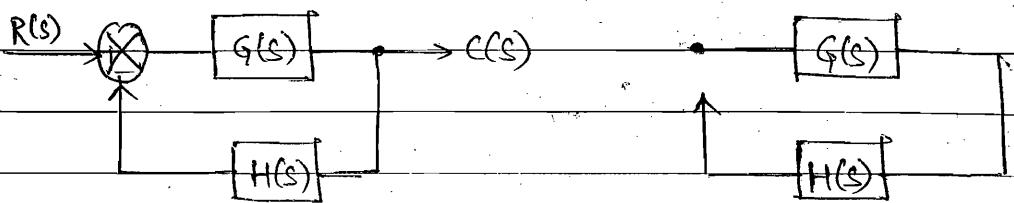
| DC Gain | Crossover frequency | GM | PM | stability |
|---------|---------------------------|-------------------|-----|---------------------|
| K_1 | $\omega_p > \omega_{g_1}$ | $+n_1 \text{ dB}$ | +ve | stable. (More). |
| K_2 | $\omega_p > \omega_{g_2}$ | $+n_2 \text{ dB}$ | +ve | stable |
| K | $\omega_p = \omega_g$ | 0 dB | 0° | M marginally stable |
| K_3 | $\omega_p < \omega_g$ | $-n_3 \text{ dB}$ | -ve | unstable. |

$$K_3 > K > K_2 > K_1.$$



* Determination of Error-coefficients from Bode Plot :

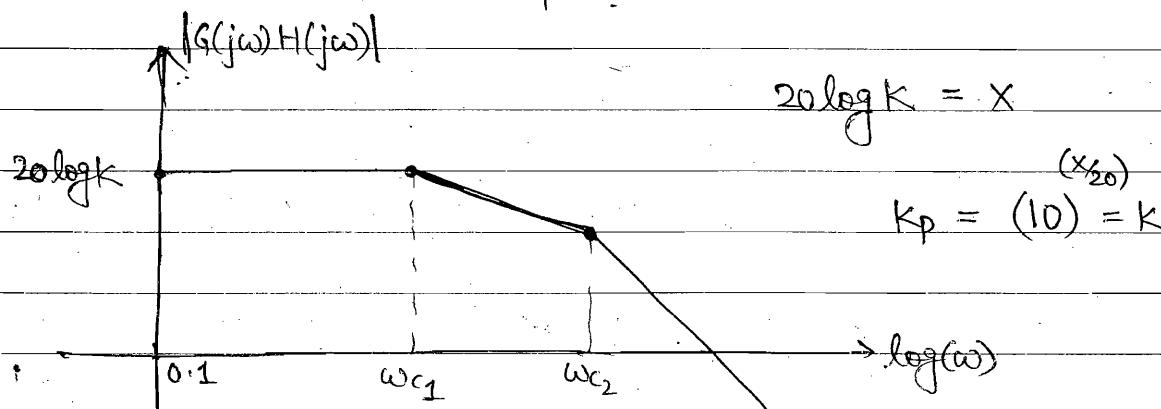
1. Positional Error-coefficient :



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

$$OLTF = G(s)H(s)$$

Let $G(s)H(s) = K$
 $(s/\omega_1 + 1)(s/\omega_2 + 1)$.



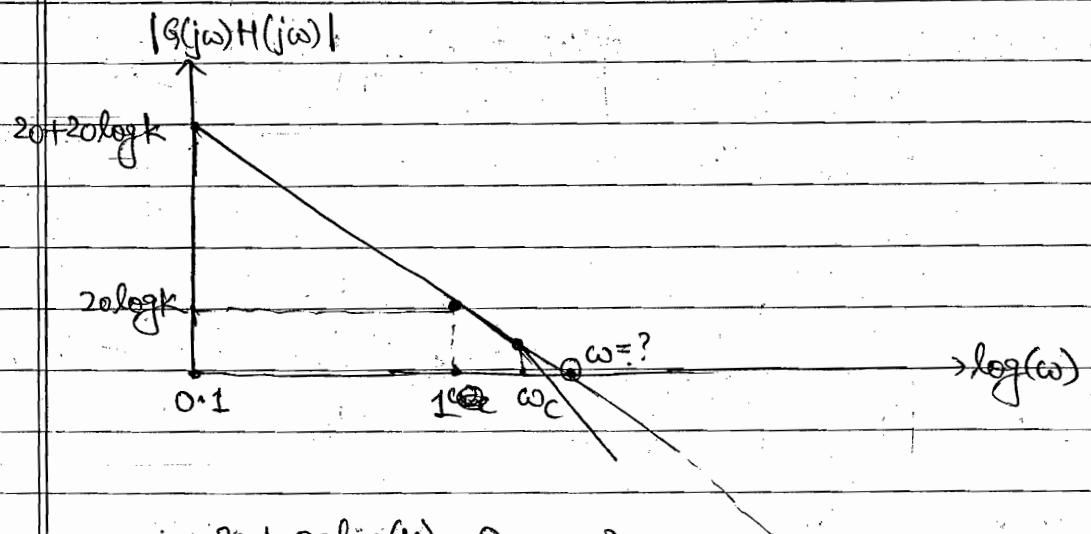
Now, $K_p = \lim_{s \rightarrow 0} \frac{K}{(s/\omega_1 + 1)(s/\omega_2 + 1)} = k$

$$\therefore e_{sc} = \frac{1}{1 + K_p}$$

$$e_{sc} = \frac{1}{1 + (10)^{x_20}} *$$

2. Velocity Error-coefficient :

$$G(s)H(s) = \frac{1}{s(s/\omega_c + 1)}$$



$$20 + 20 \log(k) - 0 = -20$$

$$\log(0.1) - \log(\omega)$$

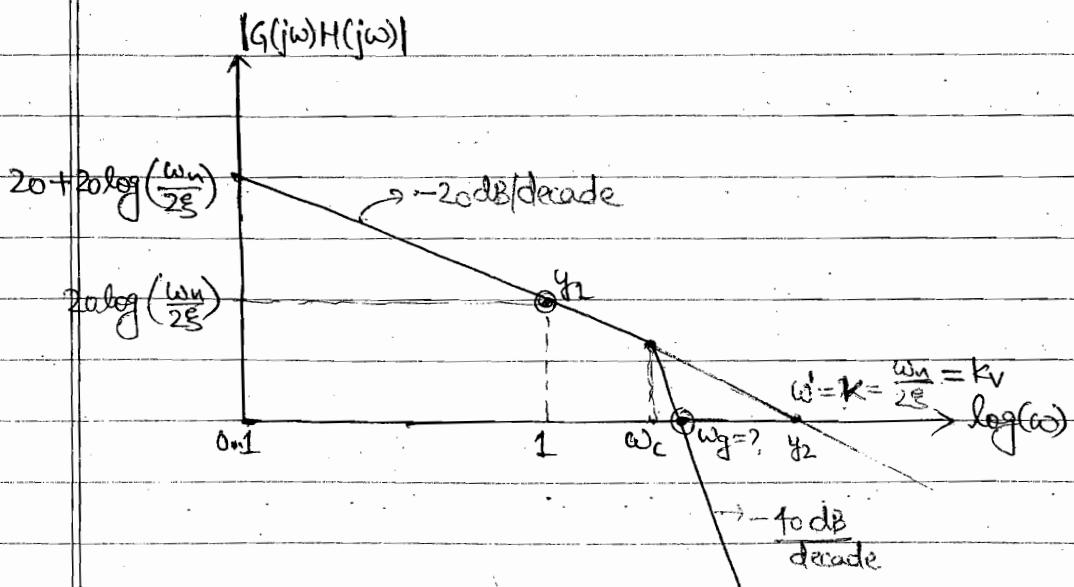
$$\Rightarrow 20 + 20 \log k = 20 + 20 \log(\omega).$$

$$\Rightarrow \boxed{\omega = K} *$$

** Now, let $G(s) \cdot H(s) = \frac{\omega_n^2}{s(s+2\zeta\omega_n)}$

* writing it in standard form, $G(s)H(s) = \frac{(\omega_n/2\zeta)}{s[s/2\zeta\omega_n + 1]}$

$$\text{Comparing } K = \frac{\omega_n}{2\zeta}$$



To find ω_g ; $0 - y_1 = -20$. $[\omega_c = 2\xi \omega_n \text{ here}]$

$$\log\left(\frac{\omega_n}{2\xi}\right) - \log(2\xi \omega_n)$$

$$\Rightarrow y_1 = 20 \cdot \log\left(\frac{1}{2\xi}\right)^2 \Rightarrow y_1 = -40 \log(2\xi) *$$

Again, $0 - (-40 \log(2\xi)) = -40$.

$$\log(\omega_g) - \log(2\xi \omega_n)$$

$$\Rightarrow 40 \log(2\xi) = -40 \log(\omega_g) + 40 \log(2\xi \omega_n)$$

$$\Rightarrow 40 \log\left(\frac{2\xi}{2\xi \omega_n}\right) = -40 \log(\omega_g)$$

$$\Rightarrow \text{or } \log\left(\frac{\omega_n}{\omega_g}\right) = \log(\omega_g)$$

$$\Rightarrow \omega_g = \omega_n *$$

Now, we have frequencies as: $\omega_c = 2\xi \omega_n$, $[\omega_g = \omega_n]$, $\omega' = \left(\frac{2\xi}{\omega_n}\right)^{-1}$

$$\xi = \frac{1}{2} \frac{\omega_c}{\omega_g} *$$

* By only finding ξ and ω_n , we can find all parameters like t_s , t_p , $\% M_p$, t_r as they depend only on ξ and ω_n .

* For e_{ss} :- $k_v = \lim_{s \rightarrow 0} s \times \frac{(s/\omega_n)/2\xi}{s(s/\omega_n + 1)} \Rightarrow k_v = \frac{\omega_n}{2\xi} = \omega'$

$$e_{ss} = \frac{2\xi A}{\omega_n} *$$

$$[\omega_c \omega' = \omega_n^2 = \omega_g^2] * \Rightarrow \omega_g = \sqrt{\omega_c \omega'} *$$

* Note * ω_g is Geometric Mean of ω_c and ω' .

* Now, by taking log both sides,

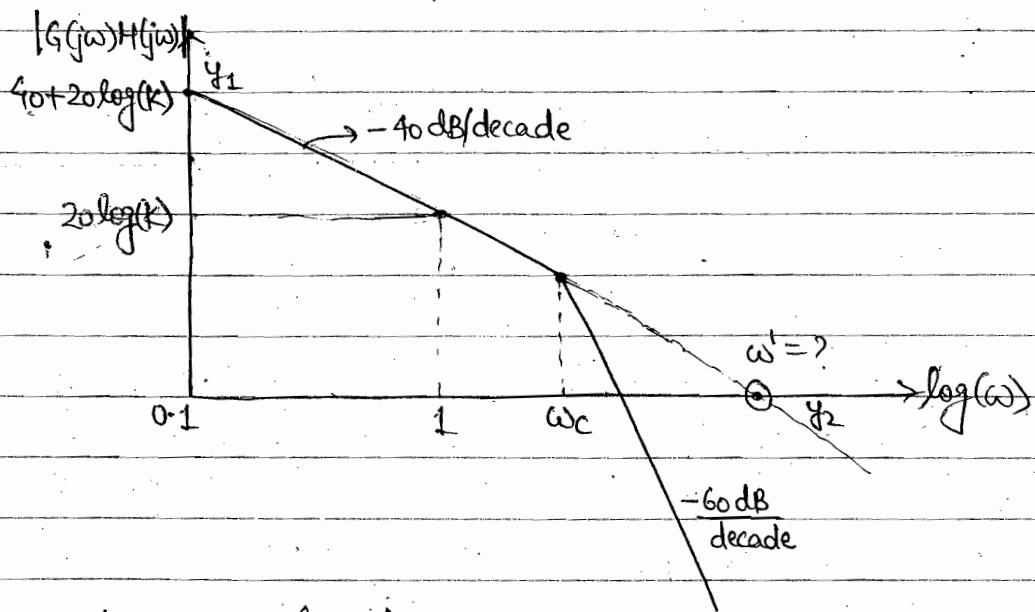
$$2 \log(\omega_g) = \log(\omega) + \log(\omega')$$

$$\Rightarrow \boxed{\log(\omega_g) = \frac{\log(\omega) + \log(\omega')}{2}} *$$

* Note: ∵ $\log(\omega_g)$ is Arithmetic Mean of $\log(\omega)$ and $\log(\omega')$.

3. Acceleration-Error Co-efficient :

$$G(s)H(s) = K ; |G(j\omega)H(j\omega)| = 20 \log(K) - 40 \log(\omega) - 20 \log(\sqrt{1 + (\omega/\omega_c)^2})$$



Using Slope formula,

$$0 - [40 + 20 \log(K)] = -40 \\ \log(\omega) - \log(0.1)$$

$$\Rightarrow -40 - 20 \log K = -40 \log(\omega') - 40$$

$$\boxed{\omega' = \sqrt{K}} *$$
— ①

$$* \text{ For } e_{ss} : - k_a = \lim_{s \rightarrow 0} s^2 \cdot \frac{k}{s^2[s/\omega_c + 1]} = k = \omega^2 \quad [\text{Using eq-07}]$$

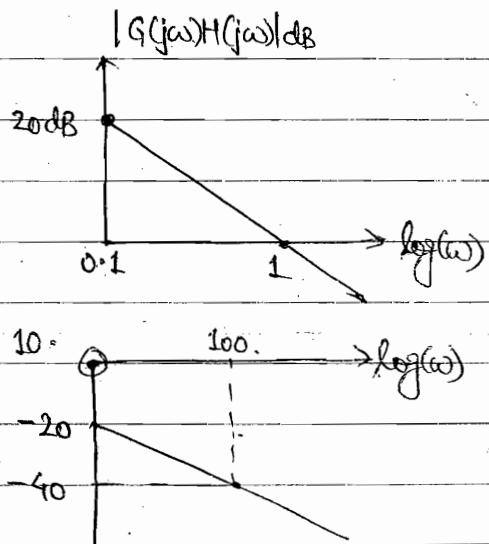
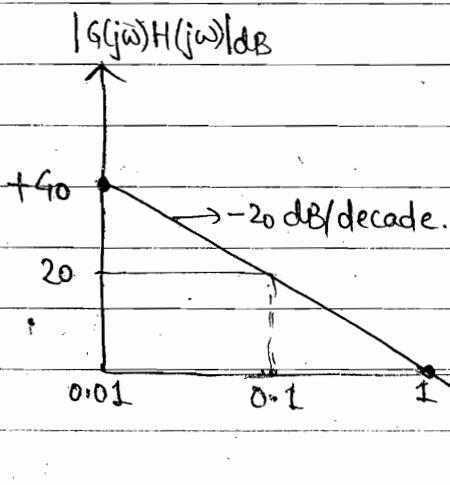
$$e_{ss} = -\frac{A}{k_a}$$

$$e_{ss} = \frac{A}{\omega^2}$$

- For $G(s)H(s) = KS(s/\omega_c + 1)$, $\omega^2 = \frac{1}{K}$.

- For $G(s)H(s) = KS^2(s/\omega_c + 1)$, $\omega^2 = \frac{1}{K}$.

\rightarrow Bode Plot of $\frac{1}{S}$:



* On clipping, the frequencies that will get clipped must not contain corner frequency.

Case - I \rightarrow Initial slope and first corner frequency $> 1 \text{ rad/sec}$

- If initially slope is there of $+20 \text{ dB/dec}$, then at origin, Pole is present.

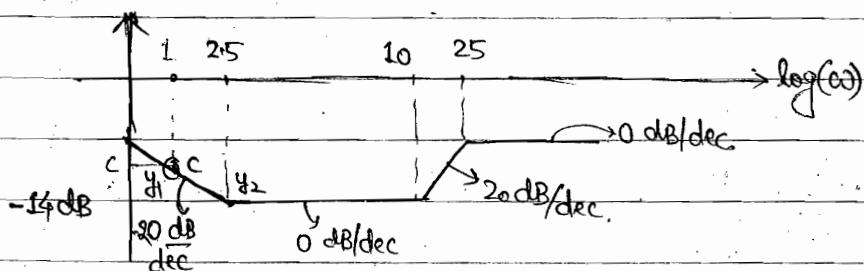
- If line is having initial slope, that means Origin contains zero, for $+20 \text{ dB/decade}$ slope.

* Now, we will search for ω_c at which slope is changing. If change in slope i.e. Final slope - Initial slope is -20 dB/decade , then that corner frequency is due to Pole and it will come into the denominator of TF. ; $\text{TF} = \frac{K}{(s/\omega_c + 1)}$

* If Final slope - Initial slope = 20 dB/decade , then that ω_c is due to zero, then it will come in Numerator of Transfer function
 $\text{TF} = (s/\omega_c + 1)$

* To calculate DC gain, we will calculate Magnitude at $\omega=1$ and then, we'll equate that Magnitude with $20 \log(K)$.

Ques:- ①



Find Transfer Function.

Ans:- ①

Using Slope formula, $\frac{C - (-14)}{\log(1) - \log(2.5)} = -20$.

$$\Rightarrow C + 14 = 20 \log(2.5) \Rightarrow C = -6.04 \quad *$$

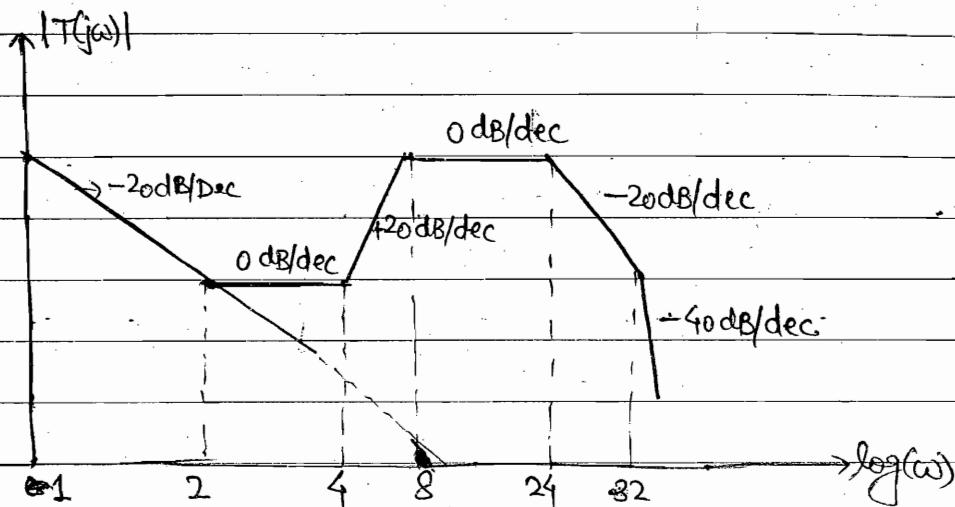
Now, $20 \log K = C \Rightarrow K = 0.5 \quad *$

$$\therefore T.F = \frac{0.5 \left(\frac{s}{2.5} + 1 \right) \left(\frac{s}{10} + 1 \right)}{s \left(\frac{s}{25} + 1 \right)}$$

Here, $0.5 = \text{DC Gain}$.

$$\Rightarrow T.F =$$

Ques-② For the given bode plot, calculate its transfer function.



Ans-② Here, DC Gain = 8 = K.

$$\text{Now, } T.F = \frac{8 \left(\frac{s}{2} + 1 \right) \left(\frac{s}{8} + 1 \right)}{s \left(\frac{s}{8} + 1 \right) \left(\frac{s}{24} + 1 \right) \left(\frac{s}{32} + 1 \right)}$$

$$T.F = \frac{\frac{8(s+2)(s+4)}{2 \cdot 4}}{\frac{s(s+8)(s+24)(s+32)}{8 \cdot 24}} = \frac{6144 \cdot (s+2)(s+4)}{s(s+8)(s+24)(s+32)}$$

Case II: origin contains pole and first corner frequency < 1 rad/sec

- For DC gain, we will magnitude at $\omega=1$ and then we will use:

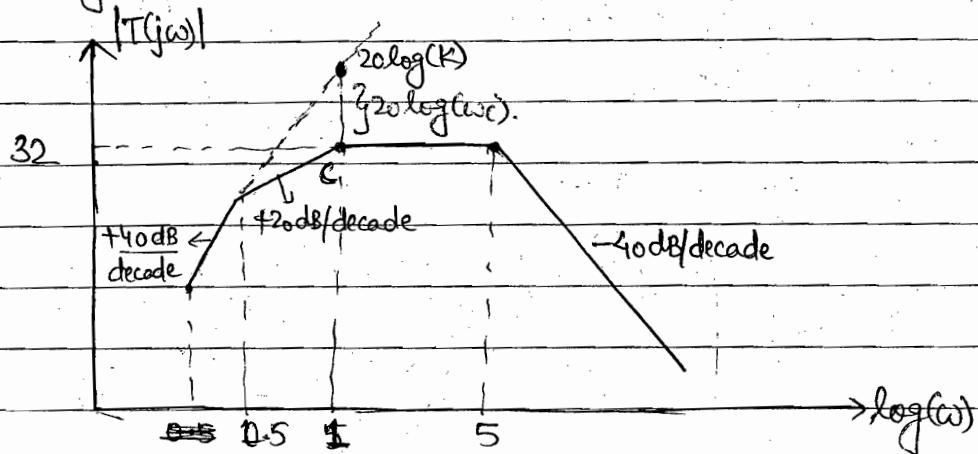
$$20\log(K) = C + 20\log(\omega_c)$$

where $C = \text{Magnitude at } \omega=1$.

$\omega_c = \text{corner frequency less than } 1 \text{ rad/sec}$

$K = \text{DC gain of the system}$.

Ques:- (3) For the given Bode plot, obtain its transfer function.



$$\text{Ans: } (3) \quad 20\log K = C - [20\log(\omega_c)]$$

$$20\log(K) = C - [20\log(0.5)] = C - [-6.02]$$

$$\Rightarrow 20\log(K) = 32 + 6.02 = 38.02$$

$$K = (10)^{\frac{38.02}{20}} \Rightarrow K \approx 80$$

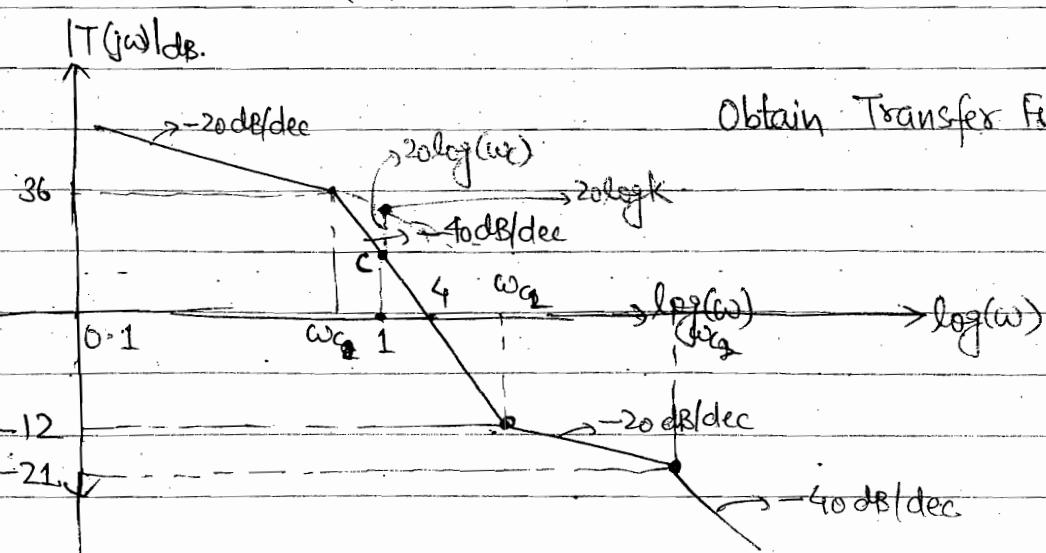
$$TF = \frac{80s^2}{(s+0.5)(s+1)(s+5)^2}$$

$$\therefore TF = \frac{80s^2 \times 25}{(2s+1)(s+1)(s^2+10s+25)}$$

$$TF = \frac{2000s^2}{(2s+1)(s+1)(s^2+10s+25)}$$

Ans

Ques:- (4)



Ans:- (4) Using slope formula, $\frac{36-0}{\log(w_c) - \log(4)} = -40$

$$\Rightarrow w_c = 0.5 \text{ rad/sec.} \quad [\text{Case II applicable}]$$

$$\frac{c-0}{\log(1) - \log(4)} = -40 \Rightarrow c = 24.08$$

$$20\log(K) = 24.08 \Rightarrow 20\log(K) = 24.08 - 20\log(0.5)$$

$$\Rightarrow 20\log(K) = 24.08 - (-6.02)$$

$$\Rightarrow 20\log(K) = 30.1 \Rightarrow K = 10^{30.1/20}$$

$$K = 32 *$$

$$\text{T.F.} = \frac{32 \left(\frac{s}{w_1} + 1 \right)}{s \left(\frac{s}{0.5} + 1 \right) \left(\frac{s}{w_2} + 1 \right)}$$

∴ For w_{c_1} ; $\frac{0 - (-12)}{\log(4) - \log(w_{c_1})} = -40$

$$\Rightarrow 12 = -40 [\log(4) - \log(w_{c_1})]$$

$$\Rightarrow w_{c_1} \approx 8 \text{ rad/sec.} *$$

∴ For w_{c_2} ; $\frac{-12 - (-21)}{\log(8) - \log(w_{c_2})} = -20$

$$\log(8) - \log(w_{c_2})$$

$$w_{c_2} \approx 22.5 \text{ rad/sec.} *$$

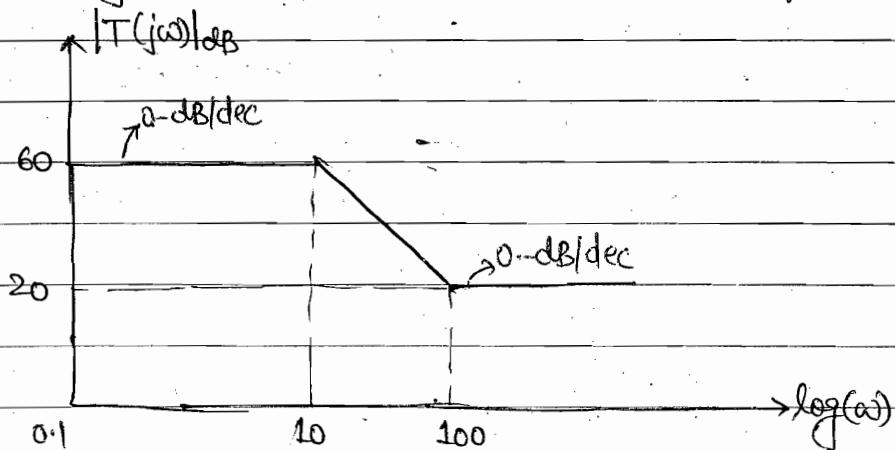
$$\text{T.F.} = \frac{32 \left(\frac{s}{8} + 1 \right)}{s \left(\frac{s}{0.5} + 1 \right) \left(\frac{s}{22.5} + 1 \right)}$$

Ans

Case-III Initial line parallel to 0-dB axis

- In this case, Origin will contain any pole or zero. In this case, we will calculate initial height of the line and then we will equate that height with $20\log(K)$. Rest of other calculations will remain same as it is in previous case.

Ques:- (5) For the given bode plot, obtain its transfer function.



Ans:- (5) $20\log K = 60$

$$\Rightarrow [K = 1000] *$$

$$\frac{60-20}{\log(10)-\log(100)} = \text{Slope}$$

$$\therefore \text{Slope} = \frac{40}{1-2}$$

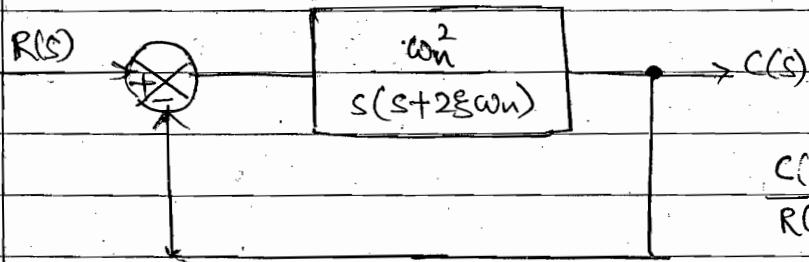
$$\Rightarrow [\text{Slope} = -40 \text{ dB/decade}] *$$

$$\therefore T.F. = \frac{1000 \cdot \left(\frac{s}{100} + 1\right)^2}{\left(\frac{s}{10} + 1\right)^2} = \frac{1000 \times \frac{1}{1000} (s^2 + 200s + 10^4)}{\frac{1}{100} (s+10)^2}$$

$$\therefore [T.F. = \frac{10^{+1} (s+100)^2}{(s+10)^2}] *$$

Ans

* Bode Plot for closed Loop second order Under-damped system:



$$C(s) = \frac{\omega_n^2}{R(s)} \cdot \frac{1}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

$$\text{Now, } T(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

$$\text{or } T(s) = \frac{1}{(s/\omega_n)^2 + 2\xi(s/\omega_n) + 1} \quad [\text{In standard form}]$$

$$\text{or } T(j\omega) = \frac{1}{[1 - (\omega/\omega_n)^2] + [2\xi(\omega/\omega_n)]}$$

$$\therefore |T(j\omega)|_{dB} = -20 \log \left[\sqrt{(1 - \omega^2/\omega_n^2)^2 + (4\xi^2 \omega^2/\omega_n^2)} \right]$$

$$\text{and } |T(j\omega)|_{dB} = -20 \log \left[\frac{2\xi(\omega/\omega_n)}{1 - (\omega/\omega_n)^2} \right]$$

$$(i) \omega \ll \omega_n : |T(j\omega)|_{dB} = -20 \log \sqrt{1}$$

$$|T(j\omega)|_{dB} = 0 \text{ dB} * ; \quad |T(j\omega)| = 0^\circ * \quad \boxed{|T(j\omega)|_{dB} = 0 \text{ dB}} * ; \quad \boxed{|T(j\omega)| = 0^\circ} *$$

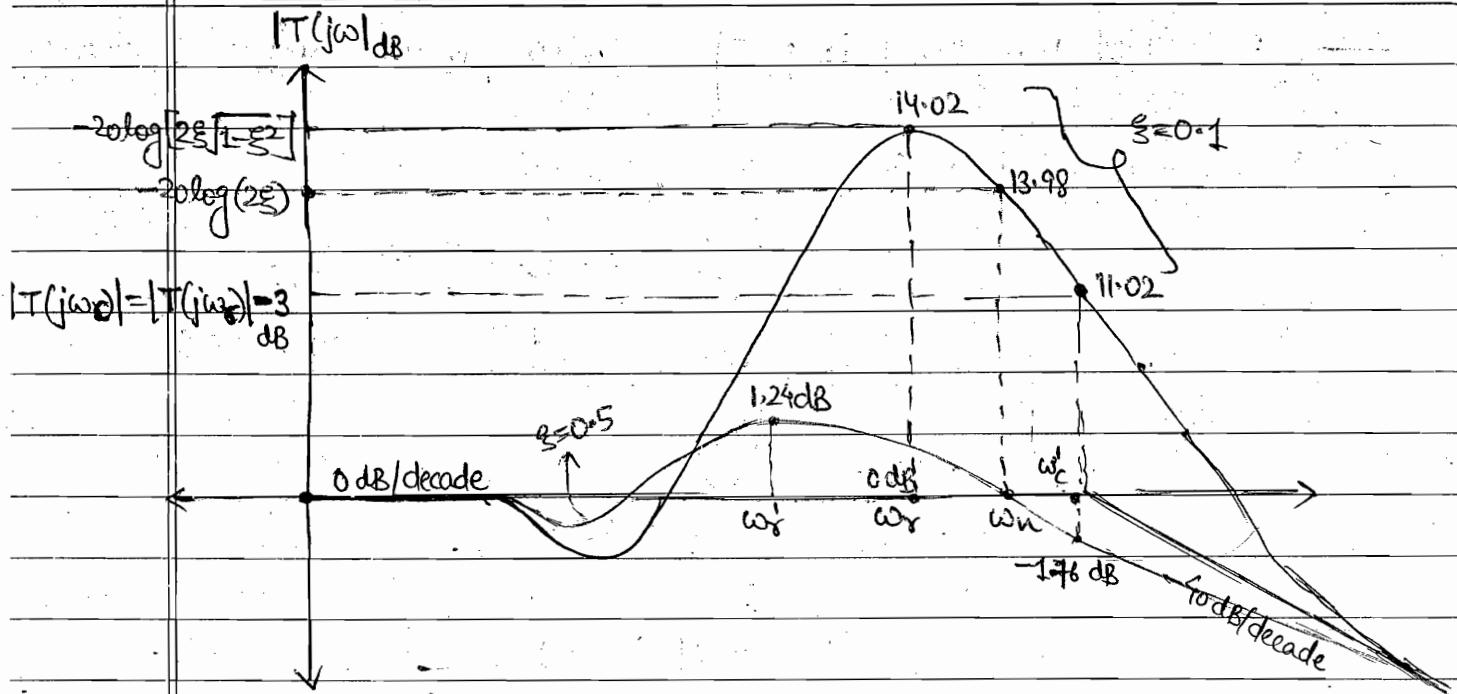
$$(ii) \omega = \omega_n : |T(j\omega)|_{dB} = -20 \log (2\xi)$$

$$\therefore |T(j\omega)|_{dB} = -20 \log (2\xi) * ; \quad |T(j\omega)| = -90^\circ * \quad \boxed{|T(j\omega)|_{dB} = -20 \log (2\xi)} * ; \quad \boxed{|T(j\omega)| = -90^\circ} *$$

$$(iii) \omega \gg \omega_n : |T(j\omega)|_{dB} = -20 \log \left(\frac{\omega^4}{\omega_n^4} \right)$$

$$\therefore |T(j\omega)|_{dB} = -40 \log(\omega) + 40 \log(\omega_n) * ; \quad |T(j\omega)| = -180^\circ * \quad \boxed{|T(j\omega)|_{dB} = -40 \log(\omega) + 40 \log(\omega_n)} * ; \quad \boxed{|T(j\omega)| = -180^\circ} *$$

where, $C = 40 \log(\omega_n)$.



(i) Resonant Frequency (ω_r) :

- It is defined as frequency at which slope of Magnitude Response is 0 and Magnitude is maximum.
- * To calculate Resonant Frequency, we will differentiate Magnitude Response with respect to ω , and putting $\frac{d|T(j\omega)|}{d\omega} = 0$

We will get,
$$\omega_r = \omega_n \sqrt{1-\xi^2} \quad *$$

Putting ω_r value in Transfer function $T(j\omega)$,

$$\therefore |T(j\omega)| = \frac{1}{2\xi \sqrt{1-\xi^2}}$$

or
$$|T(j\omega_r)|_{dB} = -20 \log [2\xi \sqrt{1-\xi^2}] \quad *$$

$$|T(j\omega_r)| = -90 - \sin^{-1}\left(\frac{\xi}{\sqrt{1-\xi^2}}\right) \quad *$$

(ii) Natural frequency (ω_n) :

$$|T(j\omega_n)| = \frac{1}{2\xi}$$

$$|T(j\omega_n)|_{dB} = -20 \log(2\xi) *$$

$$|T(j\omega_n)| = -90 *$$

$$\omega_c = \text{Bandwidth} = \omega_n \sqrt{1-2\xi^2 + \sqrt{4\xi^4 - 4\xi^2 + 2}}$$

$$|T(j\omega_c)| = \frac{1}{\sqrt{2}} |T(j\omega_n)|$$

$$\Rightarrow |T(j\omega_c)| = \frac{1}{\sqrt{2}} \left[\frac{1}{2\xi \sqrt{1-\xi^2}} \right] *$$

$$|T(j\omega_c)|_{dB} = |T(j\omega_n)|_{dB} - 3 \text{ dB} = [-20 \log(2\xi \sqrt{1-\xi^2})] - 3 \text{ dB} *$$

* For $\xi = 0.1$,

$$\omega_r = \omega_n \sqrt{1-2\xi^2} = \sqrt{0.98} \omega_n$$

$$|T(j\omega_r)| = -20 \log [2 \times 0.1 \times \sqrt{1-(0.1)^2}] = 14.02 \text{ dB.}$$

$$|T(j\omega_n)| = -20 \log (2 \times 0.1) = 13.98.$$

$$\omega_c = \omega_n \sqrt{(1-2(0.1)^2) + \sqrt{4(0.1)^4 - 4(0.1)^2 + 2}} = 1.57 \omega_n.$$

$$|T(j\omega_c)| = |T(j\omega_r)|_{dB} - 3 \text{ dB} = 11.02 \text{ dB.}$$

* For $\xi = 0.5$,

$$\omega_r = \omega_n \sqrt{1-2(0.5)^2} = \sqrt{0.5} \omega_n.$$

$$|T(j\omega_r)| = -20 \log [2 \times 0.5 \sqrt{1-(0.5)^2}] = 1.24 \text{ dB.}$$

$$|T(j\omega_n)| = -20 \log (2 \times 1) = 0 \text{ dB.}$$

$$\omega_c = \omega_n \sqrt{(1-2(0.5)^2) + \sqrt{4(0.5)^4 - 4(0.5)^2 + 2}} = 1.27\omega_n.$$

$$|T(j\omega_c)| = |T(j\omega_r)|_{dB} - 3 dB = 1.24 - 3 dB = -1.76 dB.$$

Note:- * We can observe that, when ξ is increased, ω_r and ω_c decreases. Sharpness of response reduces when ξ is increased.

* For what ξ , $|T(j\omega_r)| = 1$, or 0 in dB,

$$\frac{1}{2\xi\sqrt{1-\xi^2}} = 1 \Rightarrow 4\xi^2(1-\xi^2) = 1 \Rightarrow 4\xi^2 - 4\xi^4 = 1.$$

$$\text{or } 4\xi^4 - 4\xi^2 + 1 = 0 \Rightarrow (2\xi^2 - 1)^2 = 0.$$

$$\boxed{\xi = \frac{1}{\sqrt{2}} = 0.707 = -3 dB} *$$

* For $\xi = \frac{1}{\sqrt{2}} = 0.707$,

$$\omega_r = \omega_n \sqrt{1-2 \times \frac{1}{2}} = 0.$$

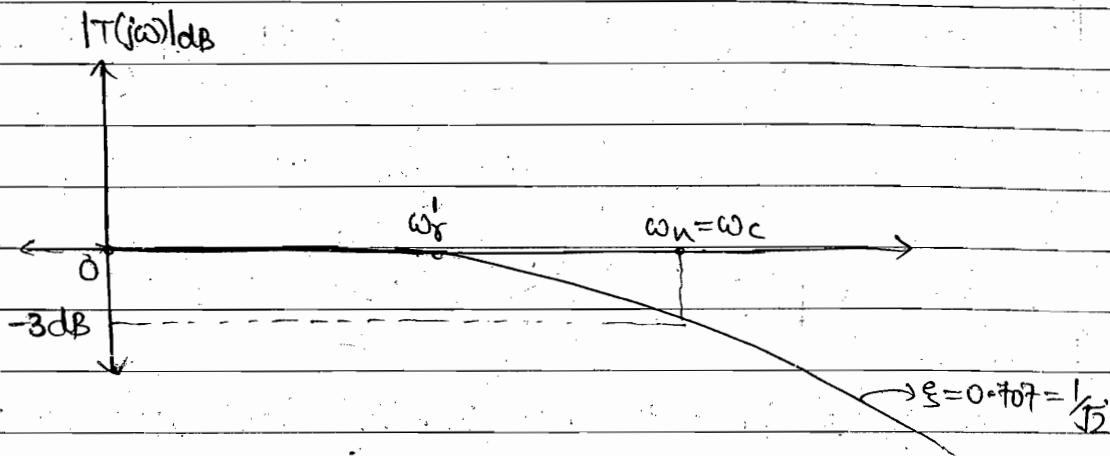
$$|T(j\omega_r)|_{dB} = -20 \log \left[2 \times \frac{1}{\sqrt{2}} \sqrt{1-\frac{1}{2}} \right] = 1 = 0 dB.$$

$$|T(j\omega_n)|_{dB} = -20 \log \left(2 \times \frac{1}{\sqrt{2}} \right) = -3 dB.$$

$$\omega_c = \omega_n \sqrt{(1-2 \times \frac{1}{2}) + \sqrt{4\xi^4 - 4\xi^2 + 2}} = \omega_n.$$

$$|T(j\omega_c)|_{dB} = |T(j\omega_r)|_{dB} - 3 dB = -3 dB.$$

* For $\xi = \frac{1}{\sqrt{2}}$, graph will be :-



* For $\xi = 0$:-

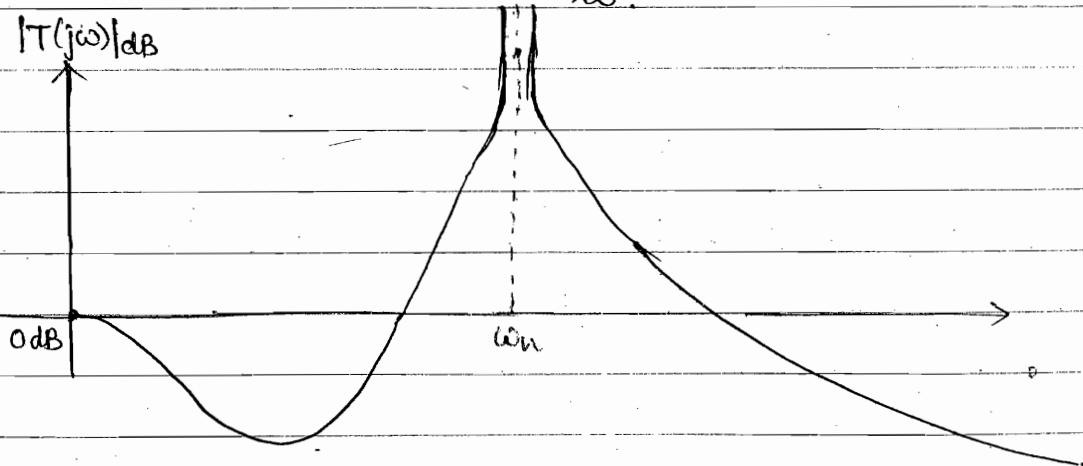
$$\boxed{\omega_r = \omega_n} * \quad \boxed{|T(j\omega_r)| = \infty} *$$

$$|T(j\omega_n)|_{dB} = \infty.$$

$$\omega_c = \omega_n \sqrt{1 + \sqrt{2}}.$$

$$|T(j\omega_c)|_{dB} = |T(j\omega)|_{dB} - 3dB = \infty.$$

$\rightarrow \infty$.



- That means, in time-domain, if for $\xi = 0$, where Response oscillates, (that frequency), in Frequency-Response, on that frequency, Magnitude will become ∞ .

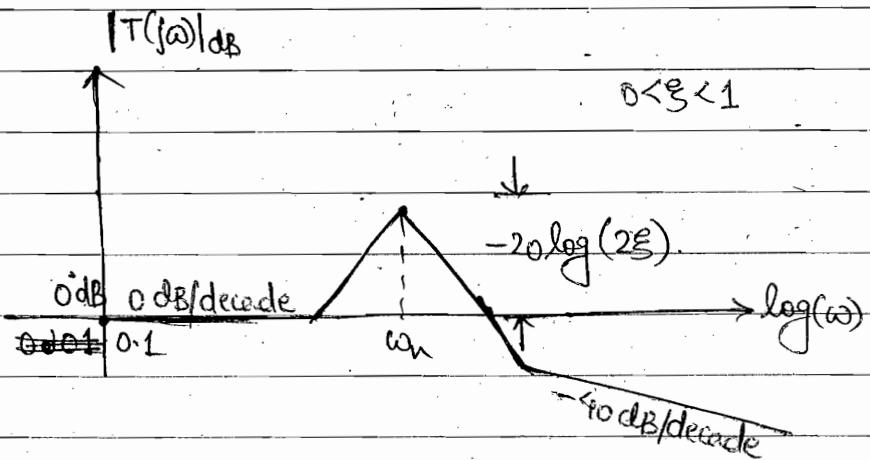
- For $\xi > \frac{1}{\sqrt{2}}$, ω_r becomes Imaginary which is not possible.

So, $0 < \xi < \frac{1}{\sqrt{2}}$ * [In Frequency-Response].

$$\omega_n > \omega_r > 0 *$$

$$\omega_n \sqrt{1+2\xi^2} > \omega_c > \omega_n *$$

Note: • When system tends towards stability, the Sharpness of Bode Magnitude plot will decrease and its bandwidth will also decrease.



Note: • In Bode Plot, as we do not consider frequency ω_r , so there is no restriction on ξ .

$\therefore 0 < \xi < 1$ * For Bode Plot only.

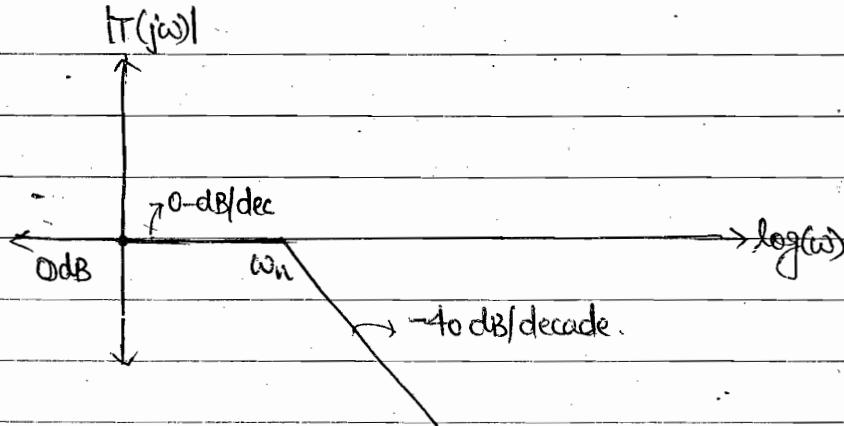
Note: • For $\xi = 0$, Bode Plot is not possible as slope is not constant anywhere.

* Bode Plot for critically Damped system:

$$T(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

- For critically-damped system, $\xi = 1$,

$$\therefore T(s) = \frac{\omega_n^2}{(s+\omega_n)^2} \Rightarrow T(s) = \frac{1}{(\zeta\omega_n + 1)^2}$$



* Bode Plot for over-damped system:

$$T(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

- For over-damped system, $\xi > 1$.

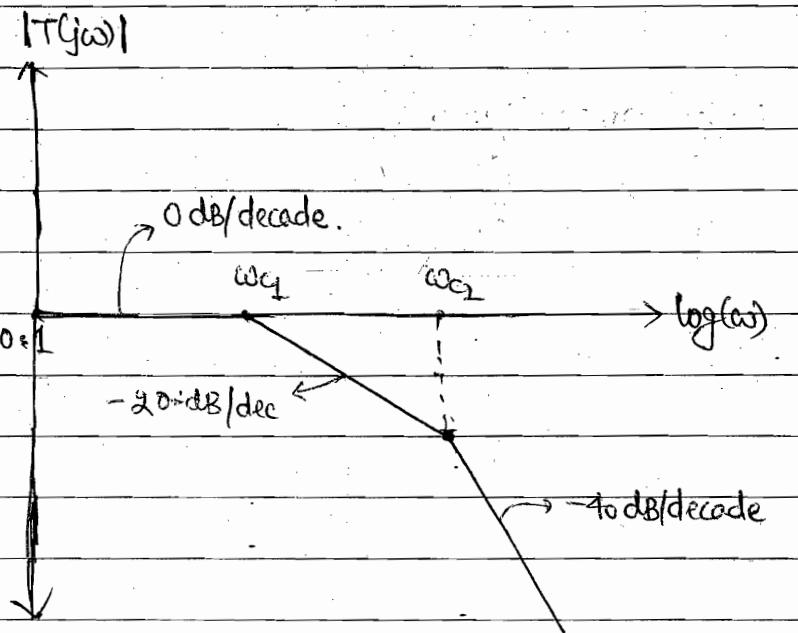
$$\therefore T(s) = \frac{\omega_n^2}{[s + (\xi\omega_n + \omega_n\sqrt{\xi^2 - 1})][s + (\xi\omega_n - \omega_n\sqrt{\xi^2 - 1})]}$$

$$\text{or } T(s) = \frac{\omega_n^2}{(\xi\omega_n + \omega_n\sqrt{\xi^2 - 1})(\xi\omega_n - \omega_n\sqrt{\xi^2 - 1})} \cdot \frac{s+1}{\xi\omega_n + \omega_n\sqrt{\xi^2 - 1}} \cdot \frac{s+1}{\xi\omega_n - \omega_n\sqrt{\xi^2 - 1}}$$

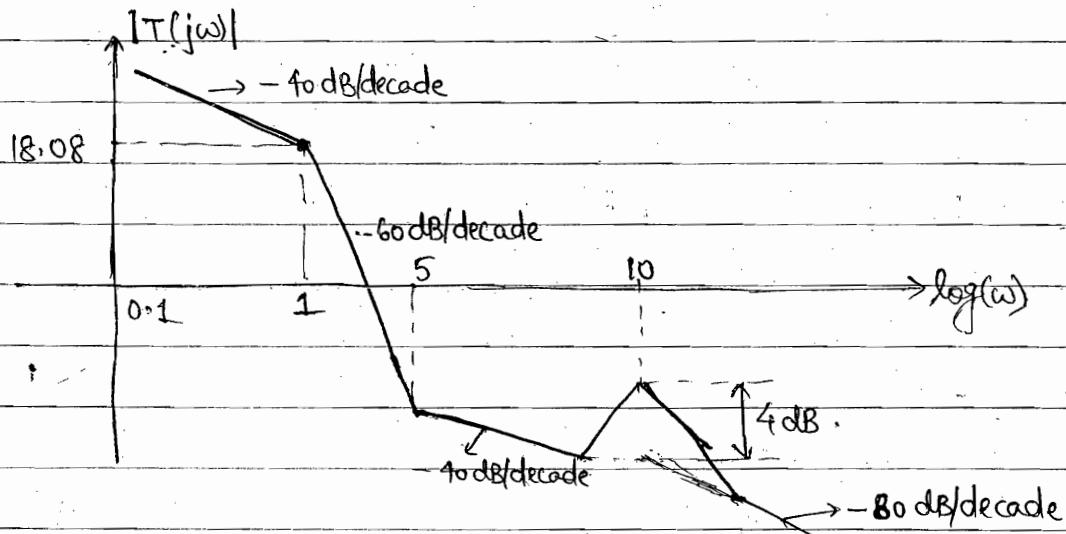
$$\text{or } T(s) = \frac{\omega_n^2}{\omega_n^2} \cdot \frac{s}{\frac{s}{\xi\omega_n + \omega_n\sqrt{\xi^2 - 1}} + 1} \cdot \frac{s}{\frac{s}{\xi\omega_n - \omega_n\sqrt{\xi^2 - 1}} + 1}$$

$$\text{or } T(s) = \frac{1}{[s/\omega_1 + 1][s/\omega_2 + 1]}, \quad \omega_q = \xi \omega_n - \omega_n \sqrt{\xi^2 - 1}$$

$$\omega_s = \xi \omega_n + \omega_n \sqrt{\xi^2 - 1}.$$



Ques:- 6



For given Bode Plot, find its Transfer function.

Ans:- 6)

$$\text{Case: I, } 20 \log(K) = 18.08 \Rightarrow K = 8.$$

$$\text{T.F.} = \frac{(s/5+1)}{s^2(s/1+1)}$$

For Under-damped system, Standardized Transfer function is:

$$\text{T.F.} = \frac{1}{(s/\omega_n)^2 + 2\xi(s/\omega_n) + 1}$$

$$\text{or } T(s) = \frac{1}{s^2 + 2\xi s + 1}$$

$$(s/10)^2 + 2\xi(s/10) + 1$$

$$\text{as } |T(j\omega)| = -20 \log(2\xi) \Rightarrow \boxed{\xi = 0.315} *$$

$$[\because |T(j\omega)| = 9 \text{ dB}]$$

$$\therefore T.F = \frac{(s/5+1)}{s^2(s/10+1)([s/10]^2 + 0.63s + 1)} \quad \underline{\text{Ans}}$$

Chapter :-

ROOT LOCUS TECHNIQUE

* In case of Root Locus, the variable is Gain of Transfer Function and we calculate the locus of pole for Closed Loop System when Gain of Open Loop Transfer Function changes.

* So, for Root Locus, stability is defined in terms of Location of Pole. Hence, Root Locus defines Absolute Stability.

* Example: $G(s)H(s) = \frac{K}{s(s+2)}$, K is a variable here.

$$T(s) = \frac{G(s)}{1+G(s)H(s)} = \frac{K}{s^2 + 2s + K} \quad [0 < K < \infty].$$

$$\therefore q(s) = s^2 + 2s + K = 0.$$

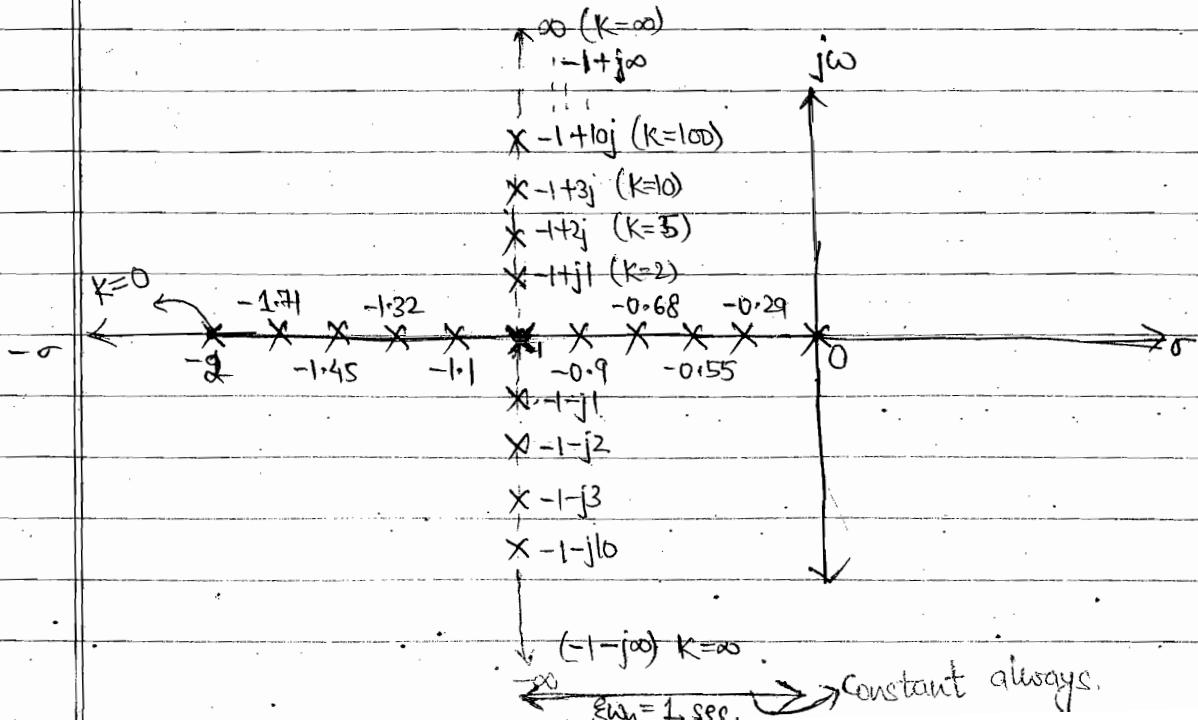
$$K=0; \quad s^2 + 2s = 0, \quad \therefore s=0, s=-2.$$

$$K=0.5; \quad s^2 + 2s + 0.5 = 0; \quad s = -0.29, s = -1.71.$$

$$K=0.8; \quad s^2 + 2s + 0.8 = 0; \quad s = -0.55, s = -1.45$$

$$K=0.9; \quad s^2 + 2s + 0.9 = 0; \quad s = -0.68, s = -1.32.$$

$$K=0.99; \quad s^2 + 2s + 0.99 = 0; \quad s = -0.9, -1.1.$$



\rightarrow Constant always.
 \leftarrow $\omega_n = 1 \text{ sec.}$

$$K=1 ; \quad s^2 + 2s + 1 = 0 ; \quad s = -1, -1.$$

$$K=2 ; \quad s^2 + 2s + 2 = 0 ; \quad s = -1 \pm j1$$

$$K=5 ; \quad s^2 + 2s + 5 = 0 ; \quad s = -1 \pm j2$$

$$K=10 ; \quad s^2 + 2s + 10 = 0 ; \quad s = -1 \pm j3$$

$$K=100 ; \quad s^2 + 2s + 100 = 0 ; \quad s = -1 \pm j10$$

$$K=\infty ; \quad s^2 + 2s + \infty = 0 ; \quad s = -1 \pm j\infty$$

- for $0 < K < 1$; Over-damped ; $\xi > 1$

$K=1$; Critically-damped ; $\xi = 1$

$K > 1$; Underdamped ; $\xi < 1$.

- This system is highly stable.

- For given system,

$$s^2 + 2s + K = 0$$

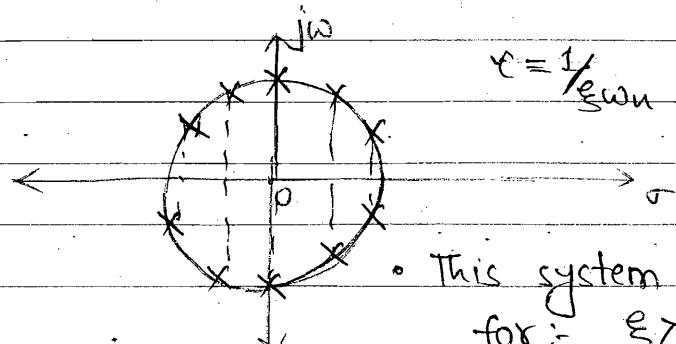
$$\therefore \omega_n = \sqrt{K} \quad \xi \omega_n = 1 \quad \text{and} \quad \therefore \xi = \frac{1}{\sqrt{K}} = \cos \phi$$

$$\boxed{\phi = \cos^{-1}\left(\frac{1}{\sqrt{K}}\right)} \quad *$$

$$\text{Now, } t_c = \frac{4}{\xi \omega_n} ; \quad t_c = 4 \text{ sec, } \tau = 1 \text{ second.}$$

$$\text{For } T(s) = \frac{\omega_n^2}{s^2 + 2\xi\omega_n s + \omega_n^2}$$

Here, ξ is variable, ω_n is constant.



• This system is conditionally stable
for $\xi > 0$.

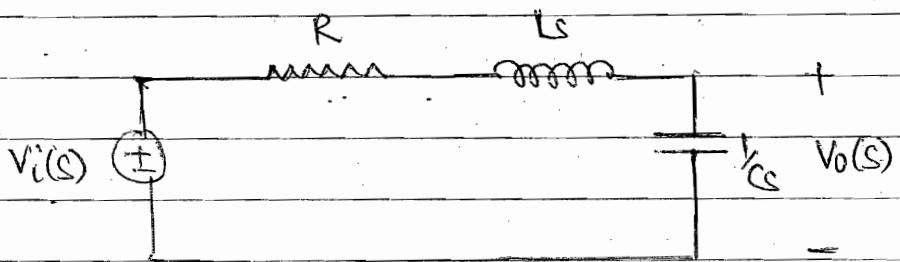
Now, for system: $T(s) = \frac{K \cdot \omega_n^2}{s^2 + 2\xi\omega_n s + K\omega_n^2}$

Here, $\xi\omega_n$ is constant, K is variable.

Undamped Natural frequency = $\sqrt{K \cdot \omega_n}$ (variable).

- But this circuit will be High stable for any value of K lying between 0 and ∞ .

* Consider a RLC circuit



$$\text{Now, } \frac{V_o(s)}{V_i(s)} = \frac{\frac{1}{C}s}{R + Ls + \frac{1}{C}s} = \frac{1}{RCs + \frac{1}{Cs} + 1}$$

$$\text{or } \frac{V_o(s)}{V_i(s)} = \frac{\left(\frac{1}{L}\right)s}{s^2 + R/s + \frac{1}{C}}$$

Here, $\omega_n = \frac{1}{\sqrt{LC}} *$ $\xi\omega_n = \frac{R}{2L} *$

$$\xi = \frac{R}{2\sqrt{LC}} *$$

- To keep ξ as variable and ω_n as constant, we can only change R but not L as if we change L , ω_n also gets varied.

• As $-\infty < R < \infty$, so $-\infty < R < 0$ and $0 < R < \infty$.

$-\infty < \xi < 0$ and $0 < \xi < \infty$.

↳ Unstable

↳ Stable

• As R is power dissipation passive element, so $0 < R < \infty$ is stable.

* Now, for ω_n to be variable but ξ_{wn} to be constant, we can only vary capacitor.

• This system will be highly Stable, hence, Gain Margin should be too.

Note:

- If Time constant is constant and ω_n is variable, system is highly stable.
- If R is varied, system won't be highly stable.
- If C is varied, (ξ_{wn} keeping constant), system will be highly stable.
- If L is varied, then also system will be highly stable.

* Poles start here from open loop pole and tends towards infinity.

Note: In any system, Order of pole = Order of zero always. In transfer functions, only those poles and zeros are visible which is located at finite distances and those poles and zeros which are not visible, they are located at ∞ , so, their individual TFs are 1.

Only, Root locus, explains that in a system, Order of Pole equals Order of zero. i.e

$$G(s)H(s) = \frac{(K_2)}{s[s_2+1]}, \text{ Actually, it is: } G(s)H(s) = \frac{(K_2)}{s} \cdot \frac{s}{s_2+1}$$

$$\text{Here, } \omega_1 = \omega_2 = \infty, \therefore \left[\frac{s}{\infty} + 1 \right] = 0 + 1 \Rightarrow 1.$$

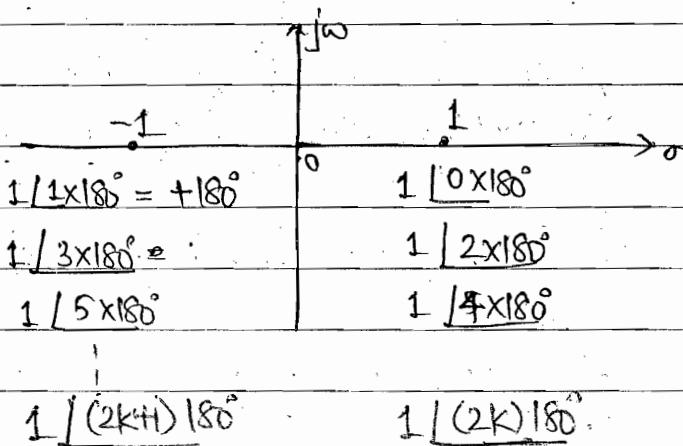
$$\therefore G(s)H(s) = \frac{(K_2) \times 1 \times 1}{s[s_2+1]}$$

$$\therefore G(s)H(s) = \frac{(K_2)}{s[s_2+1]}$$

$$G(s) = 1 + G(s)H(s) = 0$$

$$\therefore G(s)H(s) = -1 \quad *$$

** This implies that, closed loop poles will lie on s-plane on only those locations, where when we substitute value of s and K in Open Loop Transfer function, the values of $G(s)H(s)$ or open loop TF must be -1 .



Note: ∵ For closed Loop poles to lie on (-1) , Phase must be:
 $(2k+1)180^\circ$.

* Analysis: $G(s = -0.29)H(s = -0.29) = \frac{0.5}{(0.29)(2-0.29)} = -1.$

$$G(s = -1.45)H(s = -1.45) = \frac{0.8}{(-1.45)(-1.45)} = -1.$$

∴ At $K = 0.5, 0.8$ and $s = -1.45, -0.29$, closed loop poles are there as $G(s)H(s) = -1$ for these values.

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

∴ For any positive K , $G(s=1)H(s=1) \neq -1$;
so, closed loop poles does not lie at $s=1$.

• At $s = -3$, $G(s=-3)H(s=-3) = \frac{K}{(-3)(-3+2)} = \frac{K}{3}$

\therefore Here, also $s = -3$, no pole is there.

• At $s = -0.5$, $G(s=-0.5)H(s=-0.5) = \frac{K}{(-0.5)(2-0.5)} = \frac{K}{1.5}$

* In Root Locus, Phase Angle condition is dominant. If any location satisfies Phase Angle condition, then for finite value of K in $0 < K < \infty$, it will also satisfy Magnitude condition.

* Origination Point:

* Root Locus originates either from Open Loop pole or Infinity but priority will be given to Open Loop pole and value of K at origination point is zero.

* Termination Point:

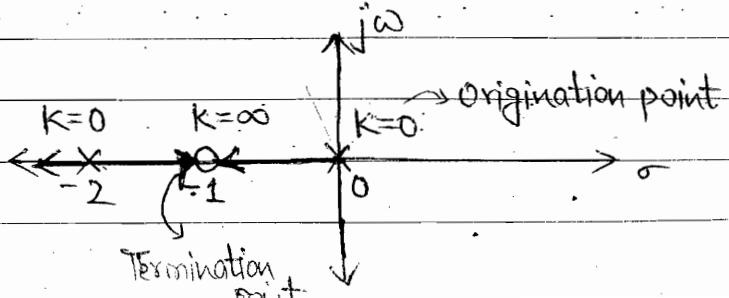
* Root Locus terminates either at Open Loop zero or Infinity but priority will be given to Open Loop zero and value of K at termination point will be ∞ .

Example: $G(s)H(s) = \frac{K(s+1)}{s(s+2)}$

$$1 + G(s)H(s) = 0 \Rightarrow \frac{K(s+1)}{s(s+2)} = -1.$$

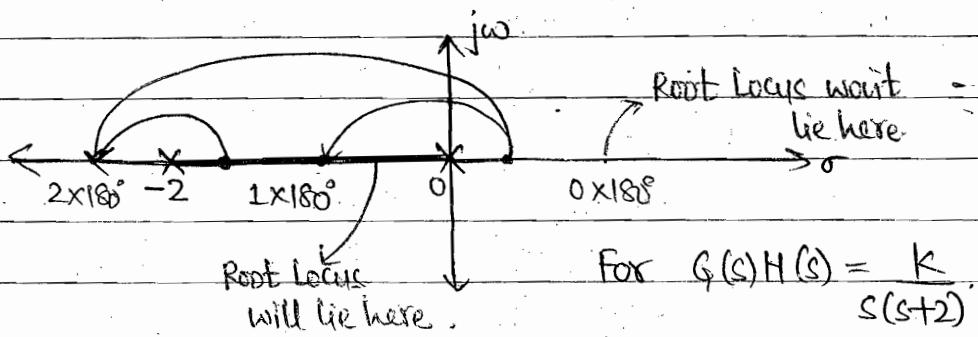
$$\frac{K(s+1)}{s(s+2)} = -1 \Rightarrow K = -\frac{s(s+2)}{(s+1)}.$$

$$\therefore K_{s=0} = -0 = 0, K_{s=-2} = 0, K_{s=\infty} = \infty.$$



* Existence of Root Locus on Real-axis

- Root Locus will exist only at that location on Real-axis whose overall angle subtended by that location with Open Loop pole and zero is : Odd Integral Multiple of 180° or in other words, Root Locus will exist only in that section of Real-axis which contains odd number of Open Loop poles and zeros towards its right side.



Here, $0x180^\circ$ represents, for any value of s here, in this location, value of $G(s)H(s)$ will be Positive.

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

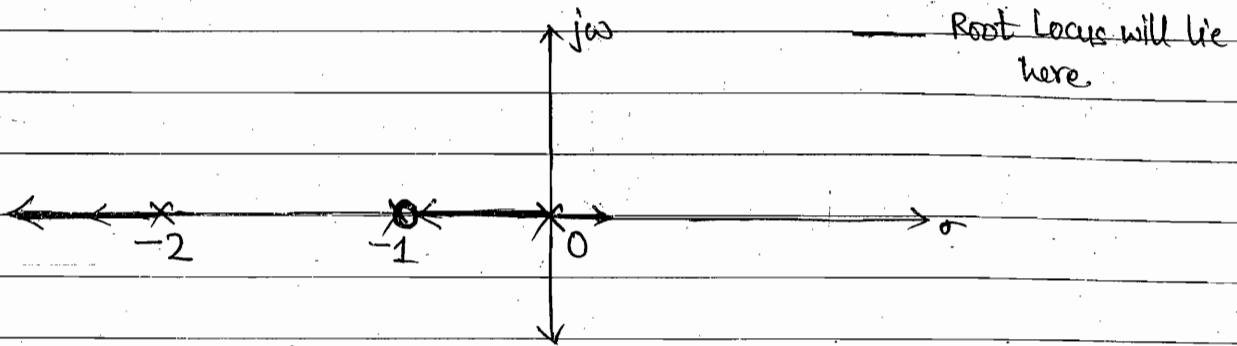
$1x180^\circ$ represents, for any value of s , one term will be negative. Hence, for a specific K , $G(s)H(s) = -ve$.

$$\therefore G(s)H(s) \Big|_{s=-1} = \frac{K}{(-1)(2-1)} = \frac{K}{(-1)} = -ve.$$

$2x180^\circ$ represents, for any value of s , ^{two} term will be negative, finally giving $G(s)H(s) = +ve$.

$$\therefore G(s)H(s) \Big|_{s=-3} = \frac{K}{(-3)(2-3)} = \frac{K}{3} = +ve.$$

• For $G(s)H(s) = \frac{K(s+1)}{s(s+2)}$

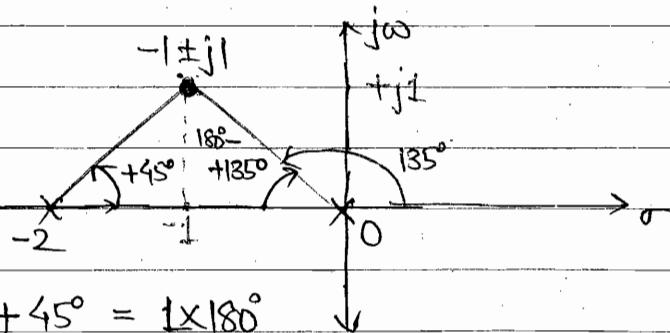


Existence of Root Locus on Complex-plane :-

- Root Locus will exist only at that location on complex-plane whose overall subtended angle from all open loop poles and zeros is : odd Integral Multiple of 180° or in other words, we substitute the given complex location in characteristics equation and then we will calculate the value of K.

* If K is real and positive, for given complex-location, then that location is valid location and closed loop pole will exist at that location.

* If K is either, Imaginary, complex or Negative, then that location will be invalid location and closed loop pole won't exist at that location.



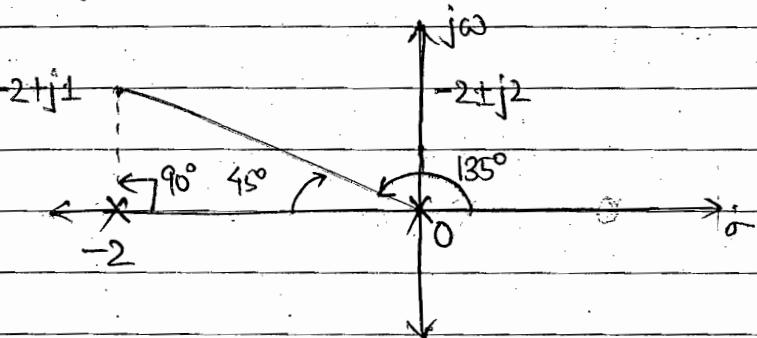
$$\therefore 135^\circ + 45^\circ = 1 \times 180^\circ$$

* Other Method :- $K \Big|_{s=-1 \pm j1} = -s [s+2] \Big|_{s=-1 \pm j1} = [(-1+j1)[-1+j1+2]]$

$$K = -(-2) \Rightarrow \boxed{K \Big|_{s=-1 \pm j1} = 2} *$$

- As $K = 2$ (pure and real), $s = -1 + j1$ lies on Root locus.

Similarly,

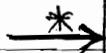


$$\therefore 135^\circ + 90^\circ = 225^\circ.$$

Other Method: $K \Big|_{-2+j2} = -[(-2+j2)[-2+j2+2]]$

$$\boxed{K \Big|_{-2+j2} = 4(1+j)} *$$

- As $K = \text{Complex}$, $s = -2+j2$ does not lie on Root locus.



- Break point is location in s-plane where two pole coincides simultaneously. It is of two type:

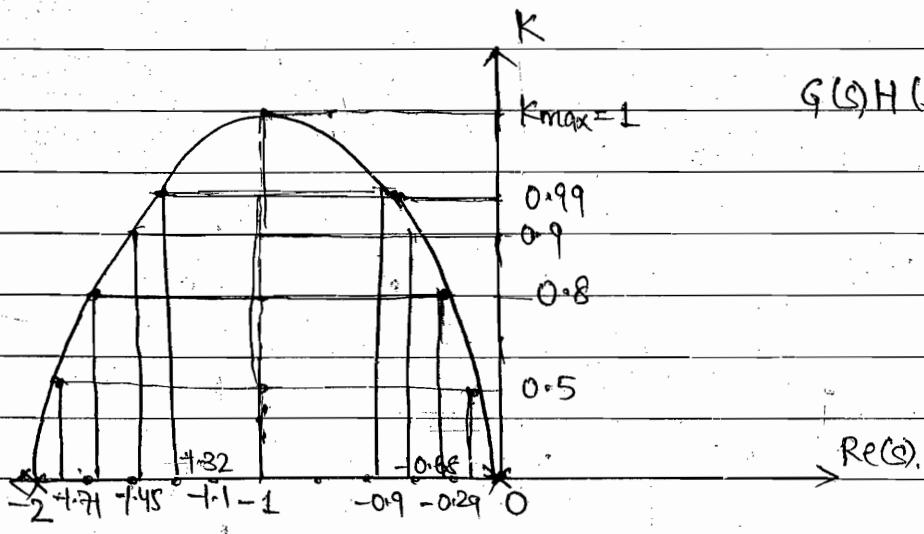
(i) Break-away point (ii) Break-in point.

(i) Break-away point :

- It is a point in s-plane where the value of K is Maximum.

Thus, whenever Root Locus shifts from Real-axis to complex plane, always Break-away point will exist. To calculate, location of Break-away point, we will differentiate K in characteristics equation with respect to s and then set,

$$\frac{dK}{ds} = 0.$$



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

- So, breakaway point is Maximum value of K for Root Locus to be on the Real-axis. If K exceeds this Maximum value, then Root Locus will enter into Complex-plane. Thus, whenever Root Locus shifts from Real-axis to Complex-plane, always Break-away point exists. To calculate location of break-away, do;

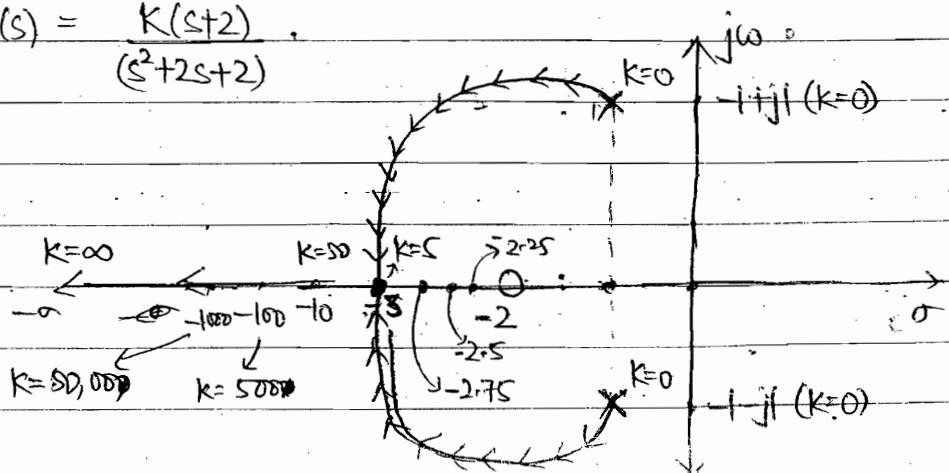
$$\frac{dK}{ds} = 0.$$

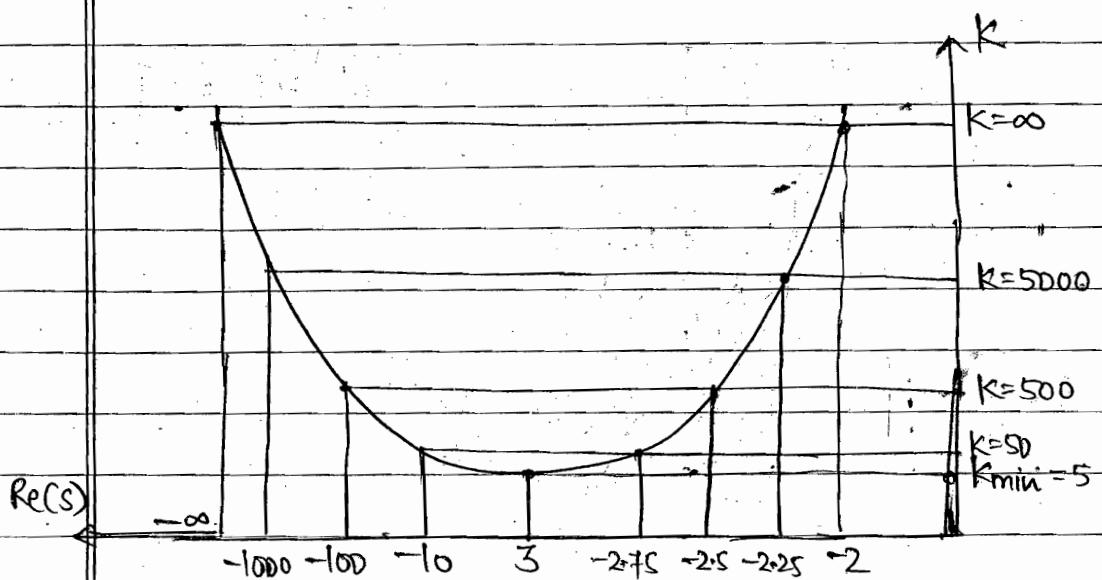
(ii) Break-in Point :

- It is the Minimum value of K for Root Locus to be on the Real-axis. When K is less than this minimum value, then Root Locus will remain in Complex-plane. Thus, whenever Root Locus shifts from Complex-plane to real-axis, always Break-in point exists. To calculate location of break-in point, do;

$$\frac{dK}{ds} = 0,$$

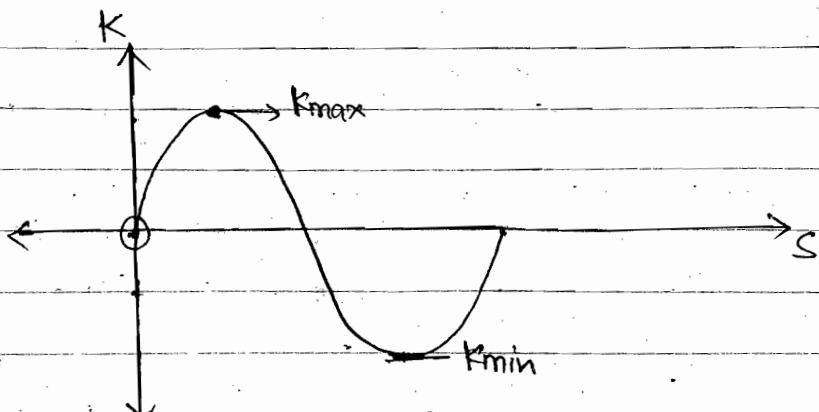
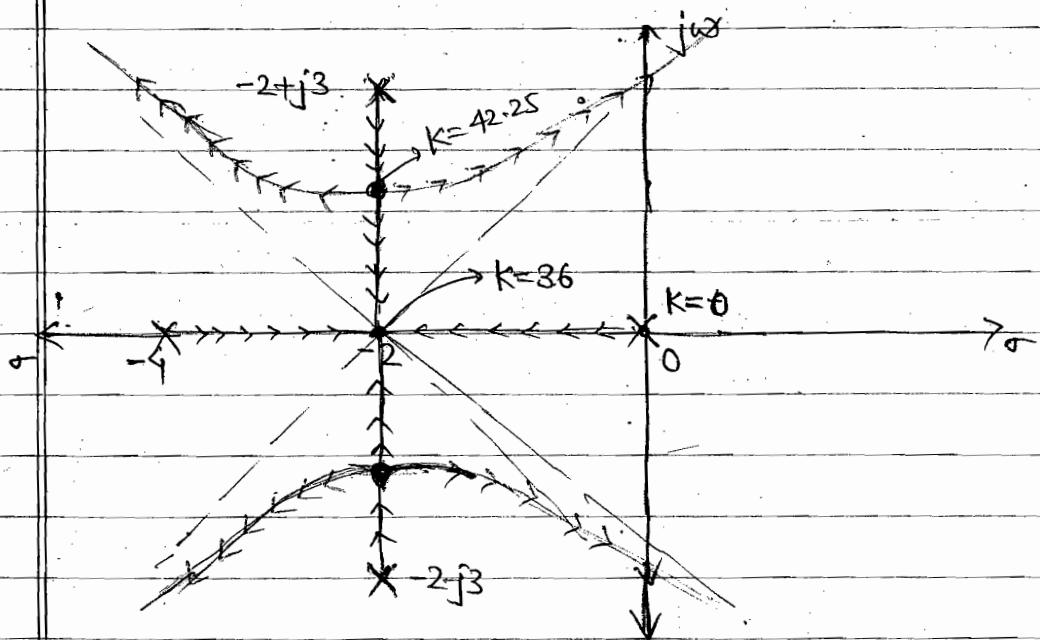
* Example:- $G(s)H(s) = \frac{K(s+2)}{(s^2+2s+2)}$.





- It is not symmetrical graph.

* Example:- $G(s)H(s) = \frac{K}{s(s+4)(s^2+4s+13)}$



→ Centroid :

- It is the origin of Asymptotic line. The centroid (X) will be:

$$X = \frac{\sum P - \sum Z}{P-Z} * \sum P = \text{Sum of the location of Open Loop pole.}$$

$\sum Z = \text{Sum of the location of Open Loop zero.}$

$P = \text{Total number of open Loop poles.}$

$Z = \text{Total number of Open Loop zero.}$

→ Angle of Asymptotes :

- We will calculate Asymptotic angle only for that branch of Root Locus which is either originating or terminating to or from infinity.

Case-I → $P > Z$:

From p number of open loop poles, p branch of Root Locus and branch will originate and out of p branches, z number of branches will terminate on z number of open loop zeros, and remaining $(p-z)$ number of branch will terminate at ∞ . We will calculate asymptotic angle only for $(p-z)$ number of branches which will terminate at ∞ .

$$\theta_k = \frac{(2k+1)180^\circ}{p-z} * k = 0, 1, 2, \dots, k_{\max}$$

$$k_{\max} = p-z-1$$

- For $G(s)H(s) = \frac{k}{s(s+2)}$

$$\Rightarrow \sum P = -2, \sum Z = 0.$$

$$\therefore X = \frac{-2-0}{2-0} \Rightarrow X = -1$$

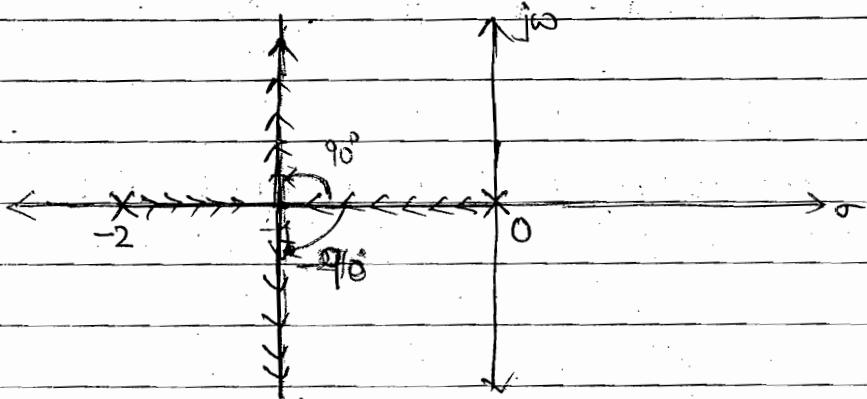
$$\text{Now, } K_{\max} = P-Z-1 = 2-0-1 = 1$$

$$\therefore K_{\max} = 0+1 = 1.$$

$$\therefore K = 0, 1.$$

$$\text{Now, } \theta_k = \frac{(2k+1)180^\circ}{P-Z} \Rightarrow \theta_0 = \frac{180^\circ}{2} \Rightarrow \theta_0 = 90^\circ.$$

$$\theta_1 = \frac{3 \times 180^\circ}{2} = 270^\circ.$$



$$*\text{ Example:- } G(s)H(s) = \frac{K(s+2)}{s(s+2)+2}$$

$$\therefore P=2, \quad Z=1, \quad K_{\max} = 2-1-1 = 0.$$

$$\therefore K=0.$$

$$\sum P = -2, \quad \sum Z = -2$$

$$P=2 \quad Z=1. \quad \therefore \theta_k = \frac{(2k+1)180^\circ}{P-Z}$$

$$X = \frac{-2+2}{2-1}$$

$$\boxed{\theta_0 = 180^\circ} *$$

$$\boxed{X=0.} *$$

* Root Locus of this OLTF is drawn earlier.

• For, $G(s)H(s) = \frac{K}{s(s+4)(s^2+4s+13)}$

Now, $K_{\max} = 4 - 0 - 1 = 3$, $K = 0, 1, 2, 3$.

$$\therefore \theta_0 = 45^\circ, \theta_1 = 135^\circ, \theta_2 = 225^\circ, \theta_3 = 315^\circ.$$

$$\Sigma P = -8 \quad \Sigma Z = 0.$$

$$\therefore X = \frac{-8-0}{4} = -2.$$

* Case-II: $Z > P$.

• Here, from p number of open-loop poles, p branch of Root Locus will originate and all p branch will terminate at p number of zeros. For termination of Remaining $(Z-p)$ number of branch, Root Locus will originate from infinity and we will calculate Angle of Asymptotes only for those branches of Root Locus which are originating from ∞ .

$$\theta_K = \frac{(2K+1)180^\circ}{Z-P}, \quad K = 0, 1, 2, \dots, (Z-P-1)$$

* Consider: $G(s)H(s) = \frac{Ks(s+1)(s+3)}{(s+2)}$

$$\Rightarrow Z = 3, \quad P = 1, \quad \Sigma Z = -4, \quad \Sigma P = -2.$$

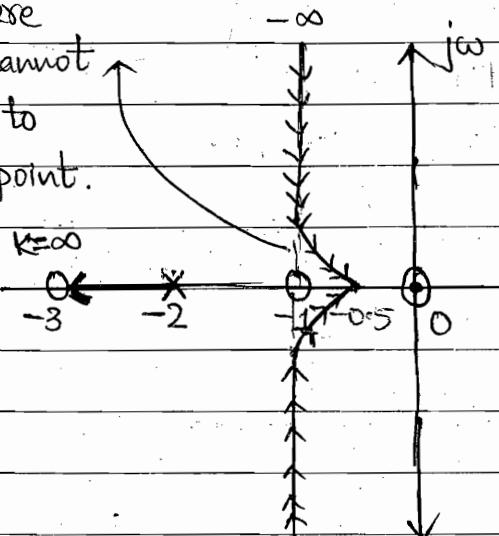
$$\therefore X = \frac{-4+2}{2} = -1$$

$$\therefore K_{\max} = (3-1)-1 = 1, \quad K = 0, 1.$$

$$\therefore \theta_0 = 90^\circ, \quad \theta_1 = 270^\circ.$$

Here

- Centroid cannot be equal to Break-in point.



Here, Break-point is : 0.5

* In first case, ($p > z$), Root Locus follows Asymptotic line for higher value of K .

* In second case ($z > p$), Root Locus follows asymptotic line for lower value of K .

\rightarrow GAIN MARGIN :

$$\text{Gain Margin} = \frac{K_{\text{marginally stable}}}{K_{\text{desired}}} *$$

- To calculate $K_{\text{marginally stable}}$, we will use R-H criterion. In R-H

criterion, we will calculate that value of K for which odd row becomes 0 and then, we will substitute that value of K in even row just above that odd row, then we will calculate location of poles. If poles are located at Imaginary-axis for this value of K , then that K will be

* For closed loop system to be stable should be > 1 and in dB, it should be positive provided OLF is Minimum phase system.

* If OLF is Non-minimum phase system, then for closed loop system to be stable, Gain Margin in ratio should be < 1 and in dB, it should be Negative.

* Angle of Departure:

- We will calculate Angle of Departure only for that open loop pole which lies at complex-conjugate location.

$$\phi_d = 180^\circ - [\phi_p - \phi_z]$$

* ϕ_p = Total angle subtended by remaining pole towards that pole whose departure angle to be calculated.

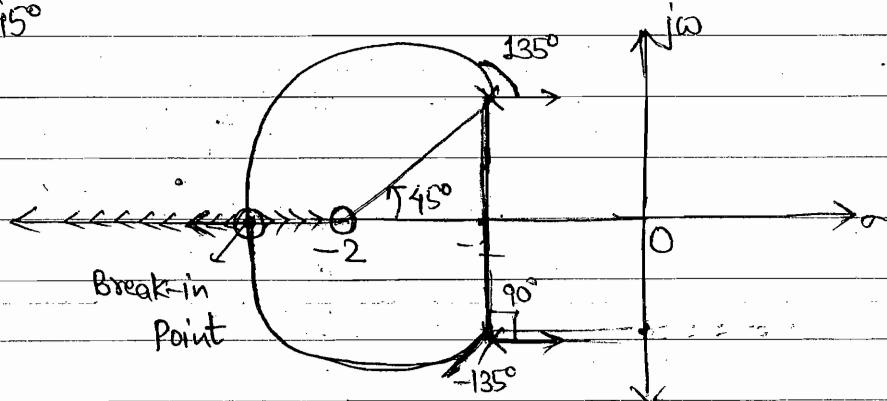
ϕ_z = Total angle subtended by odd open loop zeros towards that complex-pole whose departure angle, we are calculating.

* Example: $G(s)H(s) = \frac{k(s+2)}{s^2 + 2s + 2}$

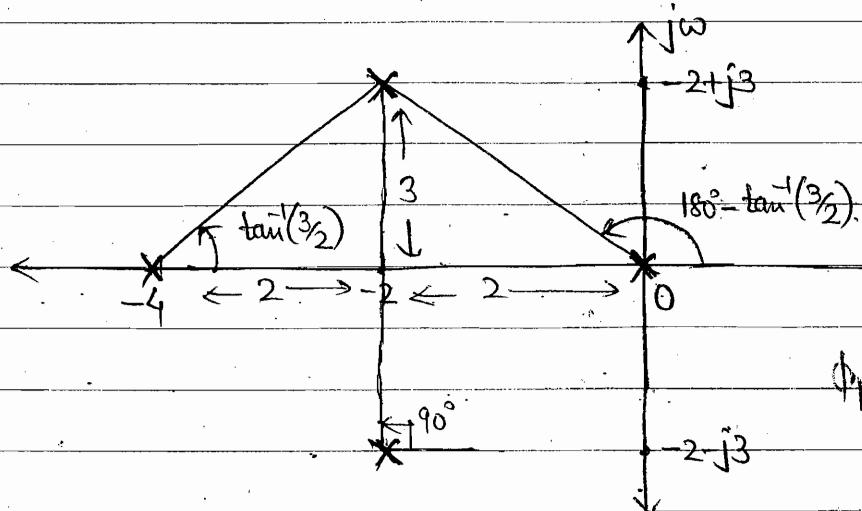
$$\phi_p = 90^\circ$$

$$\phi_z = 45^\circ$$

$$\phi_d = 135^\circ$$



* Example: $G(s)H(s) = \frac{k}{s(s+4)(s^2 + 4s + 13)}$



$$\phi_p = \tan^{-1}(3/2) + 180^\circ - \tan^{-1}(3/2) + 90^\circ$$

$$\phi_p = 180^\circ, 270^\circ$$

$$\phi_z = 0^\circ$$

$$\phi_d = 360^\circ$$

$$\text{or } \phi_d = 0^\circ$$



Angle of Arrival :

We calculate Angle of Arrival only for complex-zero.

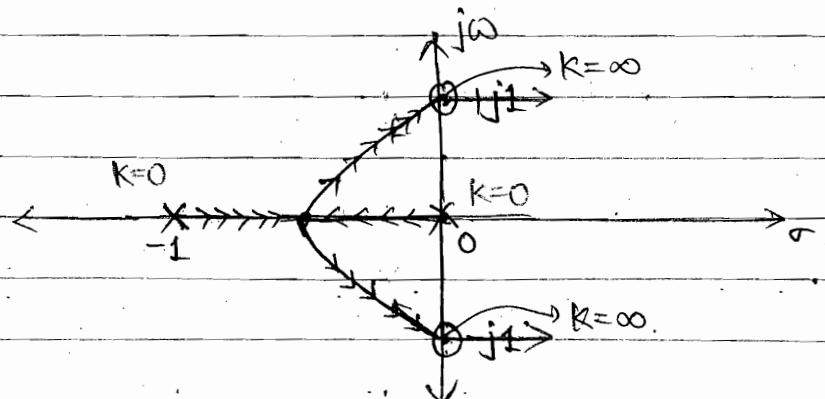
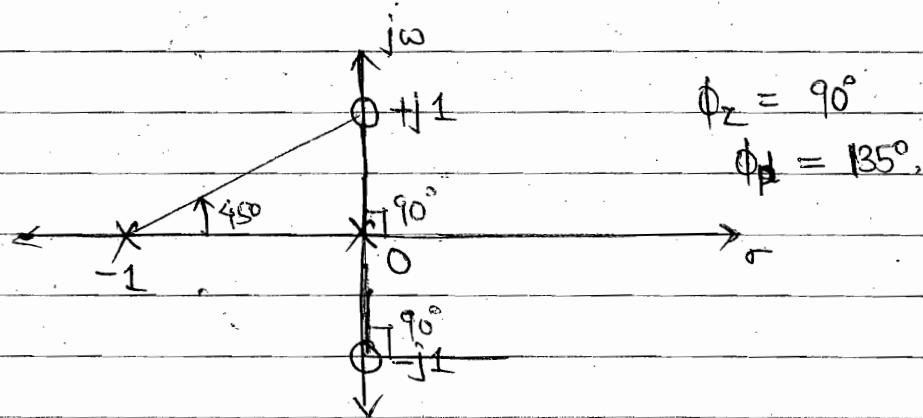
$$\theta_a = 180^\circ - [\phi_z - \phi_p]$$

* ϕ_z = Total angle subtended by remaining zero

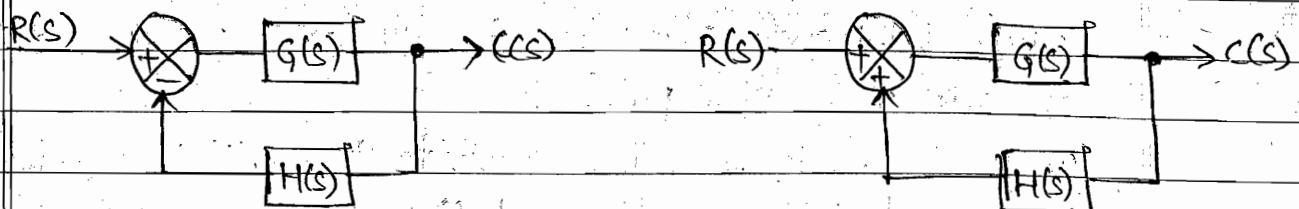
towards that complex-zero whose arrival angle we are to calculate.

ϕ_p = Total angle subtended by all open loop poles towards that zero whose arrival angle we are to calculate.

* Consider:- $G(s)H(s) = \frac{K(s^2 + 1)}{s(s+1)}$.



* Root Locus Plot For Positive Feedback system



$$\frac{C(s)}{R(s)} = \frac{G(s)}{1 + \sum G(s)H(s)}$$

$$\frac{e(s)}{R(s)} = \frac{G(s)}{1 + \sum -G(s)H(s)}$$

$$\therefore G(s)H(s) = -1$$

$$\text{or } G(s)H(s) = 1 / (2k+1) 180^\circ.$$

$$G(s)H(s) = 1$$

$$\text{or } G(s)H(s) = 1 / (2k) 180^\circ.$$

- If we provide phase lead or phase lag of 180° in Negative feedback system, then it converts to Positive feedback system.

$$\bullet \frac{G(s)H(s) = +K}{s(s+2)}$$

$$0 < K < \infty$$

implies Negative Feedback System.

$$\bullet \frac{G(s)H(s) = -K}{s(s+2)}$$

$$-\infty < K < 0$$

implies Positive feedback system

(with -ve sign already used, range of K is:
 $0 < K < \infty$).

* Existence of Root Locus on Real-axis

- Root Locus will exist only at that section of Real axis where total angle subtended by all open loop poles and zeros towards observation point is: Even Integral Multiple of 180° .

Or in other words, Root Locus exists only at that section of Real-axis which contains OL poles and zeros towards its Right side.

* Existence of Root Locus on Complex-plane:

- Root locus will exist only at that location in complex plane where total angle subtended by all open loop poles and zeros towards observation point is: Even integral multiple of 180° or in other words, we will substitute the given complex location in characteristics equation and then we will calculate the value of K , if K is real and positive, for the given complex location, then that location is valid location and closed loop poles will exist at that location.

* If K is either Imaginary, Negative or Complex for the given location, then that location will be invalid location and closed loop poles will not exist at that location.

* Angle of Departure & Asymptotes:

Case-I :- $P > Z$

$$\Theta_K = \frac{(2K)180^\circ}{P-Z}$$

$$K = 0, 1, 2, \dots, (P-Z-1)$$

Case-II :- $Z > P$

$$\Theta_K = \frac{(2K)180^\circ}{Z-P}$$

$$K = 0, 1, 2, \dots, (Z-P-1)$$

* Angle of Departure:

$$\boxed{\Theta_d = 0^\circ - (\phi_p - \phi_z)} *$$

* Angle of Arrival:

$$\boxed{\Theta_a = 0^\circ - (\phi_z - \phi_p)} *$$

Numericals

Ques-① The open loop TF of a system is: $G(s)H(s) = \frac{k}{s(s+4)}$, $0 < k < \infty$.

Draw its Root Locus and determine all possible damping conditions for different value of k . Also calculate value of k for $s = -2 + j2$.

Ans:- ① $s_{p_1} = 0, s_{p_2} = -4$

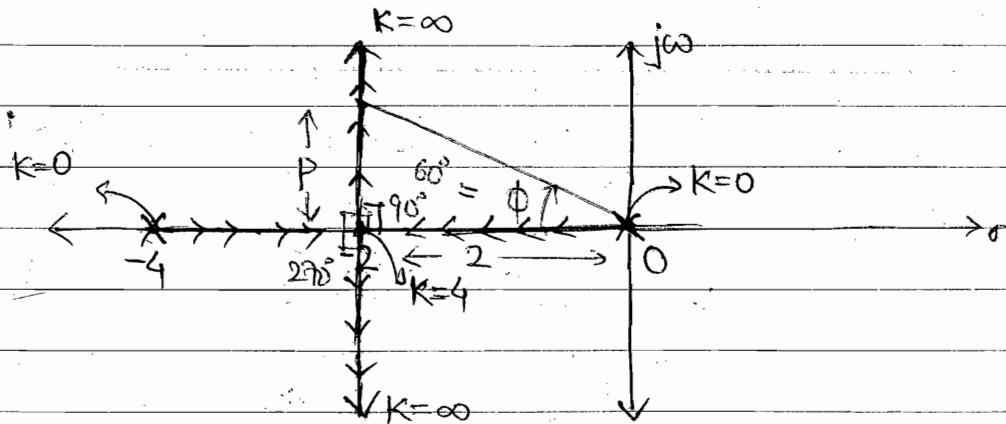
$$q(s) = 1 + G(s)H(s) = 0.$$

$$\frac{1+k}{s(s+4)} = 0.$$

$$\therefore s^2 + 4s + (4+k) = 0. \Rightarrow -k = s^2 + 4s.$$

$$\text{or } -\frac{dk}{ds} = 2s + 4 = 0.$$

$$s = -2 \quad *$$



$$\text{Now, } k|_{s=-2} = -[4-8] = 4. \quad \therefore k|_{s=-2} = 4.$$

$$\text{Now, } k_{\max} = 2-0-1 = 1. \quad \therefore k = 0, 1.$$

$$\therefore \theta_0 = 90^\circ, \theta_1 = 270^\circ.$$

$$X = \frac{\sum P - \sum Z}{P-Z} = \frac{-4-0}{2} = -2.$$

$$\text{As } q(s) = s^2 + 4s + (\cancel{4}k) = 0,$$

| | | |
|-------|-----|-----|
| s^2 | 1 | k |
| s^1 | 4 | |
| s^0 | k | |

As odd row does not become 0, so Root Locus does not cut Imaginary axis.

* Here, as for any value of K , as closed loop poles are on RHS of s -plane, so system will be: Highly Stable [GM : $+\infty$].

* $0 < k < 4$; Overdamped system ($\xi > 1$).

$k=4$; Critically-damped system ($\xi = 1$).

$k > 4$; Under-damped system ($\xi < 1$).

and system will never be undamped system.

$$\text{As } k = -s^2 + 4s.$$

$$\therefore K|_{(-2+j2)} = -[(-2+j2)[-2+j2+4]] = -[(-2+j2)(2+j2)]$$

$$K|_{(-2+j2)} = -[-4-4]$$

$$K|_{s=-2+j2} = 8 *$$

* For $\xi = 0.5$, calculate ϕ .

$$\therefore \xi = \cos\phi \Rightarrow \cos\phi = \frac{1}{2}$$

$$\therefore \phi = 60^\circ *$$

$$\tan\phi = \frac{P}{2} \Rightarrow P = 2\sqrt{3} *$$

Ques:- ② The OLTF of a system: $G(s)H(s) = \frac{-K}{s(s+4)}$.

- Draw its Root Locus and comment on stability.

Ans:- ② $s_p, z = 0, -4$.

$$q(s) = 1 - G(s)H(s) = 0$$

$$\text{or } 1 - \frac{K}{s(s+4)} = 0$$

$$\text{or } \frac{dk}{ds} = 2s + 4 \quad : \quad s = -2 \quad *$$

$$k_{\max} = (2-0)-1 = 1 \quad \therefore K=0,1$$

$$\therefore \Theta_0 = 0^\circ, \Theta_1 = 180^\circ$$

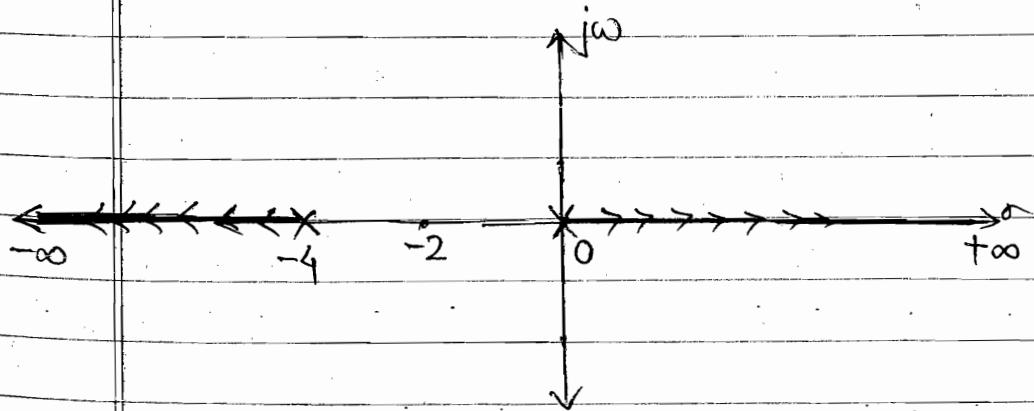
$$\therefore X = \frac{\sum P - \sum Z}{P-Z} \Rightarrow X = \frac{-4-0}{2} = -2$$

\therefore The breakpoint $s = -2$ is invalid break-point.

$$q(s) = s^2 + 4s - K = 0$$

| | | |
|-------|------|------|
| s^2 | 1 | $-K$ |
| s^1 | 4 | |
| s^0 | $-K$ | |

\therefore Pole on Right-half of s-plane = 1..



\therefore This system is highly unstable, so GM is $-ve \infty$.

Ques: (3) The open loop TF of a system is $\frac{G(s)H(s)}{s(s+1)(s+3)} = \frac{k}{s(s+1)(s+3)}$, $0 < k < \infty$.

Draw its Root Locus and determine Gain Margin at $k=6$.

Ans: (3) $s_p = 0, -1, -3$.

$$1 + G(s)H(s) = 0$$

$$\Rightarrow \frac{k}{s(s+1)(s+3)} = -1$$

$$\Rightarrow k = -s[s+1][s+3]$$

$$\therefore s = -0.45, -2.21$$

$$k|_{s=-0.45} = 0.63$$

$$\text{As } \theta_K = \frac{(2K+1)}{180^\circ(p-z)} \Rightarrow \theta_K = \frac{(2K+1)180^\circ}{3}$$

$$\therefore \theta_0 = 60^\circ, \theta_1 = 180^\circ, \theta_2 = 300^\circ$$

$$\text{Now } x = \frac{\sum p - \sum z}{p-z} = \frac{-4-0}{+3} = -\frac{4}{3} = -1.33$$

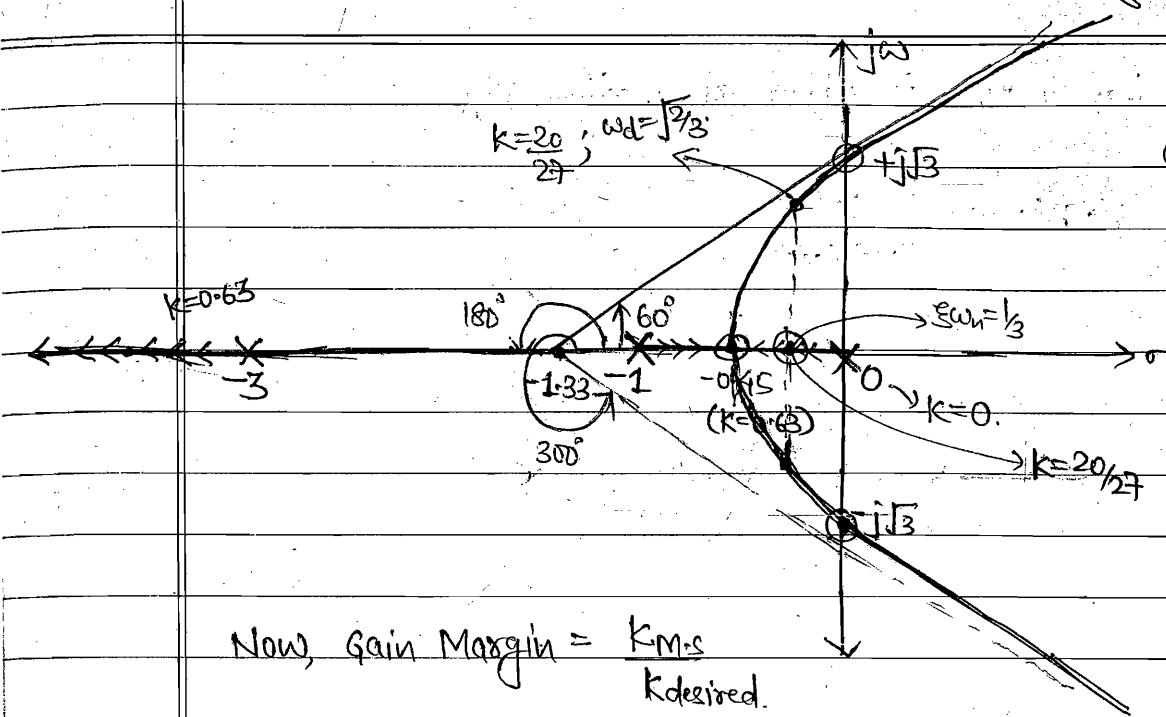
$$\text{Now, } g(s) = s^3 + 4s^2 + 3s + k = 0$$

| | | | |
|-------|--------------------|-----|--|
| s^3 | 1 | 3 | |
| s^2 | 4 | K | $\Rightarrow K = 12$ |
| s^1 | $(\frac{12+K}{4})$ | | * for system to be marginally stable. |
| s^0 | K | | |

$$\therefore 4s^2 + K = 0 \Rightarrow 4s^2 = -12 \Rightarrow s = \pm j\sqrt{3}$$

$$K = \frac{20}{27}, \omega_d = \sqrt{\frac{2}{3}}$$

$\omega_n = \sqrt{\frac{2}{3}}$ and it is not constant here.



$$\text{Now, Gain Margin} = \frac{K_M.s}{K_{\text{desired}}}$$

$$\therefore GM = \frac{12}{6}$$

$$\therefore GM = 2 * GM(\text{dB}) = 20 \log(2)$$

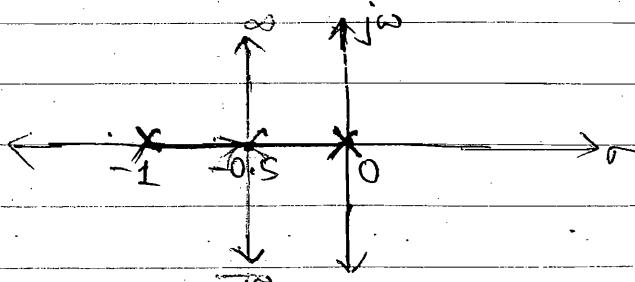
$$GM(\text{dB}) = 6.02 \text{ dB} * (\text{stable system}).$$

$$\therefore \text{For } K_{\text{desired}} = 24, \quad GM = \frac{12}{24} = \frac{1}{2}.$$

$$\therefore GM(\text{dB}) = -6.02 \text{ dB} * (\text{Unstable system}).$$

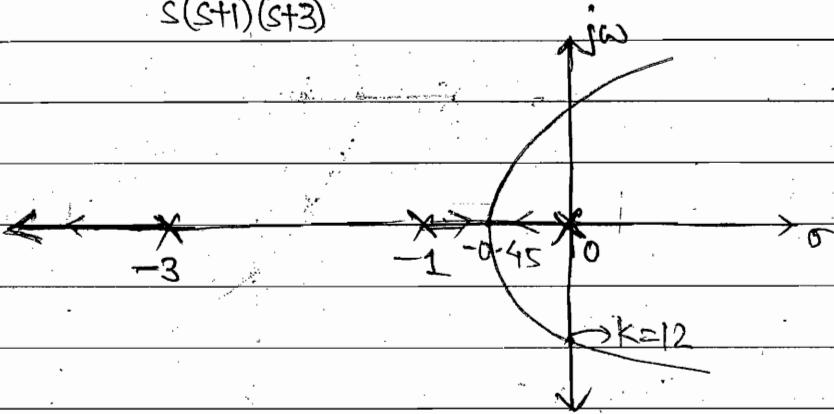
→ Effect of Adding Pole in any system:

$$* \text{ Example: } G(s)H(s) = \frac{K}{s(s+1)}$$



Now, when a pole is added at location $s = -3$.

$$\text{So, } G(s)H(s) = \frac{K}{s(s+1)(s+3)}$$



* Note: * With addition of pole in any system, its stability decreases because Root Locus which is locus of pole of closed loop system will shift towards right-side.

As stability depends on t_s , hence when stability will decrease, t_s will increase, $\% M_p$ will also increase.

Ques-④ The OLTF of a system is :- $G(s)H(s) = \frac{-K}{s(s+1)(s+3)}$; $0 < K < \infty$.

- Draw its Root Locus and comment on the stability of the system.

Ans:- ④ $s_p = 0, -1, -3, \quad G(s)H(s) = -1, \quad K|_{s=-2.21} = 2.11.$

$$\therefore \frac{dk}{ds} = 0 \text{ gives : } s = -0.45, -2.21.$$

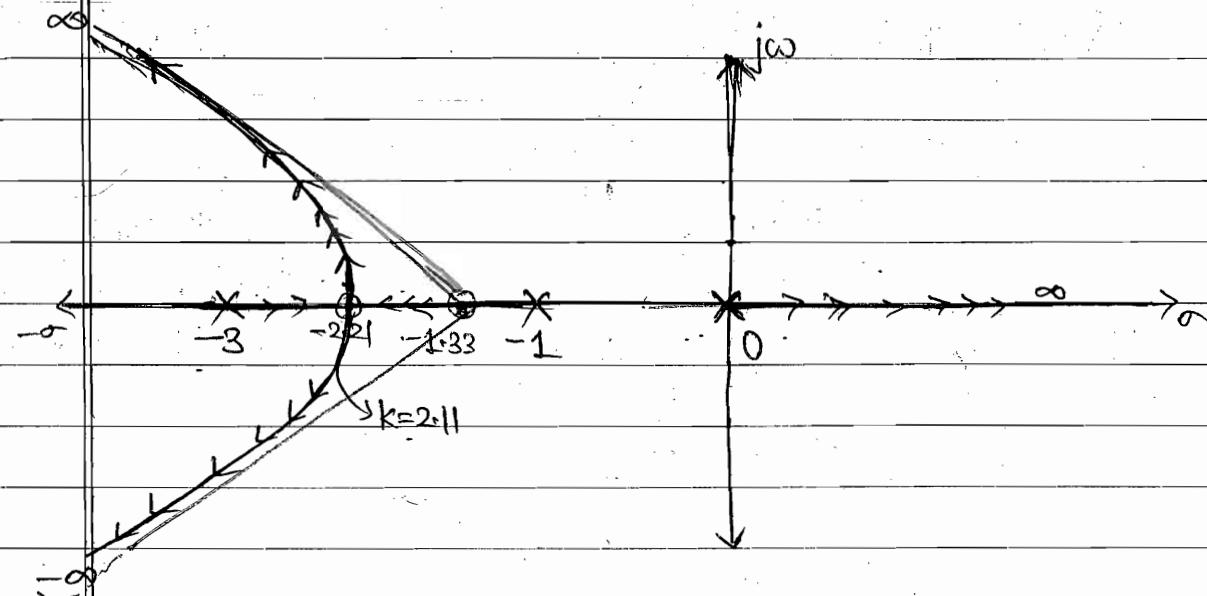
$s = -2.21$ will be valid point.

$$\Theta_0 = 0^\circ, \quad \Theta_1 = 120^\circ, \quad \Theta_2 = 240^\circ \quad \text{and} \quad x = -1.33.$$

$$\therefore q(s) = s^3 + 9s^2 + 3s - K = 0.$$

| | | |
|-------|------------|----|
| s^3 | 1 | 3 |
| s^2 | 4 | -k |
| s^1 | $(12+k)/4$ | |
| s^0 | -k | |

$\therefore k = -12$ * (for Marginally Stable)
 \therefore it is invalid value of k as
 $0 < k < \infty$.



Ques:- 5) The OLTF of a system is: $G(s)H(s) = \frac{k(s+1)^2}{(s+2)^2}$, $0 < k < \infty$

Determine the possible damping conditions for different value of k .

Ans:- 5) $s_p = -2, -2, \quad s_z = -1, -1$.

Now, $k = -\frac{(s+2)^2}{(s+1)^2}$.

or $\frac{dk}{ds} = \frac{2(s+1)^2(s+2) - 2(s+2)^2(s+1)}{(s+1)^4} = 0$

$$\Rightarrow 2(s+1)^2(s+2) = 2(s+2)^2(s+1)$$

$$\Rightarrow (s+1) = (s+2) \quad \text{or} \quad (s+1)(s+2) = 0$$

$$s = -1, -2$$

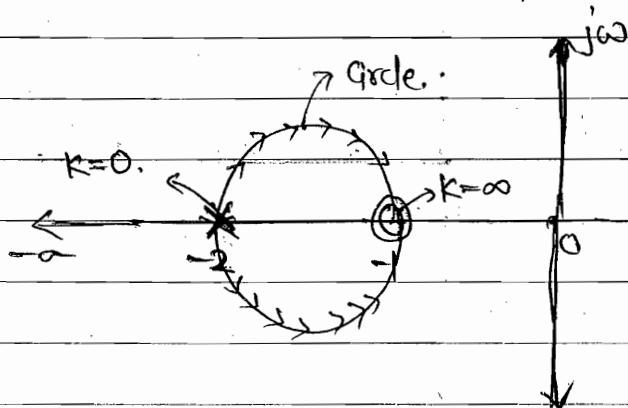
$$k|_{s=-1} = \infty \quad k|_{s=-2} = 0$$

$$\Rightarrow q(s) = (s+2)^2 + k(s+1)^2 = 0.$$

$$\text{or } (1+k)s^2 + (4+2k)s + (4+k) = 0.$$

| | | |
|-------|----------|-------|
| s^2 | $(1+k)$ | $4+k$ |
| s^1 | $(4+2k)$ | |
| s^0 | $k+4$ | |

$|k= -2| * \text{For Marginally Stable.}$
 $\hookrightarrow \text{it is invalid value.}$



$\therefore \xi < 1 | * \text{For all}$
 $\text{values of } k, \text{ system}$
 $\text{will be underdamped.}$

Ques:- ⑥ The OLTF of a system is : $G(s)H(s) = \frac{-k(s+1)^2}{(s+2)^2}$. Draw its

Root Locus and determine the range of K for system to be stable.

Ans:- ⑥ $s = -1, -2$ here.

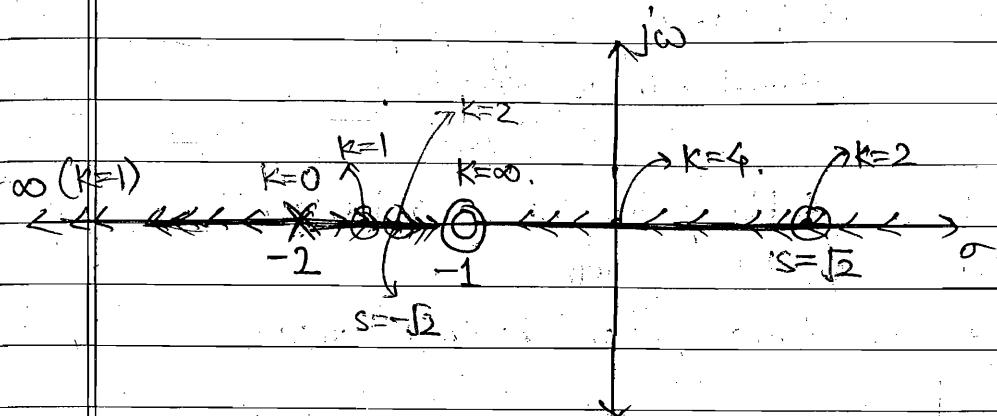
$$q(s) = (s+2)^2 - k(s+1)^2 = 0 = (1-k)s^2 + (4-2k)s + (4-k) = 0.$$

$\therefore 2k-4=0 \quad |k=2| * \text{For Marginally Stable.}$
 $\hookrightarrow \text{valid } k.$

$$s^2(1-k) + (4-k) = 0$$

$$\Rightarrow s^2(-1) + 2 = 0 \Rightarrow s^2 = +4$$

$$\cancel{s=\pm j1} \quad s=\sqrt{2}+\text{j}0$$



* Explanation :- $k = 0 \cdot 1$

$$0.9s^2 + 3.8s + 3.9 = 0 \Rightarrow s = -1.75, -2.46.$$

$$k = 0.5, \quad 0.5s^2 + 3s + 3.5 = 0$$

$$s = -1.58, -4.41.$$

$$k = 0.8, \quad 0.2s^2 + 2.4s + 3.2 = 0.$$

$$s = -1.52, -10.47.$$

$$k = 0,$$

$$0.1s^2 + 2.2s + 3.1 = 0.$$

$$s = -1.51, -20.48.$$

$$k = 1,$$

$$(2s+3) = 0, \quad s = -1.5.$$

$$k = 1.5, \quad -0.5s^2 + s + 2.5 = 0.$$

$$s = -1.44, +3.44.$$

$$k = 2, \quad -s^2 + 2 = 0$$

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

$$k = 4, \quad -3s^2 - 4s = 0. \Rightarrow s(3s+4) = 0$$

$$s = 0; -\frac{4}{3}.$$

$$K = 5, \quad -4s^2 - 6s - 1 = 0$$

$$s = -1.3, -0.19.$$

$\therefore 0 < K < 1$:- Stable system cum over-damped. ($\xi > 1$).

$1 < K < 4$:- Unstable system

$K > 4$:- Stable system and Over-damped. ($\xi > 1$).

Note:-

- The above case of switching root locus from $-\infty$ to $+\infty$ will exist only under one condition when in open loop transfer function, Order of Pole = Order of zero and feedback is Positive Feedback.

* A positive feedback system cannot be highly stable but Negative feedback system may be

* Positive feedback system may remain stable under finite range of K but it will always become unstable for range of K .

* A positive feedback system may be highly unstable.

Ques: (7) The OLTF of a system is: $G(s)H(s) = \frac{K(s+1)}{(s^2 + 0.4s + 0.4)}$, $0 < K < \infty$.

Draw its Root Locus and determine the value of K when system will be critically damped and also determine the range of K when system is under-damped and over-damped.

Aus: (7) $s_p = -0.2 \pm j0.6$, $s_z = -1$.

$$g(s) = 1 + G(s)H(s) = 0 \Rightarrow K = -\frac{(s^2 + 0.4s + 0.4)}{(s+1)}$$

$$\frac{dK}{ds} = -\frac{[(s+1)(2s+0.4) - (s^2 + 0.4s + 0.4)(1)]}{(s+1)^2}$$

$$s = 0, -2 \quad \therefore K|_{s=0} = -0.4$$

$$K|_{s=-2} = +ve. \rightarrow +\infty$$

$$\theta_0 = 180^\circ, \quad X = (-0.2 - 0.2) - (-1) \Rightarrow X = 0.6.$$

$$\text{Now, } \phi_d = 180^\circ - [\phi_p - \phi_z]$$

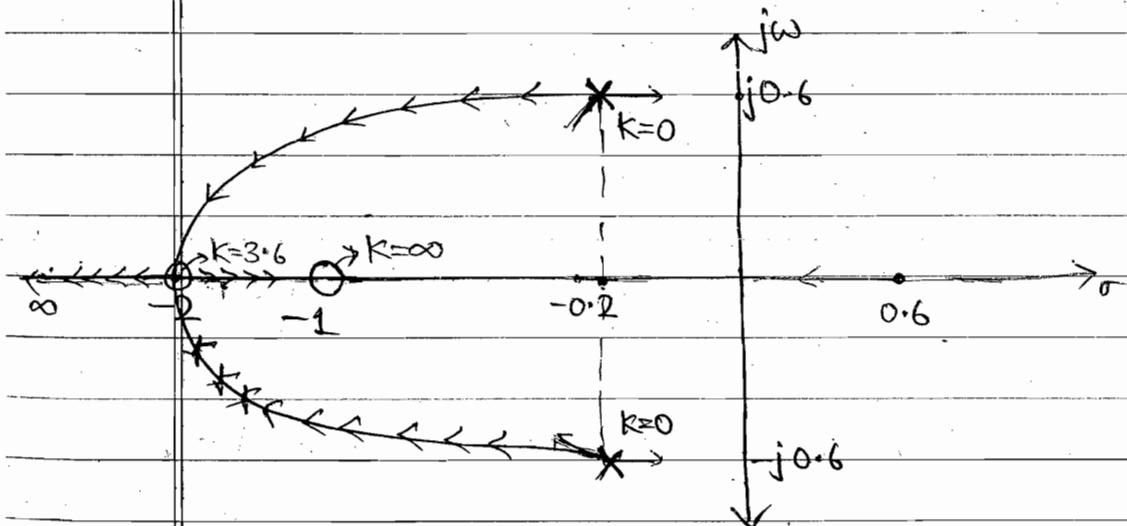
$$\phi_{d(2)} = 180^\circ - [90^\circ - 37^\circ] = 127^\circ$$

$$\phi_{d(1)} = -127^\circ$$

$$q(s) = s^2 + 0.4s + 0.4 + k(s+1) = 0$$

$$q(s) = s^2 + s(0.4 + k) + (0.4 + k) = 0.$$

$\therefore K = -0.4$ * for Marginally Stable.
 Invalid point.



$0 < K < 3.6 \therefore \zeta < 1$; Under-damped.

$K = 3.6 \therefore \zeta = 1$; Critically-damped.

$K > 3.6 \therefore \zeta > 1$; Over-damped.

Ques: 8) The open loop TF is $G(s)H(s) = \frac{-K(s+1)}{s^2 + 0.4s + 0.4}$, $0 < K < \infty$.

Plot its Root Locus and determine range of K for system to be stable.

Ans:- 8) $s_p = -0.2 \pm j0.6$, $C_2 = -1$.

$$\frac{dk}{ds} = 0 \Rightarrow s = -0.4, +0.36, |s=0, -2|$$

$$K|_{s=0} = -0.4$$

$$\theta_0 = 0^\circ, x = 0.6$$

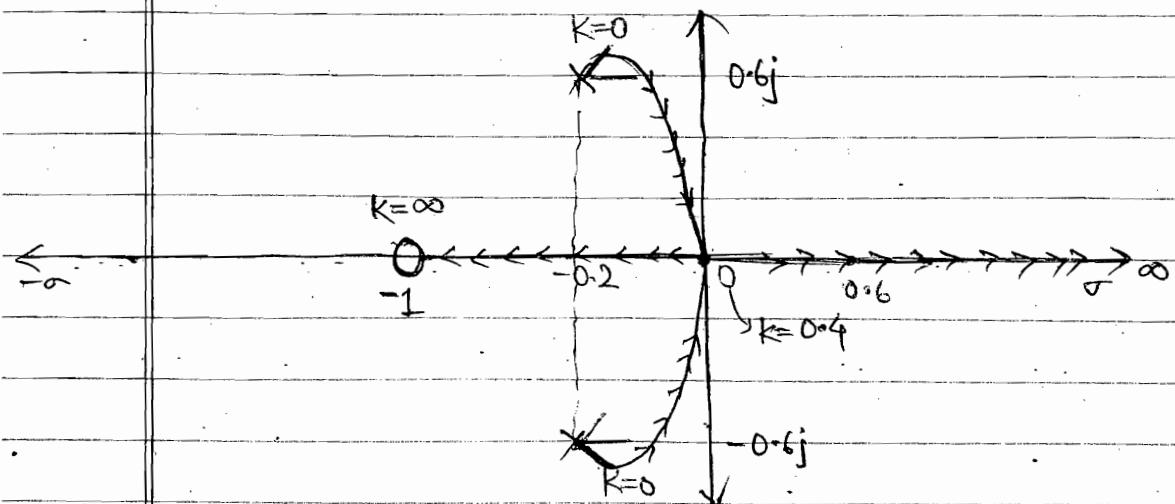
$$\theta_{d(2)} = 0 - [\phi_p - \phi_z] = -53^\circ$$

$$\theta_{d(1)} = 53^\circ$$

$$q(s) = s^2 + (0.4 + K)s + (0.4 + K) = 0$$

$\therefore K = 0.4$ * for Marginally Stable.
↓ valid K .

$\therefore s^2 + 0 = 0$ $s = 0$. [which is also breakpoint]



- * If any OLTF contains ~~zero~~ in the right-half side, then closed loop system will always become unstable for higher value of K .
- * If any OLTF contains ~~Pole~~ in the right-half side, then its closed loop system will always remain unstable for lower values of K .

Ques:- 9) The OLTF of a system is: $G(s)H(s) = \frac{K}{s(s+4)(s^2+4s+13)}$. Draw its

Root Locus and determine the value of K for system to be Marginally Stable. Also, calculate undamped Natural frequency.

Ans:- 9) $s_p = 0, -4, -2 \pm j(1.57)$, $-K = s(s+4)(s^2+4s+13)$

$$s = -2 ; s = -2 \pm j(1.57)$$

- For break-away point, to calculate it from complex-poles, use Angle condition.

$$\phi = -90^\circ + 90^\circ + \tan^{-1}\left(\frac{1.57}{2}\right) + 180^\circ - \tan^{-1}\left(\frac{1.57}{2}\right) = 180^\circ$$

As $\phi = \text{odd multiple of } 180^\circ$, so, $s = -2 \pm j(1.57)$ may be the break-point.

$$\theta_0 = 45^\circ, \theta_1 = 135^\circ, \theta_2 = 225^\circ, \theta_3 = 315^\circ$$

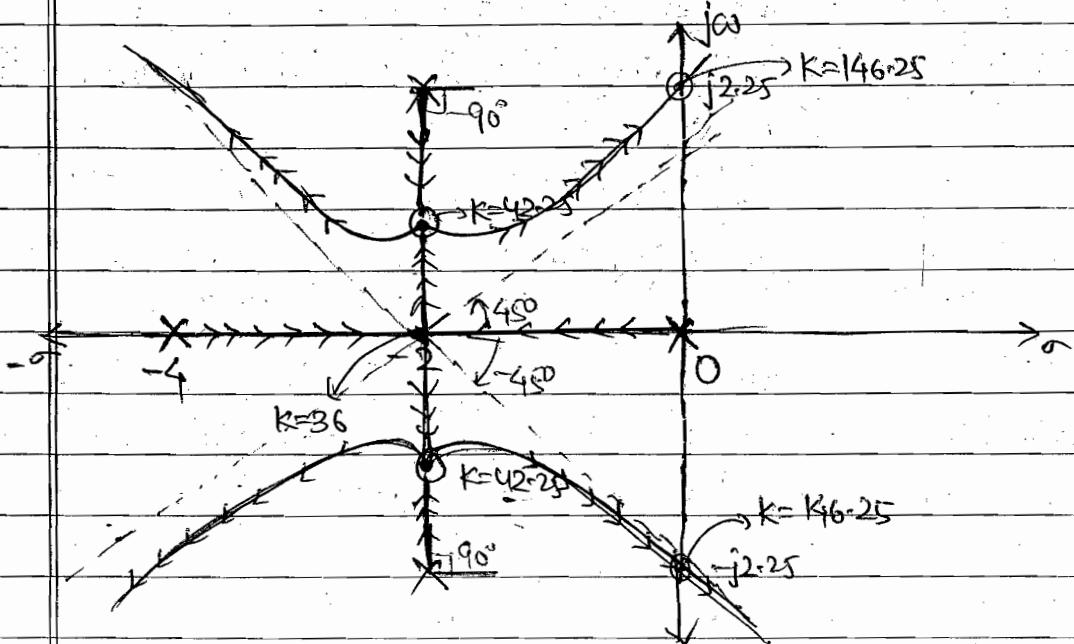
$$x = \frac{-8-0}{4-0} = -2$$

$$\phi_d = 180^\circ - [\phi_p - \phi_z] = 180^\circ - [270^\circ - 0^\circ] = -90^\circ$$

$$q(s) = (s^2+4s)(s^2+4s+13) + K = 0$$

$$\therefore K = 145.25 * (\text{For Marginally Valid stable})$$

$$s = \pm j2.55.$$



Ques: (10) The OLTF is : $G(s)H(s) = \frac{-K}{s(s+4)(s^2+4s+13)}$, $0 < K < \infty$. Draw its

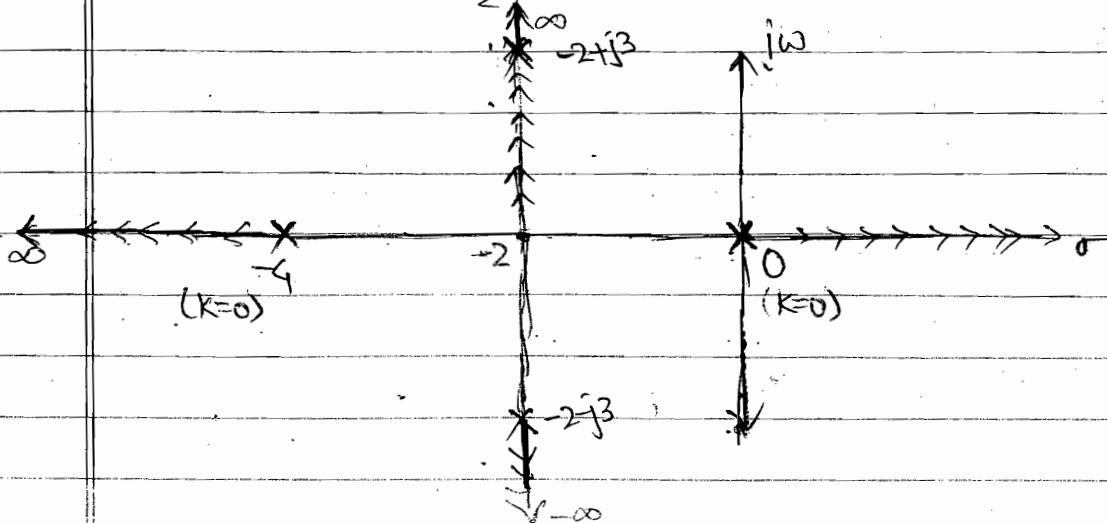
Root Locus and comment on stability.

Ans: (10) $s = -2 ; -2 \pm j(1.57)$.

$$\theta_0 = 0^\circ, \theta_1 = 90^\circ, \theta_2 = 180^\circ, \theta_3 = 270^\circ.$$

$$x = -2, \theta_{d_1} = 0 - [\phi_p - \phi_z] = -270^\circ \equiv +90^\circ.$$

$$\theta_{d_2} = -90^\circ.$$



Ques:- 11) The closed loop transfer function of a system is:

$$\frac{C(s)}{R(s)} = \frac{1}{s^2 + (4-K)s + 3}$$

Draw its Root locus.

Ans:- 11)

$$\frac{C(s)}{R(s)} = \frac{1}{(s^2 + 4s + 3) + (-Ks)}$$

$$\Rightarrow \frac{C(s)}{R(s)} = \frac{1/(s^2 + 4s + 3)}{\left[1 + \frac{s - Ks}{(s+1)(s+3)} \right]}$$

∴ Comparing, $G(s) = \frac{1}{(s+1)(s+3)}$, $H(s) = -Ks$.

$$G(s)H(s) = \frac{-Ks}{(s+1)(s+3)}$$

Now, $s_p = -1, -3$, $s_z = 0$.

$$\Theta_0 = 0^\circ \quad , \quad K = \frac{(s+1)(s+3)}{s}$$

$$\Rightarrow \frac{dk}{ds} = 0 \Rightarrow \frac{dk}{ds} = 0$$

$\therefore s = \pm \sqrt{3}$ (valid).

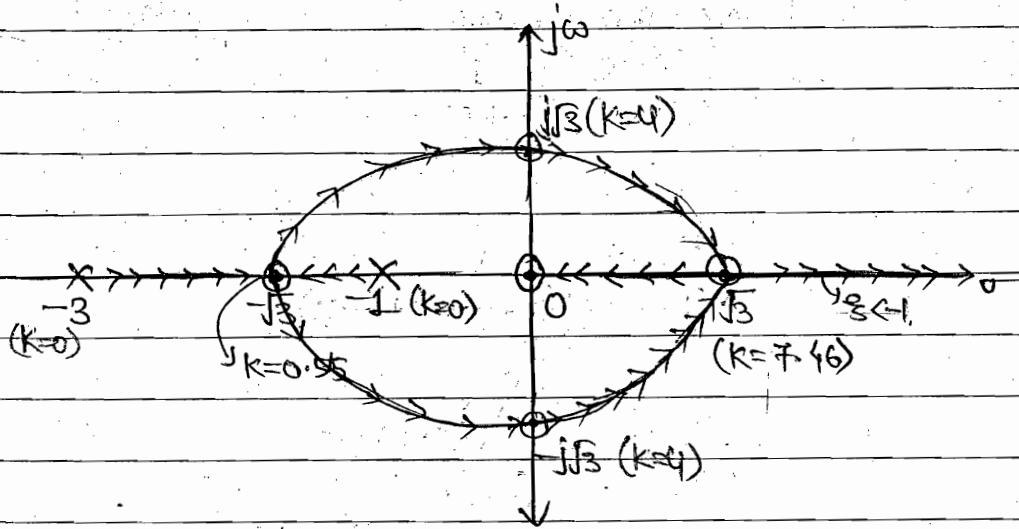
$$\therefore K|_{s=\sqrt{3}} = \frac{+(\sqrt{3}+1)(\sqrt{3}+3)}{\sqrt{3}} = +7.46. \text{ (valid)}$$

$$K|_{s=-\sqrt{3}} = \frac{(-\sqrt{3}+1)(-\sqrt{3}+3)}{-\sqrt{3}} = 0.55. \text{ (valid)}$$

$$X = \frac{-4-0}{1} = -4.$$

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

$$\text{Here, } \omega_n = \sqrt{3}, \xi \omega_n = \frac{(4-K)}{2} \text{ or } \xi = \frac{(4-K)}{2\sqrt{3}}$$



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

$\therefore 4-K=0 \Rightarrow K=4$ * For Marginally Stable,
(Valid).

$$s^2 + 3 = 0, \quad s = \pm j\sqrt{3}, \quad \omega_n = \sqrt{3} \text{ rad/sec.}$$

- Here, as ω_n is variable, ξ_{ω_n} is variable and ξ is also variable, \therefore system is Unstable.

$0 < K < 0.55 : \xi > 1 ;$ over-damped.

$0.55 < K < 4 : \xi < 1 ;$ under-damped.

~~$K > 4$~~ ; ~~$\xi < -1$~~ ; $\xi < -1$; (unstable)

$K = 0.55 ; \xi = 1 ;$ critically damped.

$K = 7.46 ; \xi = -1 ;$ (unstable)

$4 < K < 7.46 ; \xi < -1 ;$ (unstable).

* System will be unstable but can't be highly stable.

Ques: (12) The OLTF is: $G(s)H(s) = \frac{K\omega_n^2}{s(s+2\zeta\omega_n)}$, $0 < K < \infty$.

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Ans: (12) $s_p = 0, -2\zeta\omega_n$.

or $K = \frac{-s(s+2\zeta\omega_n)}{\omega_n^2}$

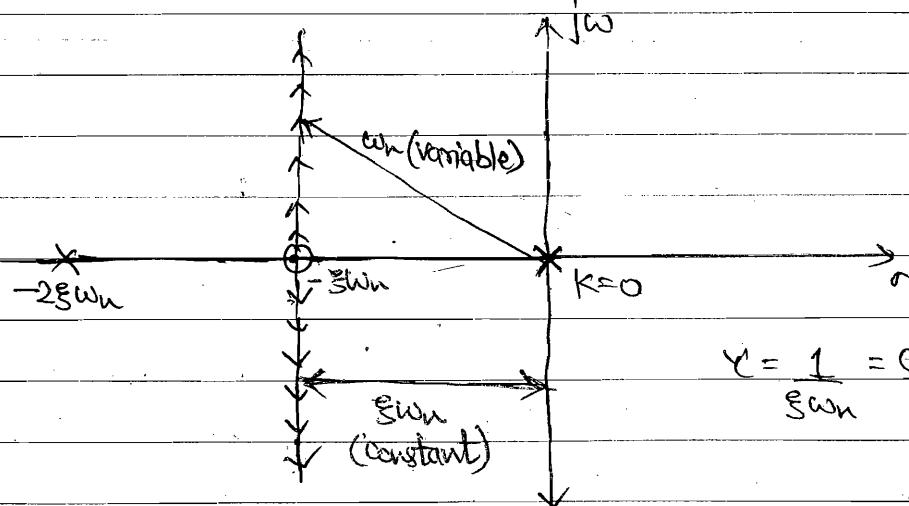
$\therefore \frac{dk}{ds} = 0,$

$s = -\zeta\omega_n \therefore K|_{s=-\zeta\omega_n} = \xi^2.$

$\theta_K = \frac{(2k+1)180^\circ}{P-Z} \Rightarrow K=0, 1$

$\therefore \theta_0 = 90^\circ, \theta_1 = 270^\circ.$

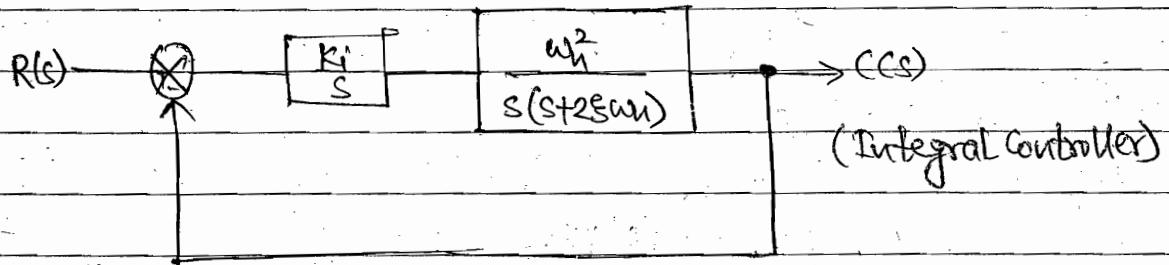
$\chi = \sum_{P-Z} -\zeta\omega_n$



$\gamma = \frac{1}{\zeta\omega_n} = \text{constant.}$

So, system will be always highly stable.

→ Understanding PI controller with Root Locus

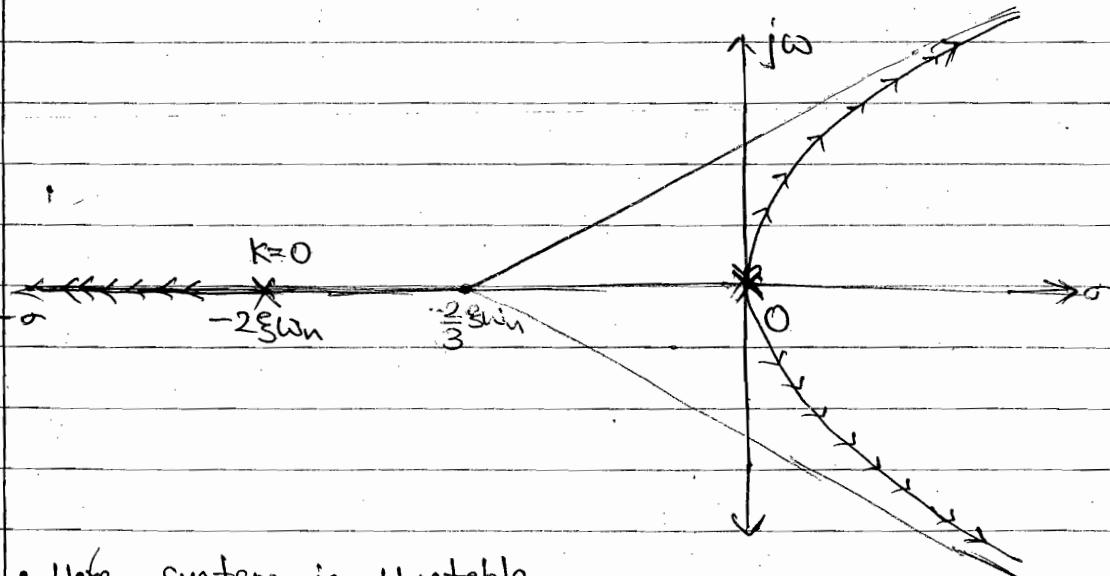


$$G(s)H(s) = \frac{K_i \cdot w_n^2}{s^2(s+2s_w_n)}$$

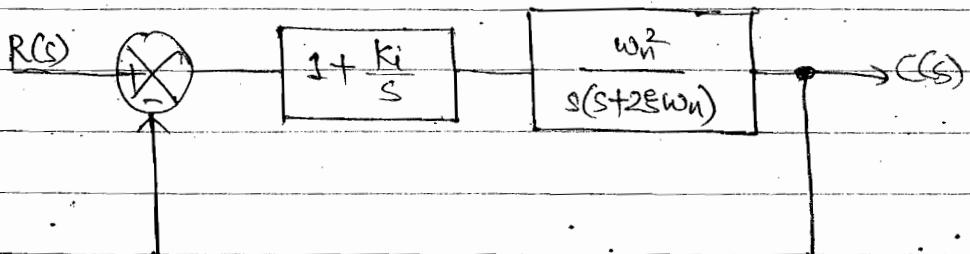
Here, $s_{\text{break}} = 0$, $K_i = 0$
 $s_{B=0}$

$$\theta_0 = 60^\circ, \theta_1 = 180^\circ, \theta_2 = 300^\circ [K=0,1,2 \text{ here}]$$

$$\alpha = \frac{2}{3} s_w n$$



- Here, system is Unstable.
 So, to overcome this, we use PI controller.



$$\therefore G(s)H(s) = \frac{(s+k_i)\omega_n^2}{s^2(s+2\zeta\omega_n)}$$

Its, closed Loop Transfer function is:

$$T(s) = \frac{(s+k_i)\omega_n^2}{(s^3 + 2\zeta\omega_n s^2 + \omega_n^2 s) + k_i \omega_n^2}$$

$$\text{Now, } T(s) = \frac{\frac{(s+k_i)\omega_n^2}{s^3 + 2\zeta\omega_n s^2 + \omega_n^2 s}}{1 + \frac{k_i \omega_n^2}{s[s^2 + 2\zeta\omega_n s + \omega_n^2]}}$$

$$\therefore G(s)H(s) = \frac{k_i \cdot \omega_n^2}{s[s^2 + 2\zeta\omega_n s + \omega_n^2]}$$

$$\text{Here, } s_p = 0, -\zeta\omega_n \pm j\omega_n\sqrt{1-\zeta^2}$$

$$\frac{dk_i}{ds} = 0 \Rightarrow s = \text{Invalid break-point.}$$

$$\theta_0 = 60^\circ, \theta_1 = 180^\circ, \theta_2 = 300^\circ$$

$$x = -\frac{2}{3}\zeta\omega_n \text{ (Centroid).}$$

Using R-H Criterion: $q(s) = s^3 + 2\zeta\omega_n s^2 + \omega_n^2 s + k_i \omega_n^2 = 0$.

$$\begin{array}{c|cc} s^3 & 1 & \omega_n^2 \\ s^2 & 2\zeta\omega_n & k_i \omega_n^2 \\ s^1 & \frac{2\zeta\omega_n^3 - k_i \omega_n^2}{2\zeta\omega_n} & \\ s^0 & k_i \omega_n^2 & \end{array} \Rightarrow (2\zeta\omega_n - k_i) \omega_n^2 = 0$$

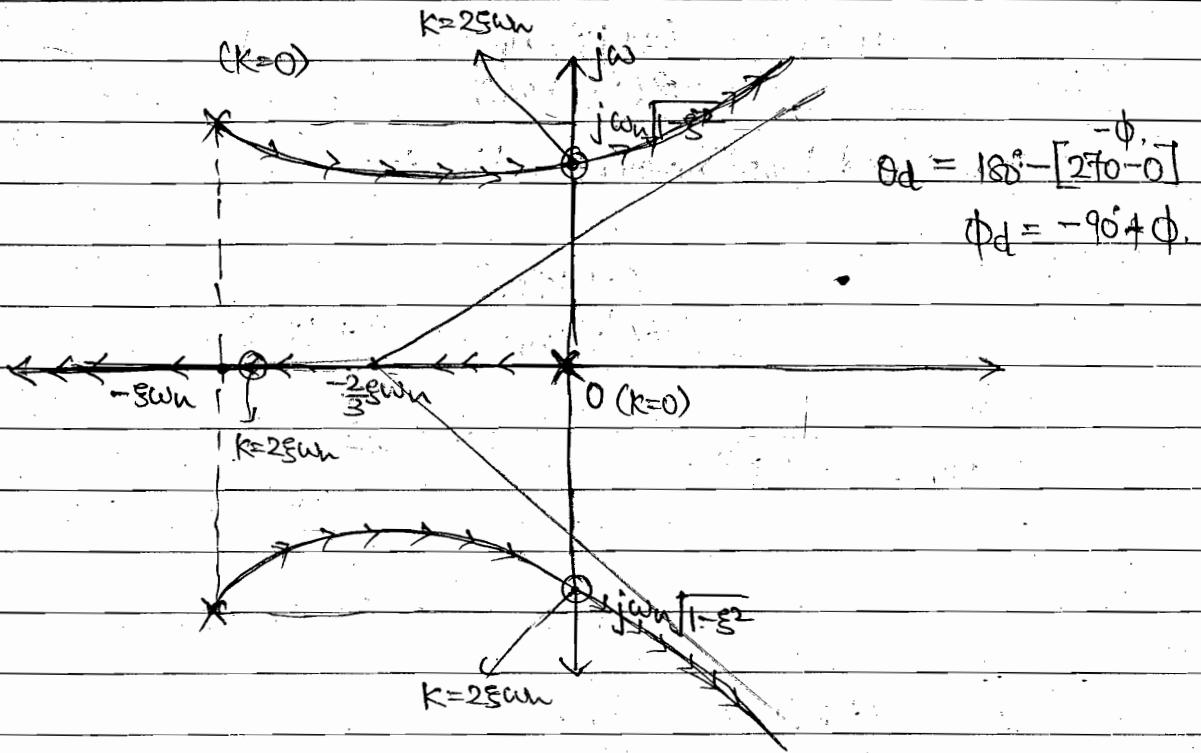
$\omega_n = 0, ; \omega_n = \frac{k_i}{2\zeta}$

$$\Rightarrow k_i = 2\zeta\omega_n$$

$$\therefore 2\zeta\omega_n s^2 + k_i \omega_n^2 = 0$$

$$\Rightarrow 2\zeta\omega_n s^2 = -k_i \omega_n^2 = -2\zeta\omega_n^3$$

$$s = \pm j\omega_n *$$



$0 < K < 2\omega_n$:- Stable system

$K = 2\omega_n$:- Marginally stable system

$K > 2\omega_n$:- Unstable system.

Chapter :- 8

NYQUIST PLOT

** In Nyquist Plot, the variable is entire s-plane while in Bode-plot, variable is positive frequency line.

- If Open Loop Transfer function is Minimum Phase system, then for closed loop system to be stable (Minimum phase), both Gain Margin and Phase Margin should be Positive.
- If Open Loop TF is Non-minimum phase system (unstable system), then for closed loop system to be stable, both Gain Margin and Phase Margin should be Negative.

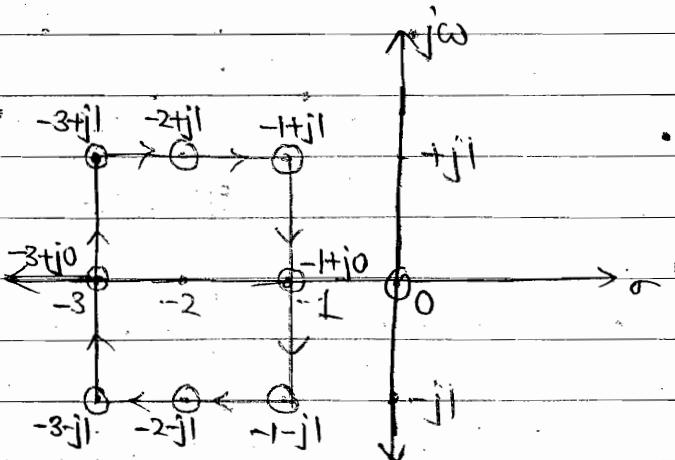
* Bode-plot defines only Relative Stability while Nyquist Plot defines both Absolute as well as Relative Stability.

* Gain Margin and Phase Margin calculated from Bode-plot is approximate GM and PM while Gain Margin and Phase Margin calculated from Nyquist Plot is Exact GM and PM.

\Rightarrow $G(s)H(s)$ PLANE

- Consider an Arbitrary plane:

$$\text{Let } G(s)H(s) = \frac{K}{(s+2)}$$



$$\left. G(s)H(s) \right|_{s=-3+j1} = \frac{1}{s(-3+j1)+2j} = \frac{1}{(-1+j1)} = \frac{1}{\sqrt{2}} \left[-\tan^{-1}\left(\frac{1}{1}\right) \right]$$

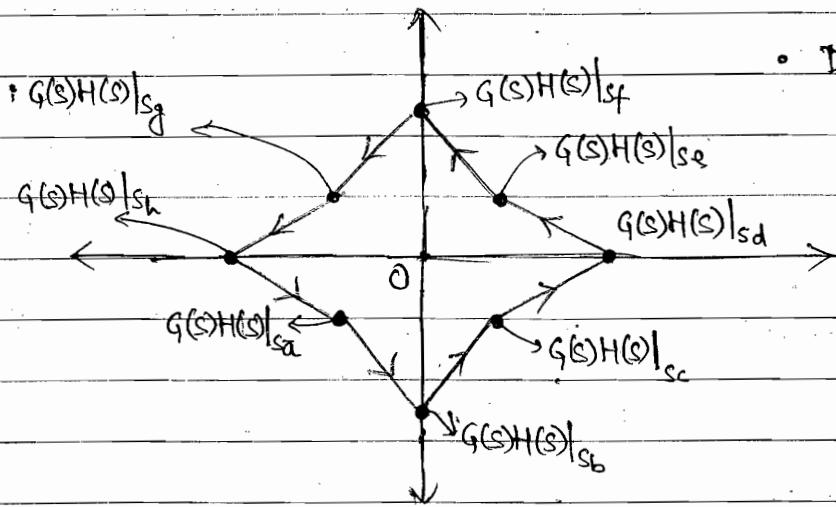
$$= \frac{1}{\sqrt{2}} \left[-135^\circ \text{ or } +225^\circ \right].$$

$$\left. G(s)H(s) \right|_{s=-2+j1} = \frac{1}{s(-2+j1)+2j} = \frac{1}{(-1+j1)} = \frac{1}{\sqrt{2}} \left[-\tan^{-1}(1) \right] = \frac{1}{\sqrt{2}} \left[-90^\circ \right].$$

$$\left. G(s)H(s) \right|_{s=-1+j1} = \frac{1}{s(-1+j1)+2j} = \frac{1}{(1+j1)} = \frac{1}{\sqrt{2}} \left[-45^\circ \right].$$

$$\left. G(s)H(s) \right|_{s=-1+j0} = \frac{1}{s(-1+j0)+2j} = \frac{1}{-1+2j} = 170^\circ.$$

$$\left. G(s)H(s) \right|_{s=-1-j1} = \frac{1}{s(-1-j1)+2j} = \frac{1}{(1-j1)} = \frac{1}{\sqrt{2}} \left[45^\circ \right].$$



- Diverging graph is because of Pole as pole makes TF infinite.

- For one pole encirclement in clockwise direction on s-plane, $G(s)H(s)$ plane will traverse one encirclement in Anti-clockwise direction.

$$(ii) G(s)H(s) = (s+2)$$

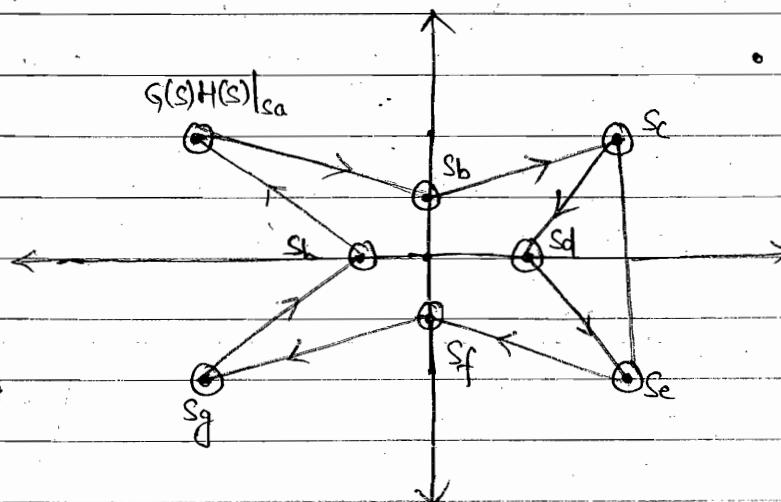
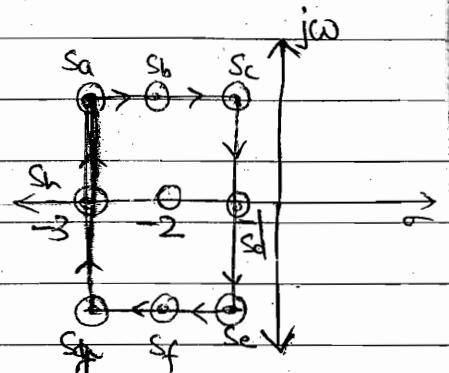
$$G(s)H(s) \Big|_{s_a=-3+j1} = (-3+j1+2) = \sqrt{2} \angle +135^\circ \text{ or } (-225^\circ)$$

$$G(s)H(s) \Big|_{s_b=-2+j1} = (-2+j1)+2 = 1 \angle 90^\circ$$

$$G(s)H(s) \Big|_{s_c=-1+j1} = (-1+j1)+2 = \sqrt{2} \angle 45^\circ$$

$$G(s)H(s) \Big|_{s_d=-1+j0} = (-1)+2 = 1 \angle 0^\circ$$

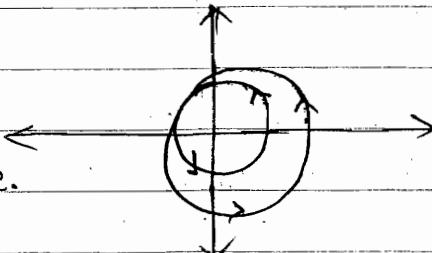
$$G(s)H(s) \Big|_{s_e=-1-j1} = (-1-j1)+2 = \sqrt{2} \angle -45^\circ$$



- Zero will have converging graph as it makes TF zero.

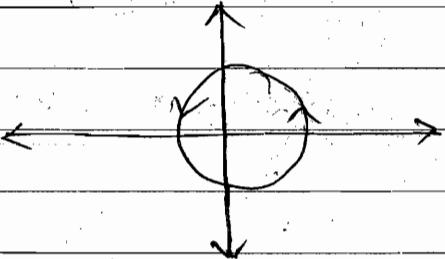
$$(ii) G(s)H(s) = \frac{1}{(s+2)(s+5)}$$

- As two poles are there,
so, two encirclements
in Anti-clockwise
directions will be there.



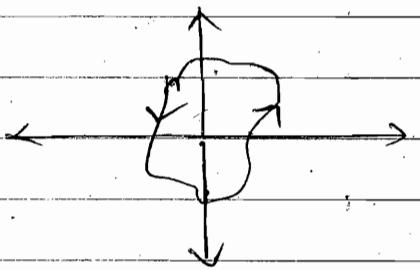
$$(iv) G(s)H(s) = \frac{(s+5)}{(s+2)(s+2.5)}$$

- As one zero and one-pole encirclements will get cancelled
so, anti-clockwise direction of one pole will remain in graph.

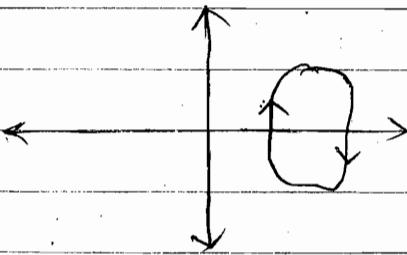


$$(v) G(s)H(s) = \frac{1}{(s+2)(s+4)}$$

- As chosen contour does not contain pole $s=-4$ in it. so, only one encirclement is there i.e due to $s=-2$ pole.



$$(vi) G(s)H(s) = \frac{s+1.5}{s+2.5}$$



- * Here, net encirclement around origin is 0, so encirclement will not there about origin.
- * Direction, here, is clockwise direction as origin, pole is far away. So, zero will be dominant.

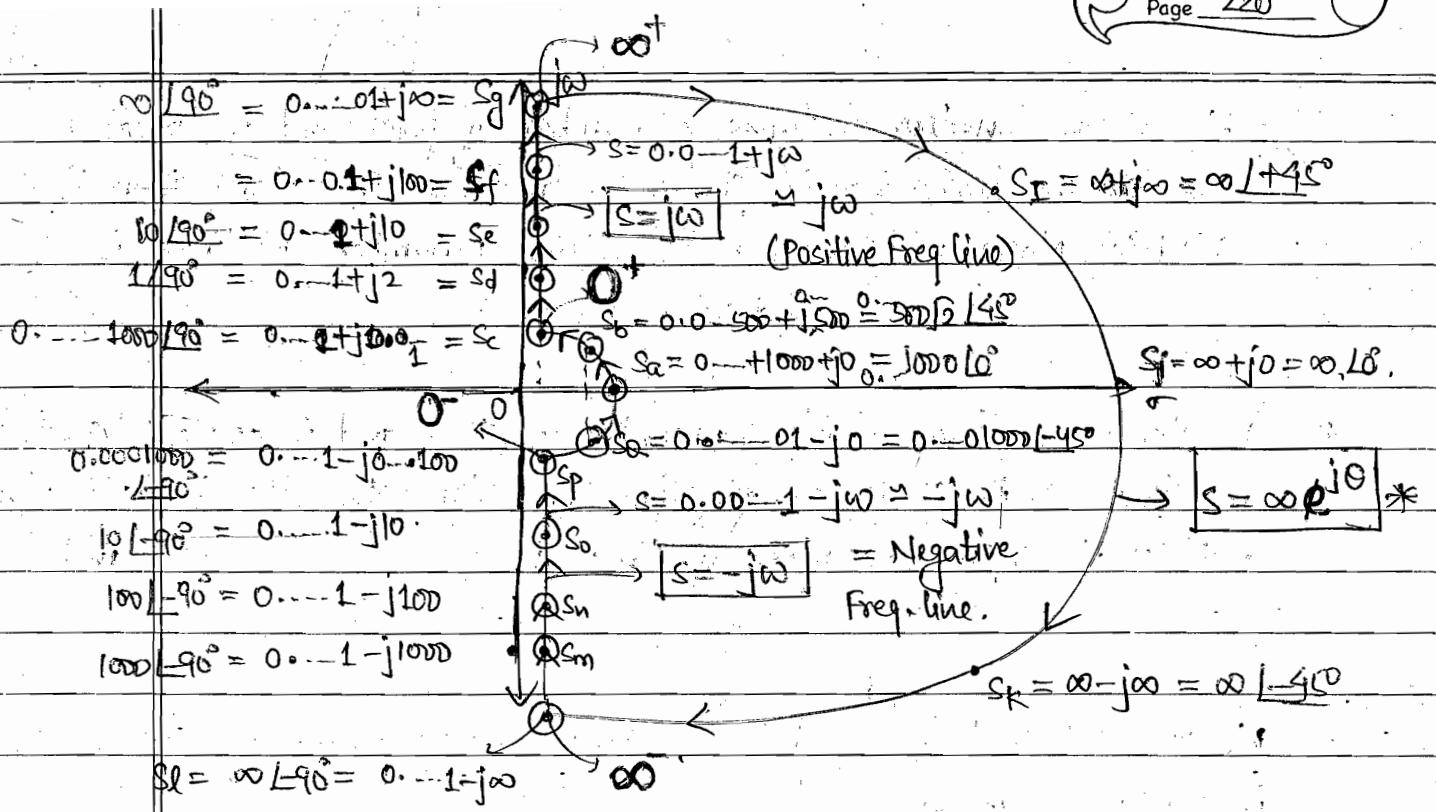
- * If chosen contour contains p -number of poles and in specified contour on traversing in clockwise direction in s -plane, then its $G(s)H(s)$ plane will encircle its origin p -number of times in Anti-clockwise direction and vice-versa.
- * If chosen contour contains z -number of zeros and in specified contour, we traverse in clockwise direction in s -plane, then its $G(s)H(s)$ plane encircles its origin z -number of times in Clockwise direction and vice-versa.
- * If specified contour ^{contains} p -number of poles and z -number of poles and in specified contour, on traversal in clockwise direction in s -plane, then its $G(s)H(s)$ plane encircles its origin $(p-z)$ times in Anti-clockwise direction ($p>z$) and $(z-p)$ times in clockwise direction.
- * Clockwise encirclement will be taken as negative while Anti-clockwise encirclement will be taken as positive.

\rightarrow Generalized Specified Contour:

$$s = \sigma + j\omega \quad (\text{In Rectangular})$$

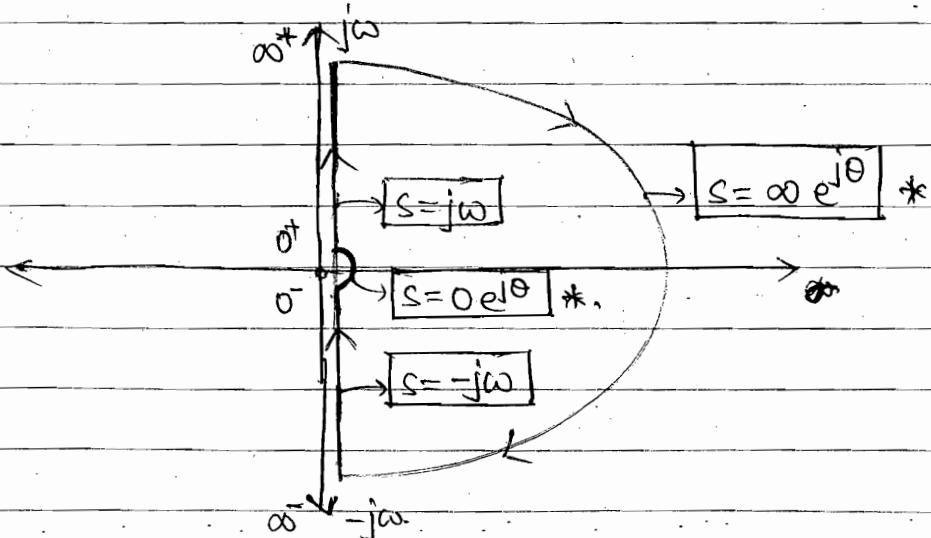
$$\gamma = \sqrt{\sigma^2 + \omega^2} ; \quad \theta = \tan^{-1}(\omega/\sigma).$$

$$s = \gamma e^{j\theta} \quad (\text{In Polar Form}).$$



Here, $0^+ \Rightarrow 0$ represents $0.0 \dots 1000$
 $+ \text{ represents Positive Frequency line}$

* Origin is not included as pole at origin does not show instability of system. System is Marginally stable when pole is at origin.



$$(s = j\omega) \Rightarrow (s = 0^+) \text{ to } (s = \infty^+) \Rightarrow G(s)H(s)|_{s=0^+} \rightarrow G(s)H(s)|_{s=\infty}$$

$$(s = \infty e^{j0}) \Rightarrow (s = \infty^+) \text{ to } (s = \infty^-) \Rightarrow G(s)H(s)|_{s=\infty^+} \rightarrow G(s)H(s)|_{s=\infty^-}$$

$(s = -j\omega) \Rightarrow (s = \infty^-)$ to $(s = 0^-) \Rightarrow G(s)H(s)|_{s=\infty^-}$ to $G(s)H(s)|_{s=0^-}$

$(s = 0e^{j0}) \Rightarrow (s = 0^-)$ to $(s = 0^+) \Rightarrow G(s)H(s)|_{s=0^-}$ to $G(s)H(s)|_{s=0^+}$.

$\Rightarrow (s = j\omega)$ and $(s = -j\omega)$ will be Mirror Image about real axis.

* Relation between Open Loop Transfer Function, characteristics Equation and Closed Loop Transfer function.

$$\text{say, } G(s)H(s) = \frac{s+1}{s+5}.$$

$$\therefore s_{z_0} = -1, \quad s_{p_0} = -5.$$

$$q(s) = \frac{2s+6}{s+5}$$

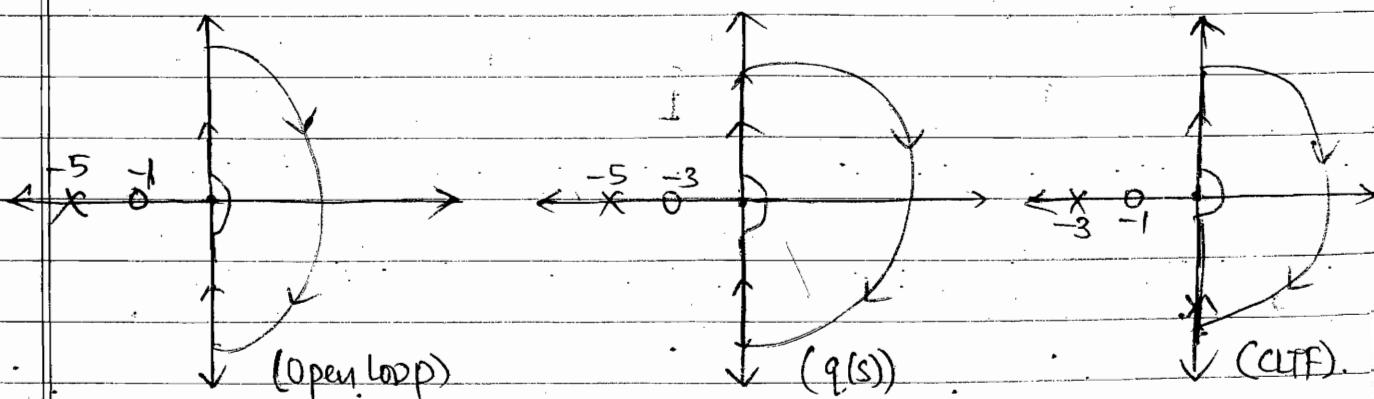
$$s_{p_c} = -5, \quad s_{z_c} = -3.$$

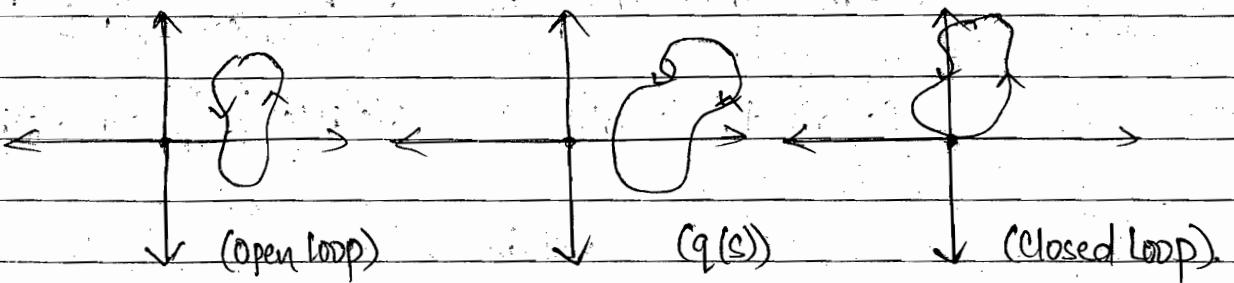
$$T(s) = \frac{G(s)}{1+G(s)H(s)} = \frac{(s+1)}{2s+6}.$$

$$s_{p_T} = -3, \quad s_{z_T} = -1$$

$\therefore [s_{p_0} = s_{p_c}] * \therefore \text{Open loop pole} = \text{Pole of characteristics Equation.}$

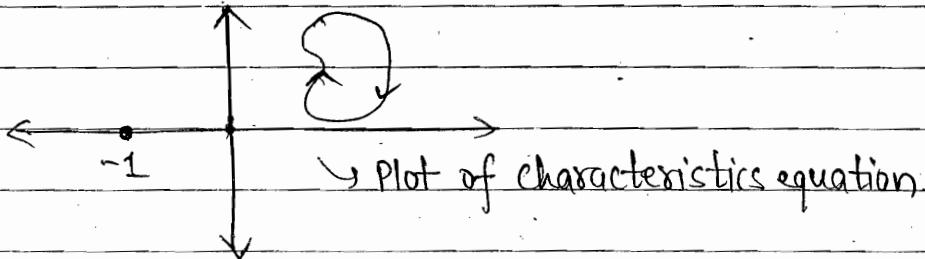
$[s_{z_c} = s_{p_T}] * \therefore \text{Zero of characteristics Equation} = \text{Pole of closed loop TF.}$



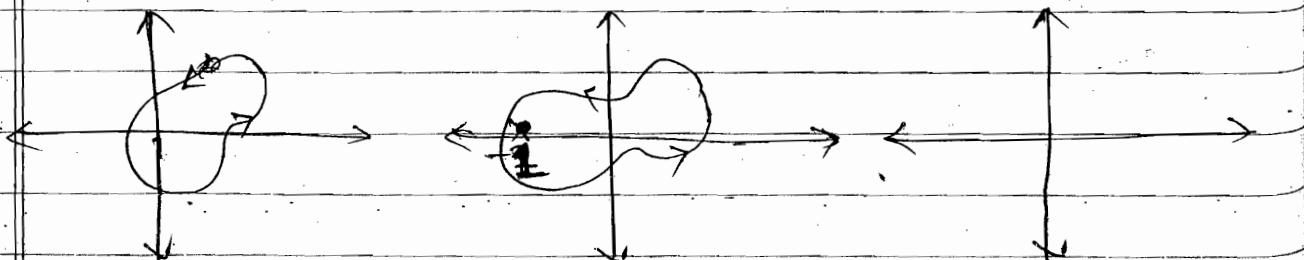
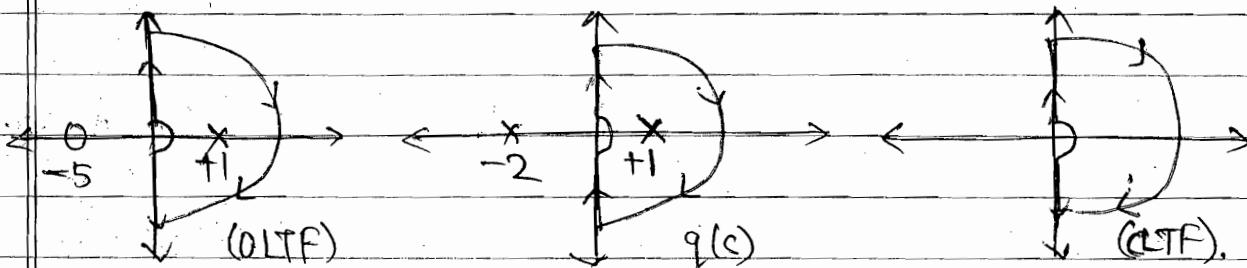


→ Poles and zeros encircle origin only as to calculate pole or zero locations, we put or equate them to 0.

$$G(s)H(s) = -1$$



* Example:- $\frac{s+5}{(s-1)} = G(s)H(s)$.



$$N = P_f - Z_f *$$

where P_f = Total number of poles in OLTTF which is lying in the right-half side of Imaginary axis and this pole itself is pole of characteristics equation.

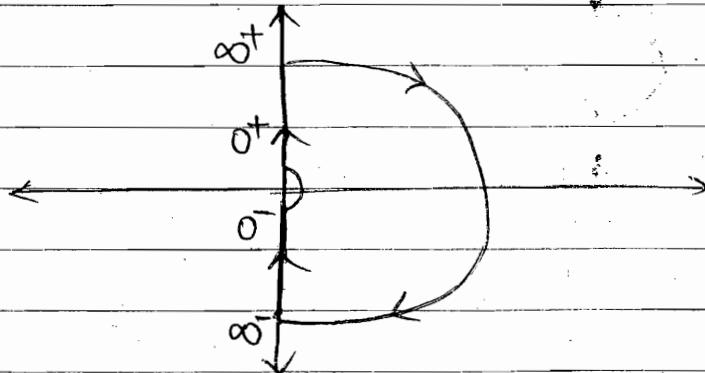
Z_f = Total number of zeros in characteristics equation which is lying in the right half-side of Imaginary axis and this zero itself is pole of closed Loop TF which is lying in the right-half side of s-plane and for closed loop system to be stable,

N = Total number of Encirclement of $(-1, 0)$ point.

- * For clockwise encirclement, N should be Negative.
For Anti-clockwise, encirclement, N will be Positive.

* Closing of Nyquist Plot :

- * Case-I: If Origin contains n number of poles of Open loop Transfer Function :



$$(s=0^+) \rightarrow (s=\infty^+) \Rightarrow G(0^+)H(0^+) \rightarrow G(\infty^+)H(\infty^+).$$

$$(s=\infty^+) \rightarrow (s=\infty^-) \Rightarrow G(\infty^+)H(\infty^+) \rightarrow G(\infty^-)H(\infty^-).$$

$$(s=\infty^-) \rightarrow (s=0^-) \Rightarrow G(\infty^-)H(\infty^-) \rightarrow G(0^-)H(0^-).$$

$$(s=0^-) \rightarrow (s=0^+) \Rightarrow G(0^-)H(0^-) \rightarrow G(0^+)H(0^+).$$

- In this case, then $G(\omega^+)H(\omega^+)$ and $G(\omega^-)H(\omega^-)$ will be short-circuited while $G(\omega^-)H(\omega^+)$ and $G(\omega^+)H(\omega^+)$ will be open-circuited. To close the Nyquist plot from $G(\omega^-)H(\omega^-)$ to $G(\omega^+)H(\omega^+)$, we will make (nT) clockwise encirclement with radius of encirclement = ∞ where ' n ' is total number of poles in OLTF located at origin.

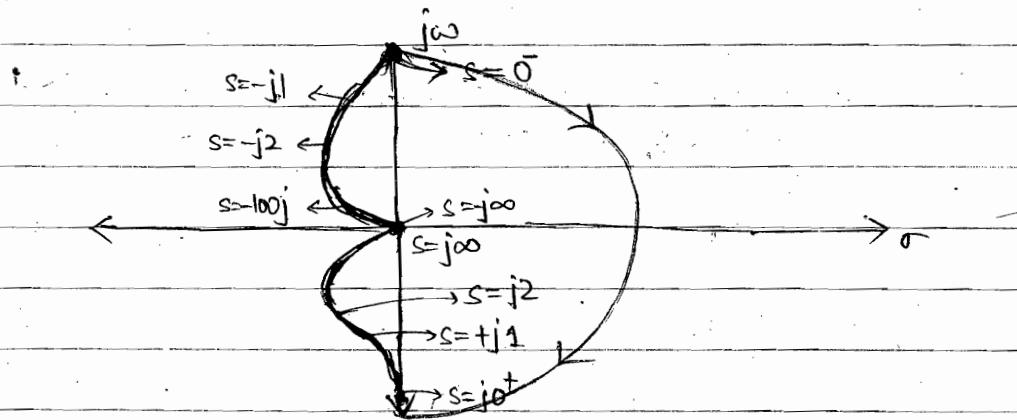
* Example:- $G(s)H(s) = \frac{1}{s(s+1)}$

$$\Rightarrow \text{Put } s=j\omega, G(s)H(s)|_{s=j\omega} = \frac{1}{j\omega(j\omega+1)} = \frac{1}{\omega \sqrt{1+\omega^2}} [-90^\circ - \tan^{-1}(\omega)]$$

$$G(s)H(s)|_{s=j0} = \frac{1}{0} [-90^\circ] = \infty [-90^\circ]$$

$$G(s)H(s)|_{s=j1} = \frac{1}{\sqrt{2}} [-135^\circ]$$

$$G(s)H(s)|_{s=j2} = \frac{1}{2\sqrt{5}} [-153^\circ]$$



* Example:- $G(s)H(s) = \frac{K}{s^n}$

$$\Rightarrow \text{Put } s = re^{j\theta}$$

$$G(s)H(s)|_{s=re^{j\theta}} = \frac{K}{(re^{j\theta})^n} = \frac{K}{r^n} e^{-jn\theta}$$

• At Initial point, $s = 0e^{-90^\circ}$

$$\therefore G(s)H(s) \Big|_{s=0e^{-90^\circ}} = K \cdot e^{\frac{-j\pi(90)}{n}} = \infty \cdot e^{j90^\circ} = \infty / (90^\circ n)$$

• At Final point, $s = 0e^{+90^\circ}$,

$$G(s)H(s) \Big|_{s=0e^{+90^\circ}} = K \cdot e^{\frac{-j(n90)}{n}} = \infty / -(90^\circ n)$$

∴ Change in phase angle of s from Initial point to Final point:
 $= |s_f - s_i| = +90^\circ - (-90^\circ) = 180^\circ$.

or change in phase angle of $G(s)H(s)$ from Initial point to Final point : $|G_f - G_i| = (-n90^\circ) - (+n90^\circ) = -180^\circ(n)$.

Again :- $G(s)H(s) = \frac{1}{s(s+1)}$

$$G(0e^{j\theta}) H(0e^{j\theta}) = \frac{1}{0e^{j\theta}[0e^{j\theta}+1]}$$

$$G(s)H(s) \Big|_{s=0e^{j\theta}} = \frac{1}{0e^{j\theta}} = \infty / e^{(j\theta)} = \infty / -0^\circ$$

$$\therefore \text{When } \theta = -90^\circ, G(s)H(s) \Big|_{s=0e^{-j90^\circ}} = \infty / 90^\circ$$

$$\text{and } G(s)H(s) \Big|_{s=0e^{-j45^\circ}} = \infty / 45^\circ$$

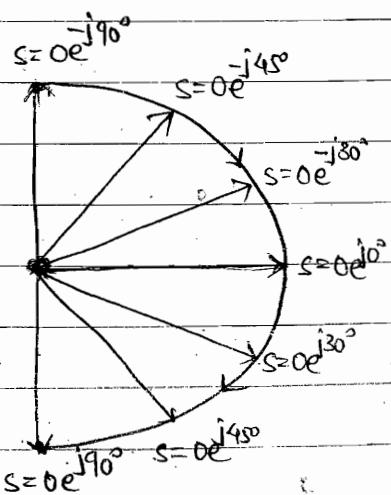
$$\text{and } G(s)H(s) \Big|_{s=0e^{-j30^\circ}} = \infty / 30^\circ$$

$$G(s)H(s) \Big|_{s=0e^{j0^\circ}} = \infty / 0^\circ$$

$$G(s)H(s) \Big|_{s=0e^{j30^\circ}} = \infty / -30^\circ$$

$$G(s)H(s) \Big|_{s=0e^{j45^\circ}} = \infty / -45^\circ$$

$$G(s)H(s) \Big|_{s=0e^{j90^\circ}} = \infty / -90^\circ$$



Now, put $s = \infty e^{j\theta}$

$$\therefore G(s)H(s) \Big|_{s=\infty e^{j\theta}} = \frac{1}{(\infty e^{j\theta})(\infty e^{j\theta} + 1)} = \frac{1}{\infty^2} e^{-j2\theta} = 0 \angle -20^\circ.$$

$$\therefore G(s)H(s) \Big|_{s=\infty e^{j90^\circ}} = 0 \angle -180^\circ$$

$$G(s)H(s) \Big|_{s=\infty e^{j45^\circ}} = 0 \angle -90^\circ.$$

$$G(s)H(s) \Big|_{s=\infty e^{-j90^\circ}} = 0 \angle 180^\circ.$$

- These all are just points on origin.

* If Magnitude is ∞ and phase is varying, this will be the closing condition of $G(s)H(s) \Big|_{s=0^+}$ and $G(s)H(s) \Big|_{s=0^-}$.

* If Magnitude is 0 and phase is varying, this will be the shorting condition of $G(s)H(s) \Big|_{s=\infty^+}$ and $G(s)H(s) \Big|_{s=\infty^-}$.

Case: II:

Order of zero is greater than order of pole

- In this case,

$G(s)H(s) \Big|_{s=0^+}$ and $G(s)H(s) \Big|_{s=0^-}$ will be short-circuit and

$G(\infty^+)H(\infty^+)$ and $G(\infty^-)H(\infty^-)$ will be open-circuited and to close the Nyquist Plot from $G(s)H(s) \Big|_{s=\infty^+}$ to $G(s)H(s) \Big|_{s=\infty^-}$, we will make $(m-n)\pi$ clockwise encirclements with radius of encirclement = ∞ , where 'm' is order of zeros, 'n' is order of poles.

* Consider :- $G(s)H(s) = \frac{(sT_1 + 1)^m}{(sT_2 + 1)^n}$, $m > n$

• Put $s = re^{j\theta}$, $G(s)H(s)|_{s=re^{j\theta}} = \frac{K [(re^{j\theta})T_1 + 1]^m}{[(re^{j\theta})T_2 + 1]^n}$

At Initial point; $s = \infty e^{j90^\circ}$

$$\therefore G(s)H(s)|_{s=\infty e^{j90^\circ}} = \frac{K [(\infty e^{j90^\circ})T_1 + 1]^m}{[(\infty e^{j90^\circ})T_2 + 1]^n} \\ = K (\infty)^{m-n} e^{j90^\circ(m-n)} = \infty / (m-n)90^\circ.$$

• At final point; $s = \infty e^{-j90^\circ}$

$$G(s)H(s)|_{s=\infty e^{-j90^\circ}} = \frac{K [(\infty e^{-j90^\circ})T_1 + 1]^m}{[(\infty e^{-j90^\circ})T_2 + 1]^n} \\ = K (\infty)^{m-n} e^{-j90^\circ(m-n)} = \infty / (m-n)[-90^\circ].$$

* Change in Phase Angle of s from Initial to Final point \downarrow
 $= |s_f - s_I| = -90^\circ - 90^\circ = -180^\circ$.

* Change in Phase Angle of $G(s)H(s)$ from Initial to Final point \downarrow
 $|G_f - G_I| = \{-(m-n)90^\circ\} - \{(m-n)90^\circ\} \\ = -(m-n)180^\circ$.

* Example! $G(s)H(s) = \frac{s^2}{(s+1)}$

$$\therefore G(s)H(s)|_{s=j\omega} = \frac{-\omega^2}{(j\omega+1)} = \frac{\omega^2}{\sqrt{\omega^2+1}} [180^\circ - \tan^{-1}(\omega)]$$

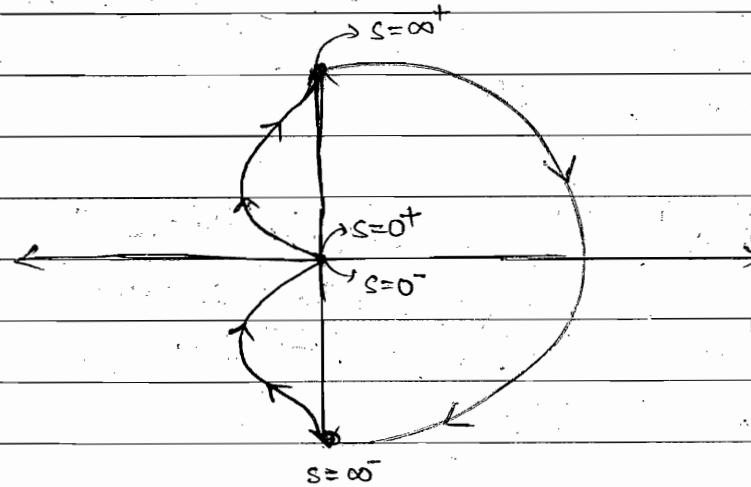
$$G(s)H(s)|_{s=j0} = 0 / 180^\circ$$

$$G(s)H(s)|_{s=j1} = \frac{1}{\sqrt{2}} / 180^\circ - 45^\circ = \frac{1}{\sqrt{2}} / 135^\circ$$

$$G(s)H(s)|_{s=j2} = \frac{4}{\sqrt{5}} / 180^\circ - 63^\circ = \frac{4}{\sqrt{5}} / 117^\circ$$

$$G(s)H(s)|_{s=j\infty} = \infty |+90^\circ.$$

$$\begin{aligned} & \frac{1}{1+\omega^2} \\ \Rightarrow & \omega^2 = \infty \\ \Rightarrow & \int \frac{1}{\omega^2} d\omega = \int \frac{1}{\infty} d\omega = \infty \end{aligned}$$



Now, put $s = \infty e^{j\theta}$.

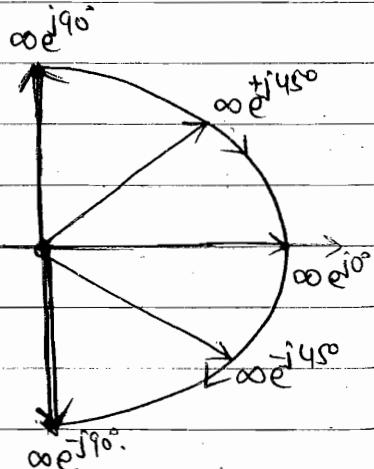
$$G(s)H(s)|_{s=\infty e^{j\theta}} = \frac{(\infty e^{j\theta})^2}{(\infty e^{j\theta})^1} = \infty e^{j(2-1)\theta} = \infty |0^\circ.$$

$$\therefore G(s)H(s)|_{s=\infty e^{j90^\circ}} = \infty |90^\circ$$

$$G(s)H(s)|_{s=\infty e^{j45^\circ}} = \infty |45^\circ.$$

$$G(s)H(s)|_{s=\infty e^{j0^\circ}} = \infty |0^\circ$$

$$G(s)H(s)|_{s=\infty e^{-j45^\circ}} = \infty |-45^\circ$$



$$G(s)H(s)|_{s=\infty e^{-j90^\circ}} = \infty |-90^\circ. \quad (\text{Closing Condition})$$

$$\text{For } s = 0e^{j0^\circ}, \quad G(s)H(s) = \frac{(0e^{j0^\circ})^2}{(0e^{j0^\circ} + 1)} = 0 |20. \rightarrow \text{Shorting Condition}$$

* Case-III: Type of system is 0 and order of pole \geq Order of zero:

- In this case, $G(s)H(s)|_{s=0^+}$ will be short-circuited and $G(s)H(s)|_{s=\infty^-}$, $G(s)H(s)|_{s=\infty^+}$ will also be short-circuited.

* Example: $G(s)H(s) = \frac{1}{(s+1)}$

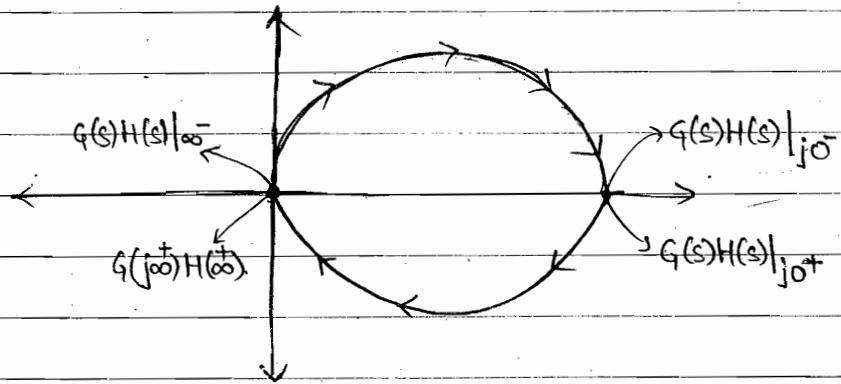
$$\Rightarrow G(s)H(s)|_{s=j\omega} = \frac{1}{j\omega+1} = \frac{1}{\sqrt{\omega^2+1}} \angle -\tan^{-1}(\omega/1).$$

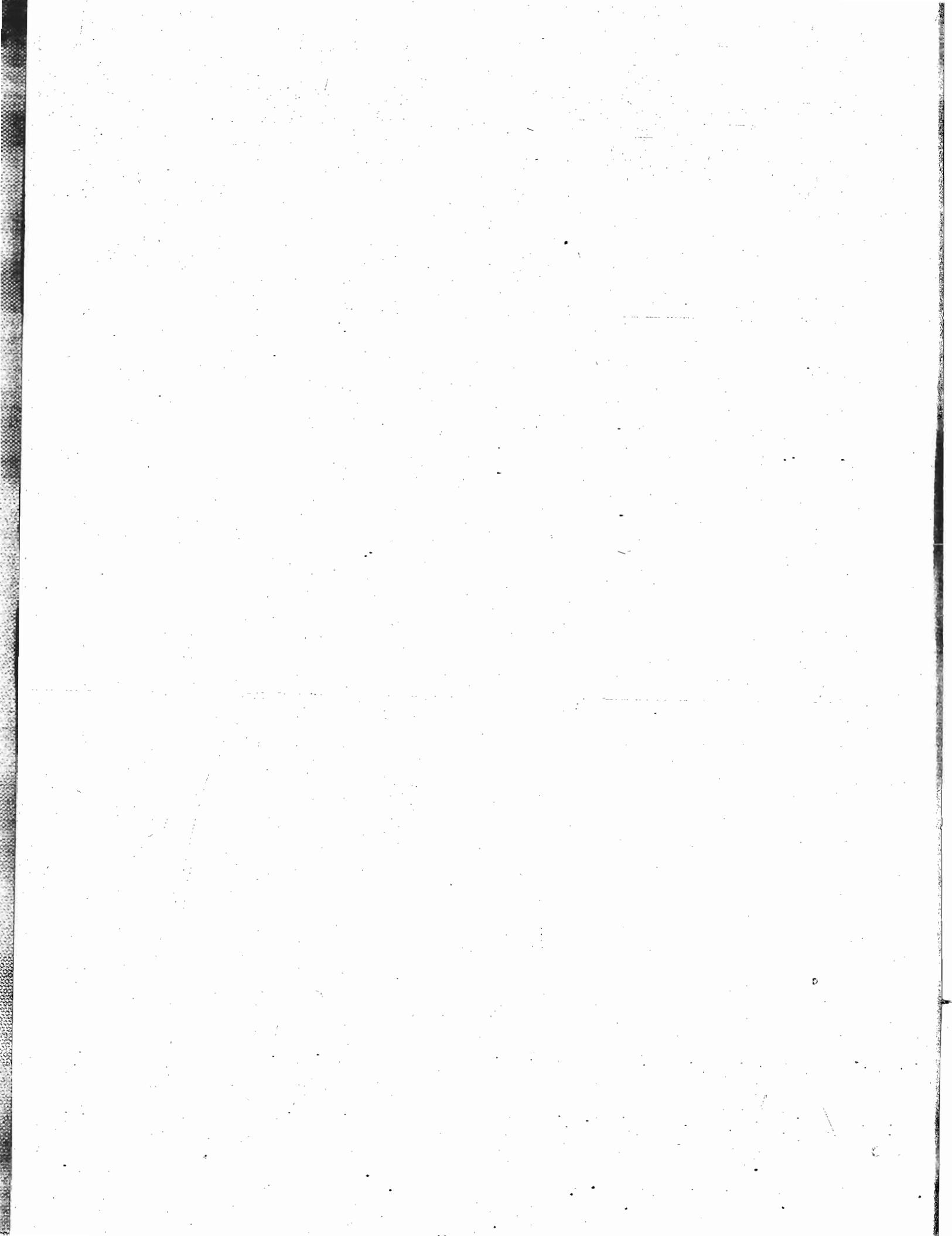
$$G(s)H(s)|_{s=j0^+} = 1 \angle 0^\circ.$$

$$G(s)H(s)|_{s=j1} = \frac{1}{\sqrt{2}} \angle -45^\circ.$$

$$G(s)H(s)|_{s=j2} = \frac{1}{\sqrt{5}} \angle -63^\circ$$

$$G(s)H(s)|_{s=j\infty} = 0 \angle -90^\circ.$$





For encirclement w.r.t. origin

$$G(\infty e^{j0})H(\infty e^{j0}) = \frac{(\infty \cdot e^{j0})^2}{(\infty e^{j0} + 1)} = (\infty)^{2-1} e^{-j(2-1)0} = \infty \angle 0^\circ$$

∞e^{j0}

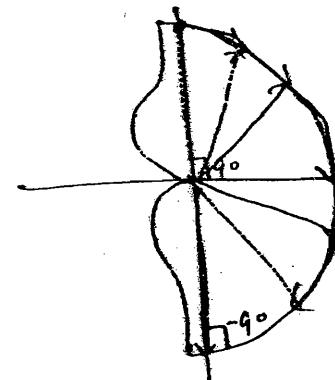
$$G(\infty \cdot e^{+j90^\circ}) \cdot H(\infty \cdot e^{+j90^\circ}) = \infty \angle +90^\circ$$

$$G(\infty \cdot e^{+j45^\circ}) \cdot H(\infty \cdot e^{+j45^\circ}) = \infty \angle +45^\circ$$

$$G(\infty \cdot e^{j0}) \cdot H(\infty \cdot e^{j0}) = \infty \angle 0^\circ$$

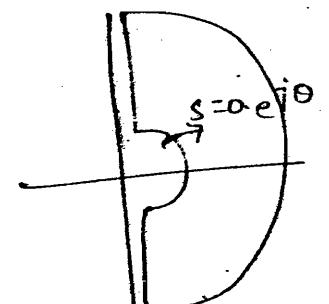
$$G(\infty \cdot e^{-j45^\circ}) \cdot H(\infty \cdot e^{-j45^\circ}) = \infty \angle -45^\circ$$

$$G(\infty \cdot e^{-j90^\circ}) \cdot H(\infty \cdot e^{-j90^\circ}) = \infty \angle -90^\circ$$



for unit radius circle

$$G(0 \cdot e^{j0}) \cdot H(0 \cdot e^{j0}) = \frac{(0 \cdot e^{j0})^2}{(0 \cdot e^{j0} + 1)} = 0^2 \cdot e^{j20} = 0 \angle 20^\circ$$



Case-3 type of System is 0 and order of pole is either > or order of zero

* In case $G(0^-) \cdot H(0^-)$ will be short circuited and $G(\infty^+) \cdot H(\infty^+)$, $G(\infty^-) \cdot H(\infty^-)$ will also be short circuit

Exa $G(s) \cdot H(s) = \frac{1}{s+1}$

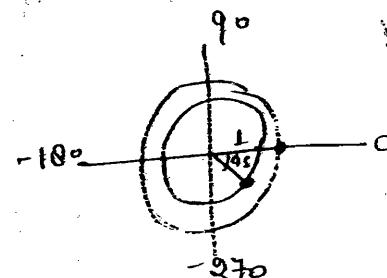
for +ve freq line

$$G(iw) \cdot H(iw) = \frac{1}{iw+1} = \frac{1}{\sqrt{1+w^2}} \angle -\tan^{-1}(w)$$

$$G(i0) \cdot H(i0) = 1 \angle -\tan^{-1}0 = 1 \angle 0^\circ$$

$$G(i1) \cdot H(i1) = \frac{1}{\sqrt{2}} \angle -90^\circ$$

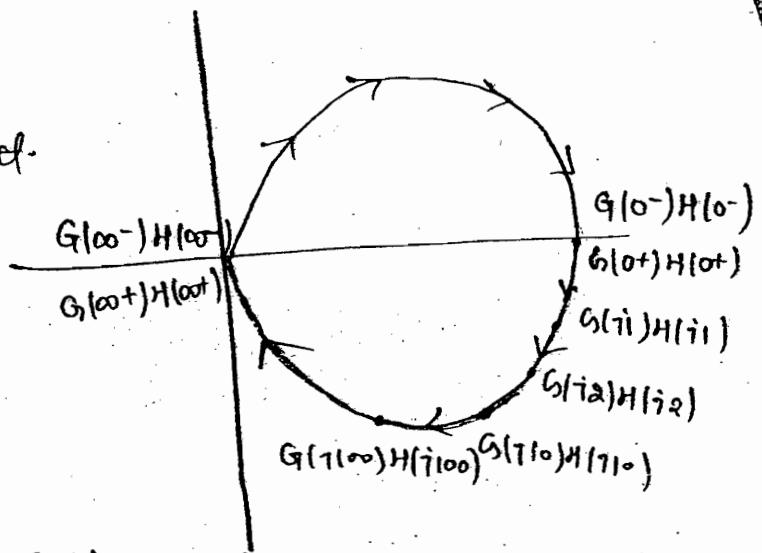
$$G(i2) \cdot H(i2) = \frac{1}{\sqrt{5}} \angle -63^\circ$$



$$r(-\infty) \cdot H(-\infty) = 0 \angle -90^\circ$$

is Graph already encircled.

closed



Response of closed-loop system with encirclement
P (-1, 0) point.

$$G(s)H(s) = \frac{K}{s[sT_1+1][sT_2+1]}$$

$$j\omega \cdot H(j\omega) = \frac{K}{(j\omega)[1+j\omega T_1][1+j\omega T_2]}$$

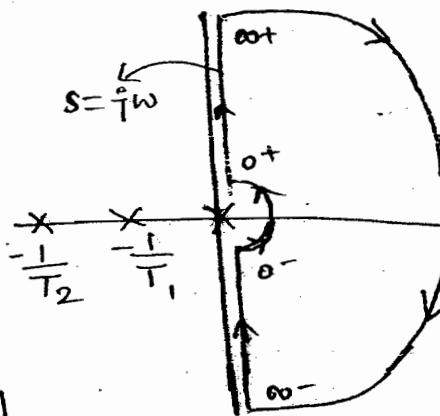
$$(j\omega) \cdot H(j\omega) = \frac{1}{\omega \sqrt{1+\omega^2 T_1^2} \sqrt{1+(\omega T_2)^2}}$$

$$\underline{j\omega H(j\omega)} = \left[-90 - \tan^{-1}\left(\frac{\omega T_1}{1}\right) - \tan^{-1}\left(\frac{\omega T_2}{1}\right) \right]$$

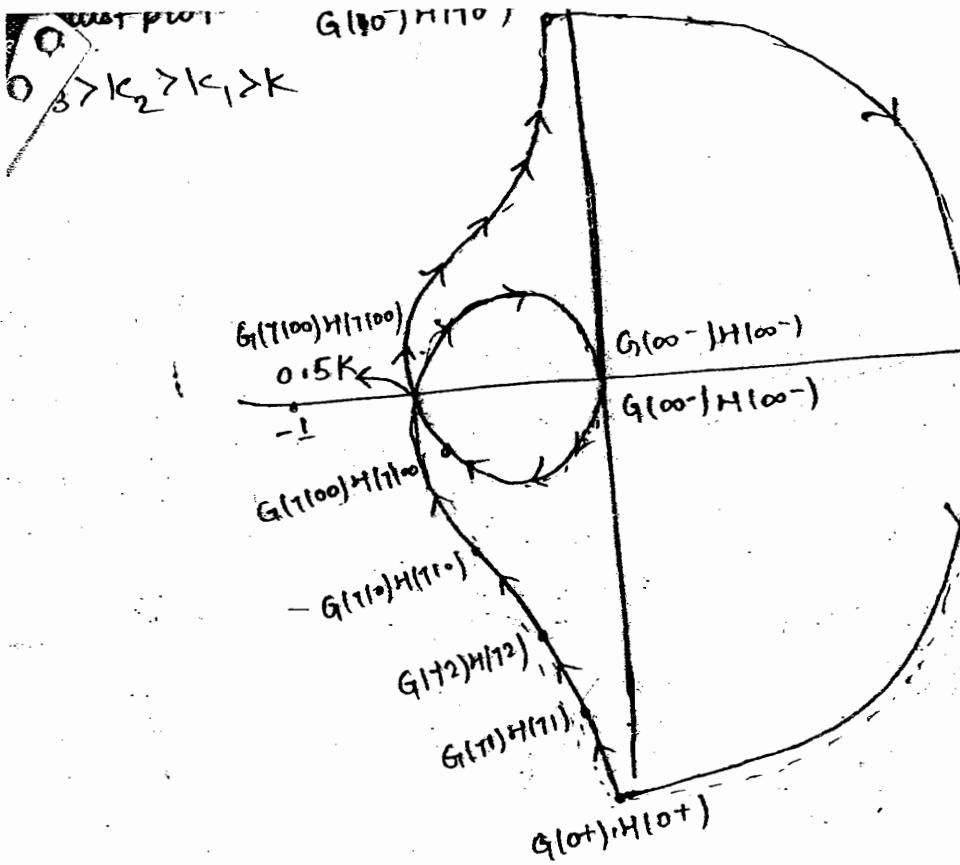
$$= 70$$

$$\underline{H(j\omega)} = \infty \angle -90^\circ$$

$$G(j\omega) \cdot H(j\omega) = 0 \angle -270^\circ$$



$$\frac{C(s)}{R(s)} = \frac{K}{s[sT_1+1][sT_2+1]+K}$$

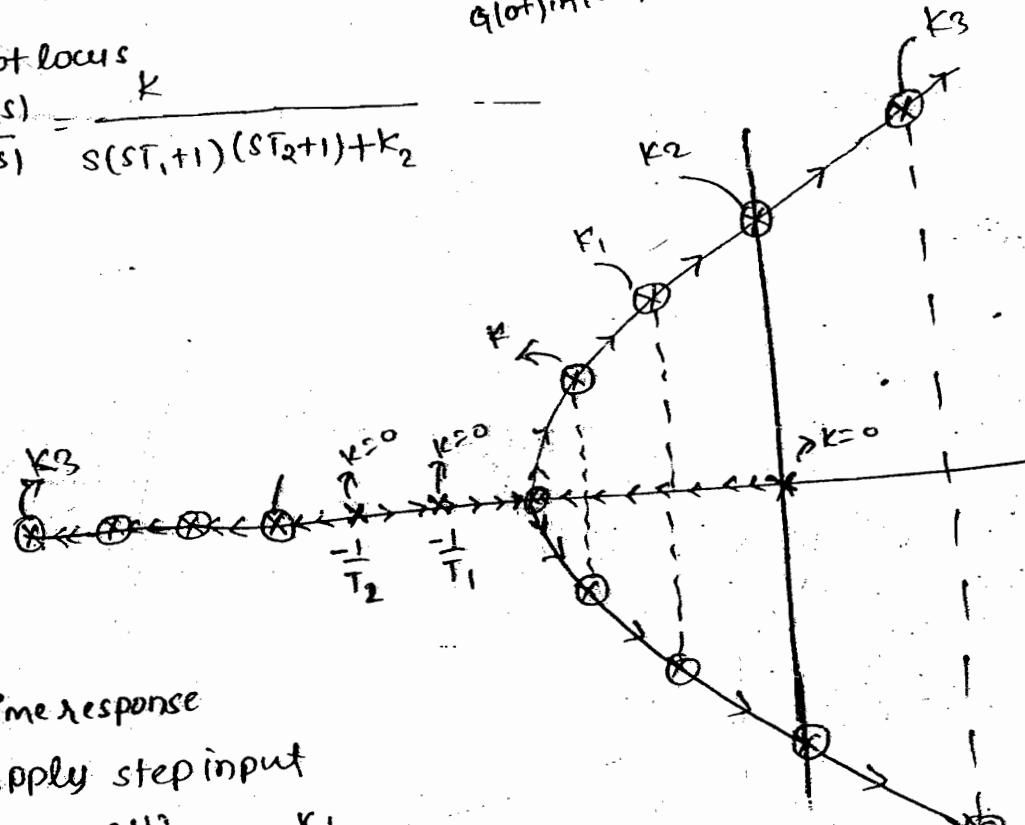


- ① $0.5K < 1$ — stable
- $0.5K < 0.5K_1 < 1$ — stat
- $0.5K_1 < 0.5K_2 = 1 - H$
- ④ $1 = 0.5K_2 < 0.5K_3$
2 unstab

① $P_+ = 0$ ④ $P_+ = 0$
 $N = 0$ $N = -2$

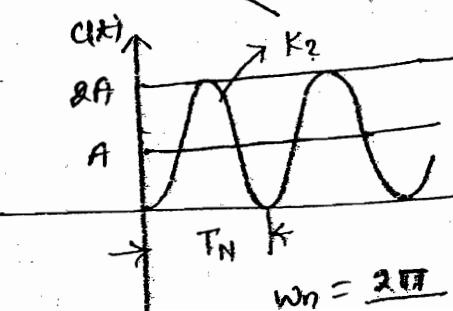
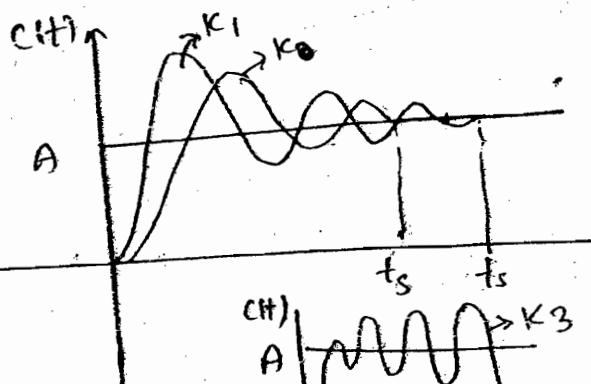
$N \geq P_+ - Z_+$
 $2 = P_+ - Z_+$
 $Z_+ = 2 \rightarrow \text{unstab}$

Root locus
 $\frac{P(s)}{R(s)} = \frac{k}{s(sT_1+1)(sT_2+1)+k_2}$

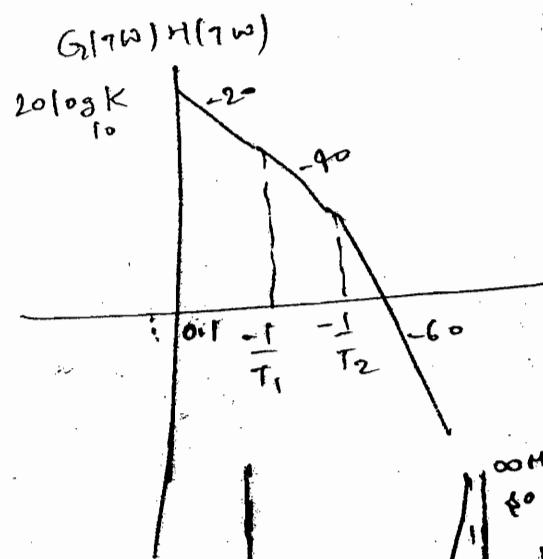


time response

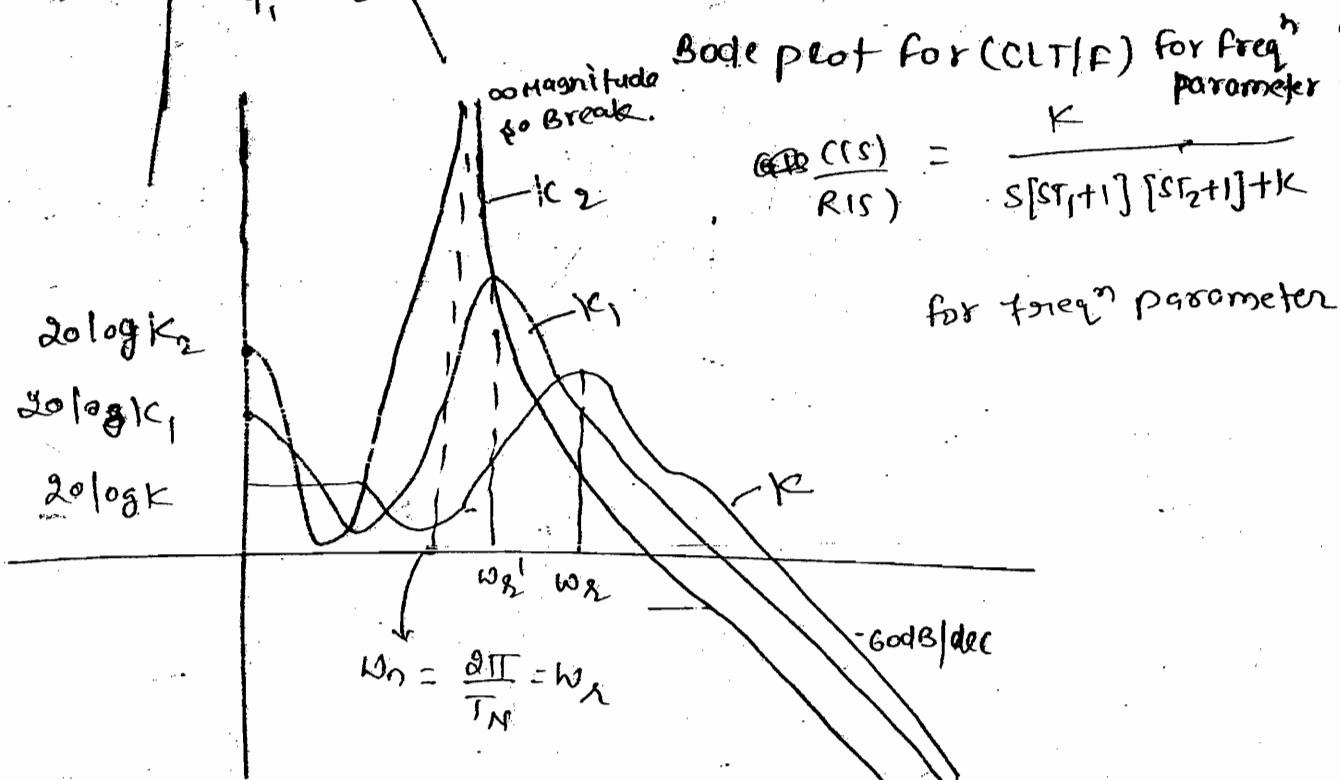
apply step input



de phasor (CLTF)



$$G(s)H(s) = \frac{K}{s[sT_1+1][sT_2+1]}$$



System goes to instability, then sharpens ↑ of Bode plot.

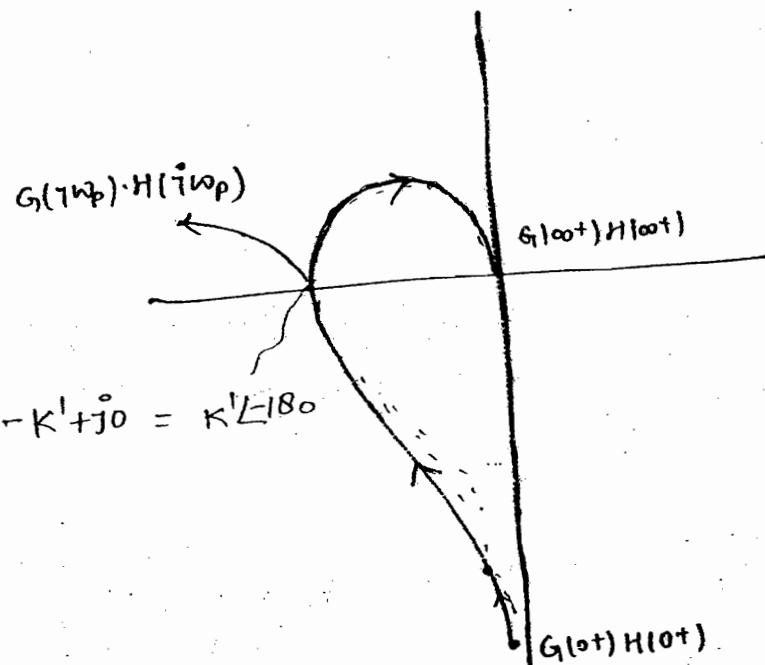
Gain Margin and phase margin

$$G(s)H(s) = \frac{K}{s[sT_1+1][sT_2+1]}$$

$$G(j\omega)H(j\omega) = \frac{K}{(j\omega)[1+j\omega T_1][1+j\omega T_2]}$$

$$= \frac{K}{\sqrt{1+(j\omega T_1)^2} \sqrt{1+(j\omega T_2)^2}} \left[-90 - \tan^{-1}\left(\frac{\omega T_1}{1}\right) - \tan^{-1}\left(\frac{\omega T_2}{1}\right) \right]$$

$$= |G(j\omega)H(j\omega)| \angle G(j\omega)H(j\omega)$$



at $\omega = \omega_p$

$$G(j\omega_p)H(j\omega_p) = |G(j\omega_p)H(j\omega_p)| \angle G(j\omega_p)H(j\omega_p) = \frac{K}{\omega_p \sqrt{1+(\omega_p T_1)^2} \sqrt{1+(\omega_p T_2)^2}} \angle -180^\circ$$

$$\boxed{-K' + j0 = \sqrt{(K')^2 + (0)^2} \angle \tan^{-1} \frac{0}{-K'} = K' \angle -180^\circ} = -K' \angle -180^\circ$$

$$\text{Gain Margin} = \frac{1}{|G(j\omega_p)H(j\omega_p)|} = \frac{1}{|K'|}$$

$$G.M. = -[+20 \log |G(j\omega_p)H(j\omega_p)|] = -[20 \log |K'|]$$

when $K' \rightarrow \infty$

* In polar form

* phase crossover freq is defined as freq at which

phase angle of O.L.T/F become 180° and G.M.

is inverse of magnitude at phase cross-over freq.

Rectangular form

* In R. form p. crossover frequency is define as freq at which imaginary term is zero and real term is negative and G.M. is inverse of magnitude of real term

In the given OLT/F put $s = j\omega$ for positive freqⁿ line
 then by rationalizing numerator and denominator
 remove all imagi term from Denominator and
 in q numerator separate real and imagi term.
 then calculate the frequency at which Imaginary
 term become zero. If real term at that freqⁿ
 is Negative then that freqⁿ will be phase
 cross-over freqⁿ and inverse of magnitude of
 real term will be gain margin.

$$G(s)H(s) = \frac{K}{s[sT_1 + 1][sT_2 + 1]}$$

$$\text{if } s = j\omega \quad G(j\omega)H(j\omega) = \frac{K \times j^2 [1 - j\omega T_1] [1 - j\omega T_2]}{j\omega(1 + j\omega T_1)(1 + j\omega T_2)[1 - j\omega T_1][1 - j\omega T_2]}$$

$$(j\omega T_1)(1 - j\omega T_2) = (1 - j^2(\omega T_1))^2 = 1 + (\omega T_1)^2$$

$$(j\omega)H(j\omega) = \frac{-jK[(1 - \omega^2 T_1 T_2) - j\omega(T_1 + T_2)]}{\omega [1 + (\omega T_1)^2][1 + (\omega T_2)^2]}$$

$$G(j\omega)H(j\omega) = \frac{-K(T_1 + T_2)}{\omega [1 + (\omega T_1)^2][1 + (\omega T_2)^2]} - \frac{jK(1 - \omega^2 T_1 T_2)}{\omega [1 + (\omega T_1)^2][1 + (\omega T_2)^2]}$$

for imagi term zero

$$-j\omega_p^2 T_1 T_2 = 0 \Rightarrow \boxed{\omega_p = \frac{1}{\sqrt{T_1 T_2}}} = \text{phase crossover freq.}$$

$$G(j\omega_p)H(j\omega_p) = \frac{-K(T_1 + T_2)}{\left[1 + (\omega_p T_1)^2\right]\left[1 + \omega_p^2 T_2^2\right]} + j0$$

$$= \frac{-K(T_1 + T_2)}{\left(1 + \frac{T_2}{T_1}\right)\left(1 + \frac{T_1}{T_2}\right)} + j0$$

$$G(i\omega_p) \cdot H(i\omega_p) = -\frac{K \cdot (T_1 + T_2) \cdot T_1 \cdot T_2}{(T_1 + T_2)^2} + j0$$

$$G(i\omega_p) \cdot H(i\omega_p) = \frac{-(T_1 \cdot T_2) \cdot K}{(T_1 + T_2)} + j0 = -K' + j0$$

$\approx -K' + j0$

$$\Rightarrow \boxed{\text{Gain Margin} = \frac{T_1 + T_2}{K T_1 \cdot T_2}}$$

From Routh Array

$$1 + G(s)H(s) = 0 \Rightarrow T_1 \cdot T_2 s^3 + (T_1 + T_2) s^2 + s + K = 0$$

| | | |
|-------|---|-----------------------------------|
| s^3 | $T_1 \cdot T_2$ | $\times 1$ |
| s^2 | $T_1 + T_2$ | $\otimes K$ |
| s^1 | $\frac{(T_1 + T_2) - KT_1T_2}{T_1 + T_2}$ | 0 |
| s^0 | K | 0 |

For s/T to be marginally stable

$$\frac{(T_1 + T_2) - KT_1T_2}{T_1 + T_2} = 0$$

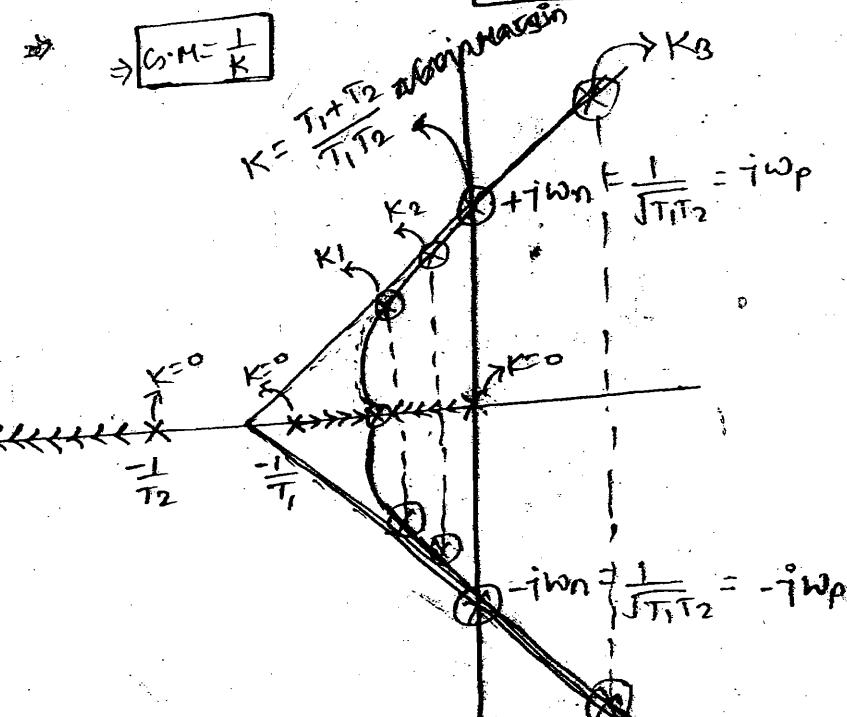
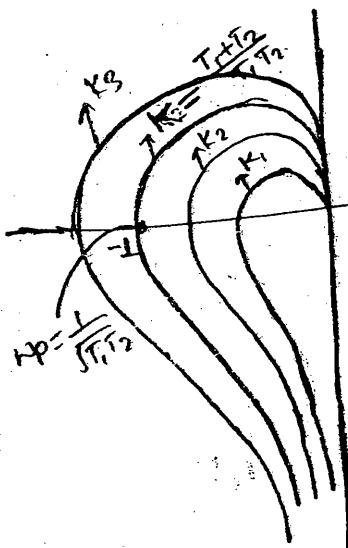
$$K = \frac{T_1 + T_2}{T_1 \cdot T_2} = \frac{T_1 + T_2}{T_1 \cdot T_2}$$

Now location of pole $(T_1 + T_2)s^2 + \frac{T_1 + T_2}{T_1 \cdot T_2} = 0$

$$\Rightarrow s = \pm i \left(\frac{1}{\sqrt{T_1 \cdot T_2}} \right) = \pm j \omega_n$$

$$\Rightarrow \boxed{\omega_n = \frac{1}{\sqrt{T_1 \cdot T_2}}}$$

from root locus
correlation



Imitation of Gain Margin

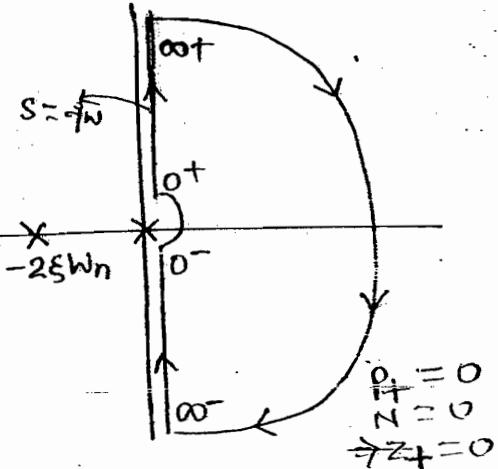
If at phase cross-over freqⁿ imagi term is zero and real term is not -ve in that case phase cross over freqⁿ will not exist and gain margin will be either +∞ or -∞ it will be define by absolute stability of the system.

$$G(j\omega)H(j\omega) = \frac{K\omega_n^2}{s(s+2\zeta\omega_n)}$$

Specified Region

$$(j\omega)H(j\omega) = \frac{K\omega_n^2}{j\omega(2\zeta\omega_n+j\omega)}$$

$$= \frac{K\cdot\omega_n^2}{\omega \left[\sqrt{(2\zeta\omega_n)^2 + \omega^2} \right]} \quad \left| \begin{array}{l} \text{qo} = \tan^{-1} \frac{j\omega}{2\zeta\omega_n} \\ \text{N} = 0 \end{array} \right.$$



$$(j\omega)H(j\omega) = \frac{K\omega_n^2 \times j^2 (2\zeta\omega_n - j\omega)}{(j\omega)(2\zeta\omega_n + j\omega)(2\zeta\omega_n - j\omega)}$$

$$= \frac{K\cdot\omega_n^2}{(2\zeta\omega_n^2 + \omega^2)} - j \frac{(2\zeta\omega_n^3) \cdot K}{\omega \left[(2\zeta\omega_n)^2 + \omega^2 \right]} \quad (\text{Rectangular form})$$

if $\omega = \infty$ (only at $\omega = \infty$ the imaginary term will be zero)

for P. cross-over freqⁿ imagi = 0 at this ω real term should be -ve
Here P. crossover freqⁿ not defined.

$$G(j\infty)H(j\infty) = 0 + j0$$

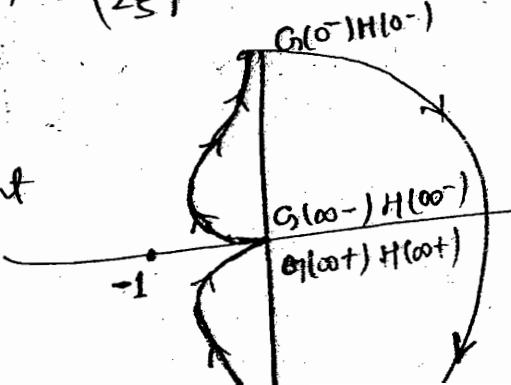
at $\omega = 0$

$$G(j0)H(j0) = \left(\frac{K}{2\zeta}\right) - j0 = a \angle -90^\circ$$

at any value of ω cut off

freqⁿ & no encirclement

System Highly stable. So
 $G \cdot M = +\infty$

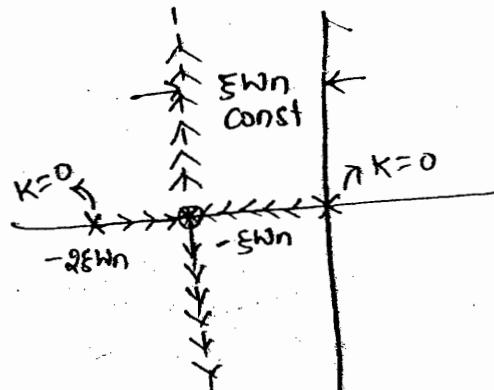


Om root locus

- any value of K there
- is no pole to right side so Highly stable.

$$\frac{C(s)}{R(s)} = \frac{k \cdot \omega_n^2}{s^2 + 2\zeta \omega_n s + \omega_n^2 k}$$

const variable



$$u \cdot n \cdot f = \sqrt{k} \omega_n \text{ (variable)} \quad T = \frac{1}{\zeta \omega_n} \text{ (constant)}$$

If this was

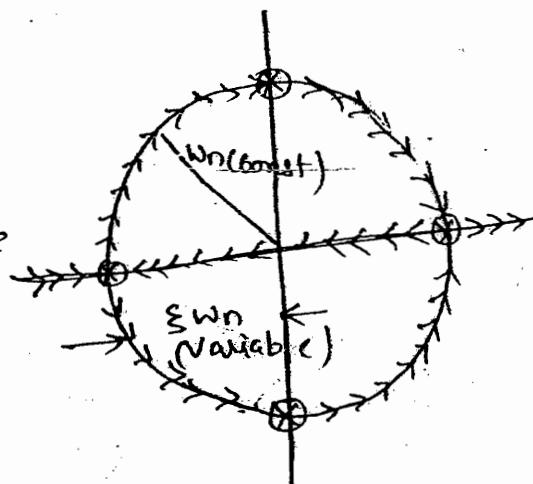
$$G(s)H(s) = \frac{\omega_n^2}{s(s+2\zeta\omega_n)}$$

variable constant

Here no K term $K=1$ (constant)
so we can't draw ω , Nyquist and R so
only time domain analysis.

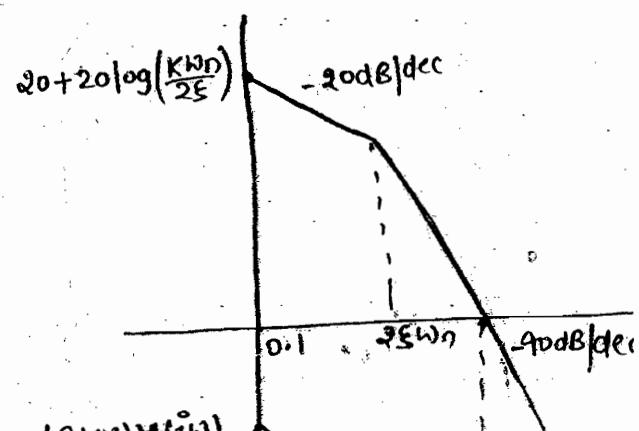
$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

variable constant



Now from Bode plot

$$G(s)H(s) = \frac{\left(\frac{\omega_n}{2\zeta}\right)}{s \left[\frac{s}{2\zeta\omega_n} + 1 \right]}$$

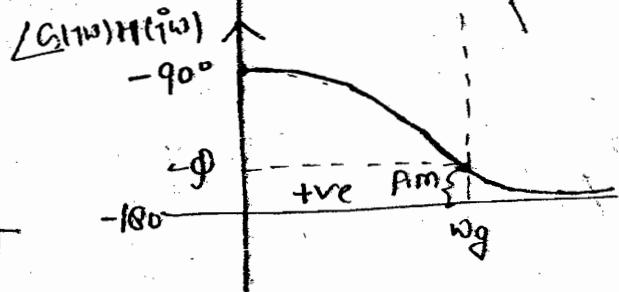


- It never cuts -180° line so
- phase cross-over freq "not exists"

PM = always +ve so G.M = +infinity

$$PM = 180 + (G(j\omega_g) \cdot H(j\omega_g))$$

अतः P.M. -ve देखा कि G.M. off -ve एवं



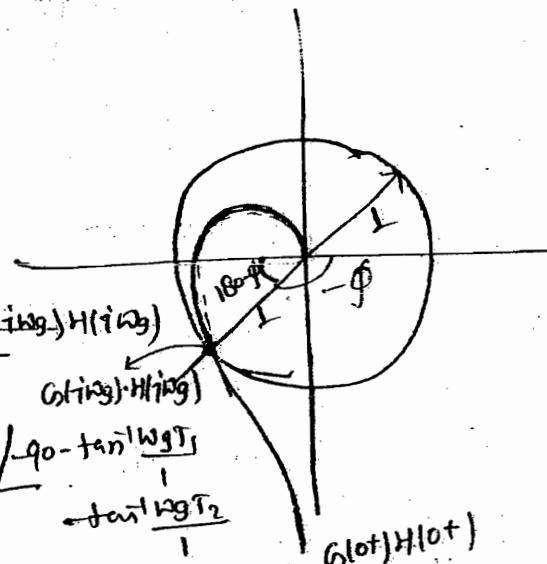
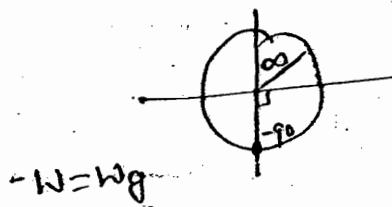
phase Margin

$$G(s)H(s) = \frac{K}{s[ST_1+1][ST_2+1]}$$

$$(j\omega)H(j\omega) = \frac{K}{j\omega[1+j\omega T_1][1+j\omega T_2]}$$

$$= \left\{ \frac{K}{\omega \sqrt{1+(\omega T_1)^2} \sqrt{1+(\omega T_2)^2}} \right\} \angle -90^\circ - \tan^{-1}\left(\frac{\omega T_1}{1}\right) - \tan^{-1}\left(\frac{\omega T_2}{1}\right)$$

$$(j\omega)H(j\omega) = \infty \angle -90^\circ$$



$$= 1 \angle -\phi = 1 \angle -\phi$$

$$\text{p.m.} = 180 + \angle G(j\omega_g)H(j\omega_g) = 180 - \phi$$

gain cross-over frequency

Gain cross-over freqⁿ is defined as freqⁿ at which magnitude of open loop T/F become equal to 1 and p.m. is 180 + phase angle at gain crossover freqⁿ.

In given open loop T/F put $s=j\omega$

for +ve positive freqⁿ line then equate the magnitude of open loop T/F with 1 to calculate -

* In cross-over freqⁿ - valid if cross-over freqⁿ should be real and +ve for +ve freqⁿ line then we will calculate phase angle at gain cross-over freqⁿ.

$$\text{p.m.} = 180 + \angle G(i\omega) \cdot H(i\omega) = 180 - \phi$$

$$|G(i\omega)H(i\omega)| = \frac{K}{\omega \sqrt{1 + (\omega T_1)^2} \sqrt{1 + (\omega T_2)^2}} = 1$$

on solving ω_g = Real and positive. (should be)

$$\angle G(i\omega) \cdot H(i\omega) = -90 - \tan^{-1} \frac{\omega T_1}{1} - \tan^{-1} \frac{\omega T_2}{1} = -\phi$$

Limitation of Phase margin

* For finite gain cross-over freqⁿ Nyquist plot should intersect unity circle if any plot is not intersecting unity circle in that case Gain cross-over freqⁿ will not be real and +ve for +ve freqⁿ line. It will be either -ve or imagi, or complex which is invalid gain cross-over freqⁿ as p.m. in that case is either +oo or -oo depending on absolute stability of the system.

Exq $G(s) \cdot H(s) = \frac{0.5}{(s+1)}$

$$G(i\omega)H(i\omega) = \frac{0.5}{1+i\omega} = \frac{0.5}{\sqrt{1+\omega^2}} \left[-\tan^{-1}\left(\frac{\omega}{1}\right) \right]$$

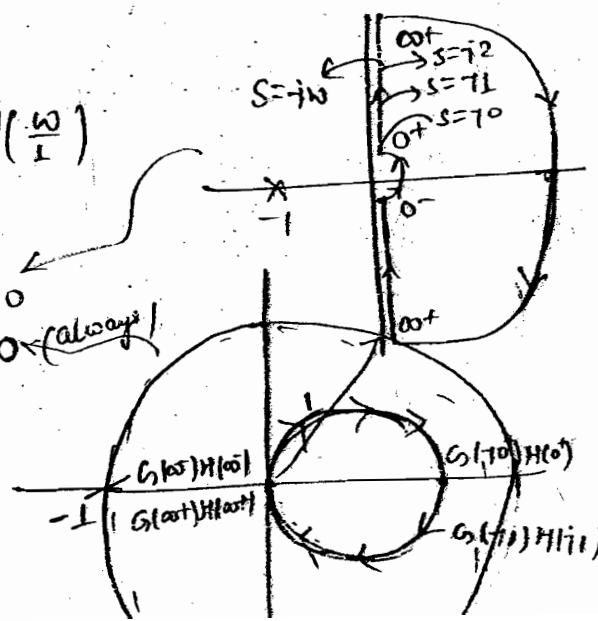
$$G(i0)H(i0) = 0.5 \angle 0^\circ$$

$$G(i1)H(i1) = \frac{0.5}{\sqrt{2}} \angle -90^\circ$$

$$G(i2)H(i2) = \frac{0.5}{\sqrt{2}} \angle -63^\circ \Rightarrow Z_f = 0$$

$$G(i\infty)H(i\infty) = 0 \angle -90^\circ \text{ Highly stable}$$

$$\text{p.m.} = +\infty$$



* never cut unit circle

$$|G(i\omega g)H(i\omega g)| = 1 \Rightarrow \frac{0.5}{\sqrt{1+\omega^2}} = 1 \Rightarrow \omega g = \pm i\sqrt{0.75}$$

gain margin for this

↓
invalid

$$G(i\omega)H(i\omega) = \frac{0.5(1-i\omega)}{(1+i\omega)(1-i\omega)} = \frac{0.5}{1+\omega^2} - j \frac{0.5\omega}{1+\omega^2}$$

$\omega = 0$

$$G(i0)H(i0) = +0.5 + j0 \quad (\text{real term not -ve})$$

do not ω_p

$\omega = \infty$

$$G(i\infty)H(i\infty) = \frac{0.5}{1+\infty^2} - j \frac{0.5}{\frac{1}{\infty} + \infty} = \frac{0.5}{1+\infty} - j \frac{0.5}{\frac{1}{\infty} + \infty}$$

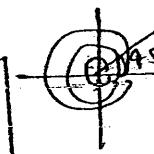
$$= +0 + j0 \quad \{ \text{Here also real term not -ve} \}$$

System always stable \therefore gain margin also $= +\infty$

plot को कितना भी बढ़ावा दें (मिले बारे बारे) कर्मि भी $(-1j0)$
को cut नहीं करेगा $\Rightarrow P.M = +\infty$

Conditionally stable system

If any plot contain more than one phase cross-over frequency in that case relative stability will be undefined and its stability will be define by absolute stability and for system to be stable Z_f should be $= 0$, Z_f is zero of charac eq lying in the right side of the imaginary axis which itself is pole of closed loop system lying in the right half side of imagi axis

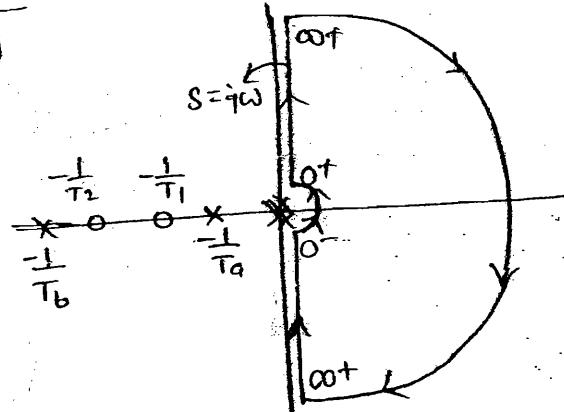


$$\begin{aligned} & s + 1 \times 360 \\ & s + 2 \times 360 \\ & s + 3 \times 360 \\ & s + n \times 360 \\ & s + \infty \times 360 \\ & = \infty \end{aligned}$$

In most cases no of phase cross-over freq will be equal to no of zero in open loop T/F

$$G(s)H(s) = \frac{K(sT_1 + 1)(sT_2 + 1)}{s^3(sT_a + 1)(sT_b + 1)}$$

$$G(i\omega)H(i\omega) = \frac{K(1+i\omega T_1)(1+i\omega T_2)}{(i\omega)^3(1+i\omega T_a)(1+i\omega T_b)}$$



$$\boxed{|G(i\omega)H(i\omega)| / |G(i\omega)H(i\omega)|}$$

$$= \frac{K \sqrt{1+(WT_1)^2} \sqrt{1+(WT_2)^2}}{W^3 \sqrt{1+(WT_a)^2} \sqrt{1+(WT_b)^2}} \begin{pmatrix} -270 + \tan^{-1}\frac{WT_1}{1} + \tan^{-1}\frac{WT_2}{1} \\ -\tan^{-1}\frac{WT_2}{1} - \tan^{-1}\frac{WT_1}{1} \end{pmatrix}$$

$$G(i0) \cdot H(i0) = \infty \angle -270^\circ \quad (+90^\circ)$$

$$G(i\infty) \cdot H(i\infty) = 0 \angle -270^\circ \quad (+90^\circ)$$

gf(-1,0) lie here

$$P_f = 0$$

$$N = -1 + 0 + 0 - 1$$

$$N = -2$$

$$N = P_f - Z_f \Rightarrow \boxed{Z_f = +2}$$

→ unstable CLSIT

gf(-1,0) lie there

$$N = 0 + 1 + 0 - 1 = 0$$

$$P_f = 0$$

$$N = P_f - Z_f \Rightarrow \boxed{Z_f = 0}$$

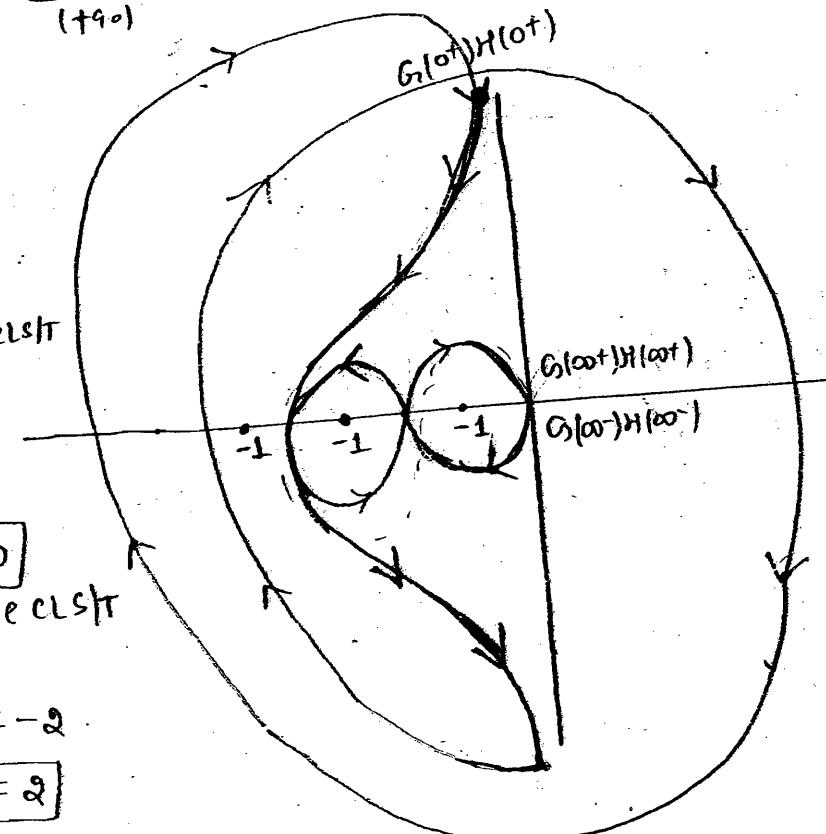
→ stable CLSIT

$$P_f = 0$$

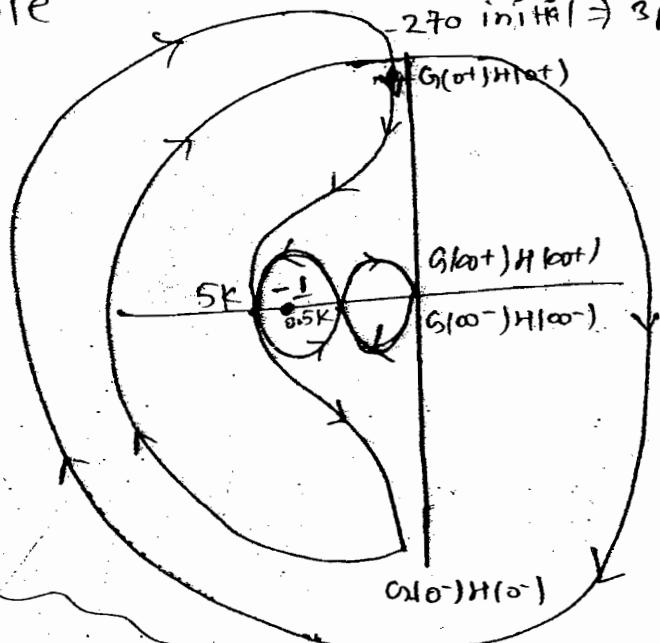
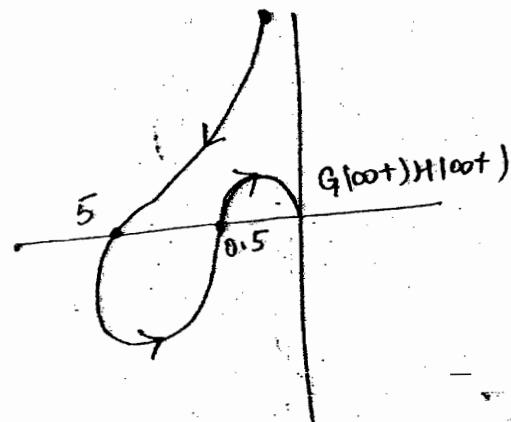
$$N = 0 + 0 + 1 - 1 = -2$$

$$N = P_f - Z_f \Rightarrow \boxed{Z_f = 2}$$

⇒ CLSIT unstable



- Given a plot for stable open loop SIT having unity gain find the range of gain for closed loop system to be stable



$$\text{if } G(s)H(s) = \frac{K}{s+1}$$

$$G(i\omega)H(i\omega) = \frac{1 \times K}{1+i\omega} = \frac{1 \times K}{\sqrt{1+\omega^2}} \angle -\tan^{-1}\frac{\omega}{1}$$

$$G(j0)H(j0) = 1 \times K \angle 0$$

$$G(i1)H(i1) = \frac{1 \times K}{\sqrt{2}} \angle -45^\circ$$

$$G(i2)H(i2) = \frac{1 \times K}{\sqrt{5}} \angle -63^\circ$$

$$G(j\infty)H(j\infty) = 0 \times K \angle -90^\circ$$

for stable

$$0.5 < 1$$

$$5K > 1$$

$$\boxed{\frac{1}{5} < K < 2}$$

^{oleft}
Given SIT stable $\Rightarrow P_+ = 0$

$$Z_+ = 0$$

$$N = P_+ - Z_+ \Rightarrow N = 0$$

for stable N should be 0

at
initially start from -270

> 3 pole at origin

> 3 encircles.

The open loop T/F of a SIT is $G(s)H(s) = \frac{K(s+1)}{(s+0.5)(s-2)}$
 Draw its Nyquist plot and determine range of K
 for closed loop S/T to be stable

Soln

$$G(s)H(s) = \frac{K(s+1)}{(s+0.5)(s-2)}$$

$$G(i\omega)H(i\omega) = \frac{K(1+i\omega)}{(0.5+i\omega)(-2+i\omega)}$$

$$G(i0)H(i0) = \frac{K[1+i0]}{(0.5+i0)(-2+i0)}$$

$$= \frac{K[1]}{0.5(-2)} = \frac{K}{-1} = \frac{K}{j^2} = K/-180 = -K + i0$$

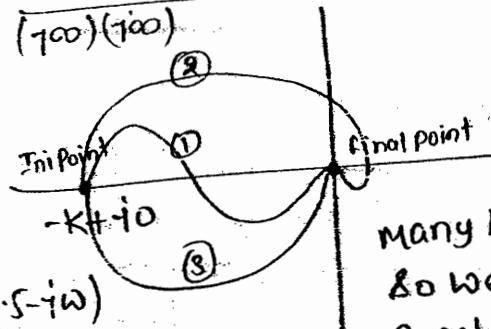
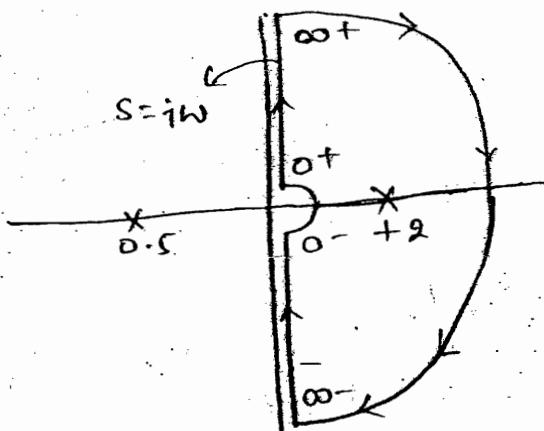
$$G(i\infty)H(i\infty) = \frac{K[1+i\infty]}{(0.5+i\infty)(-2+i\infty)} = \frac{K[i\infty]}{(\infty)(i\infty)}$$

$$= \frac{K}{j\infty} = 0 \angle -90^\circ$$

$$G(i\omega)H(i\omega) = \frac{K[1+i\omega](-2-i\omega)(0.5-i\omega)}{(0.5+i\omega)(-2+i\omega)(-2-i\omega)(0.5-i\omega)}$$

$$= \frac{-K[1+2.5\omega^2]}{(0.25+\omega^2)(9+\omega^2)} - \frac{jK\omega(\omega^2-0.5)}{(0.25+\omega^2)(4+\omega^2)}$$

specified region.



Many No of ways
 So we require
 exact analysis

For all possible value of ω , real term remain -ve,
 For imag term

$$\rightarrow \omega^2 < 0.25 \Rightarrow \omega < \sqrt{0.25} = 0.5 \text{ or } 0.707$$

Imaginary term will be +ve

$$\omega^2 = 0.5 \Rightarrow \omega = \sqrt{0.5}$$

Imag term = 0 & real term = -ve

$$so \quad \omega_p = \pm \sqrt{0.5}$$

$$G(i\sqrt{0.5}), H(i\sqrt{0.5}) = \frac{-K[1 + 2 \cdot 5 \times 0.5]}{(0.25 + 0.5)(4 + 0.5)} + j0 \\ = -\frac{2}{3}K + j0$$

$$\omega^2 > 0.5 \Rightarrow \omega > \sqrt{0.5}$$

Imagi term = -ve

$$0 < \omega < \sqrt{0.5}$$

Re = -ve, Imag = +ve

$\Rightarrow 2$ Quadrant \nexists plot

$$\sqrt{0.5} < \omega < \infty$$

$$\omega = \sqrt{0.5} \quad Re = -\frac{2}{3}, Im = 0$$

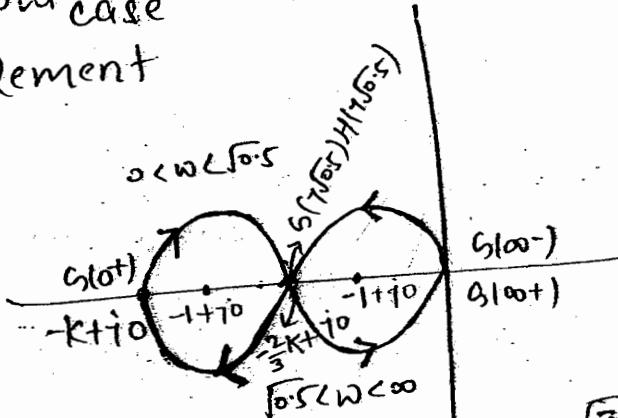
Re \rightarrow -ve, Imag = -ve

③ 3rd quadrant

$$\omega > \sqrt{0.5} < \infty$$

plot will be

it is lies under IIIrd case
no require encirclement



$$K < 1$$

$$P_+ = 1$$

$$N = 0$$

$$j = P_+ - Z_+ \Rightarrow Z_+ = 1$$

unstable

②

$$1 < K < 1.5$$

$$P_+ = 1$$

$$N = -1$$

$$N = P_+ - Z_+$$

$$-1 = 1 - Z_+ \Rightarrow Z_+ = 2$$

$$K > 1 \\ \frac{2}{3}K > 1 \\ K > \frac{3}{2} \\ K > 1.5$$

$$K > 1 \\ \frac{2}{3}K > 1 \\ K > \frac{3}{2} \\ K > 1.5$$

③

$$K > 1$$

$$\frac{2}{3}K > 1$$

$$K > \frac{3}{2}$$

$$K > 1.5$$

$$P_+ = L$$

$$N = \theta + L$$

$$N = P_+ - Z_+$$

$$Z_+ = 0$$

of char eqn

$$\frac{G(s)}{R(s)} = \frac{G(s)}{1 + G(s)H(s)} = \frac{K(s+1)}{s^2 + (K-1-s)s + (K+1)}$$

$$1 + G(s)H(s) = s^2 + (K-1-s)s + (K+1) = 0$$

$K=0.5$ in this one pole in right side.

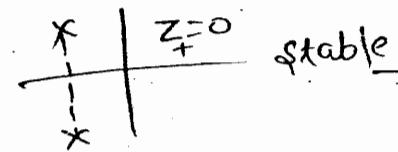
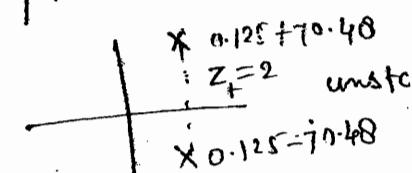
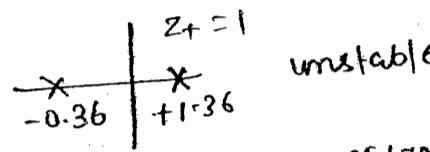
$$s^2 - 1s + 0.5 = 0, s = +1.36, -0.36$$

$$K=1.25$$

$$s^2 - 0.25s + 0.25 = 0, s = +0.125 \pm j0.48$$

$$③ [K=2]$$

$$s^2 + 0.5s + 1 = 0 \Rightarrow s = -0.25 \pm j0.96$$



g) The open-loop TLF of a SIT is $G(s)H(s) = (s+0.25)$

Determine both absolute stability

$$s^2(s+0.5)(s+1)$$

as well as relative stability

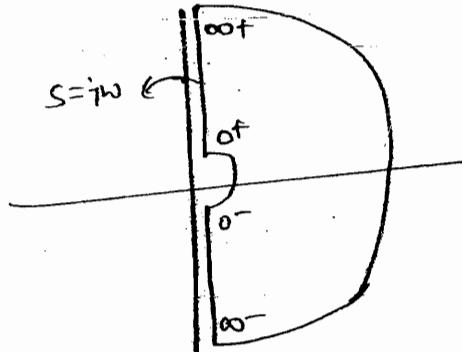
Solⁿ

$$G(s)H(s) = \frac{s+0.25}{s^2(s+0.5)(s+1)}$$

$$G(i\omega)H(i\omega) = \frac{(0.25+i\omega)}{(-\omega)^2(0.5+i\omega)(1+i\omega)}$$

$$G(i\omega)H(i\omega) = \frac{(0.25+i\omega)}{(-\omega)^2(0.5+i\omega)(1+i\omega)} \xrightarrow{\text{No phase inform}}$$

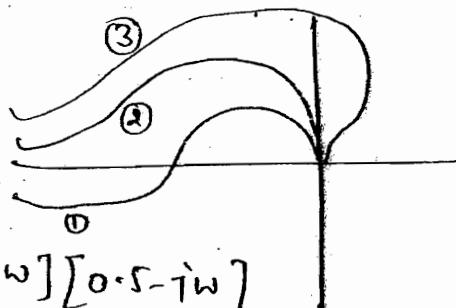
$$= \frac{(0.25)}{(-\omega)^2(0.5)(1)} = \frac{1}{\omega^2} = \infty \angle -180^\circ$$



$$G(i\omega)H(i\omega) = \frac{(0.25+i\omega)}{(-\omega)^2(0.5+i\omega)(1+i\omega)} = \frac{0.25-i\omega}{(\omega^2(0.5+i\omega)+i\omega)}$$

$$= \frac{1}{j^3\omega} = 0.1 \angle -270^\circ (+90^\circ)$$

Can be many plot to find
exact plot we use
Rationalization method



$$G(i\omega)H(i\omega) = \frac{-(0.25 + i\omega)(1 - i\omega)(0.5 - i\omega)}{\omega^2[0.5 + i\omega][1 + i\omega][0.5 - i\omega][1 - i\omega]}$$

In solving

$$= -\frac{[0.125 + 1.25\omega^2]}{\omega^2(1 + \omega^2)(0.25 + \omega^2)} + \frac{i}{\omega[1 + \omega^2](0.25 + \omega^2)}$$

For all +ve values of ω , Real term will always remain -ve
For Imag term

$$\omega^2 < 0.125, \omega < \sqrt{0.125}$$

\Rightarrow Imag term = -ve for this freqn range.

$$\omega^2 = 0.125, \omega = \pm \sqrt{0.125}$$

$$\omega_p = \pm \sqrt{0.125}$$

$$G(i\sqrt{0.125})H(i\sqrt{0.125}) = -\frac{(0.125 + 1.25 \times 0.125)}{(0.125)(1 + 0.125)(0.25 + 0.125)} + i0$$

$$\omega^2 > 0.125, \omega > \sqrt{0.125}$$

Imag term = +ve

$0 < \omega < \sqrt{0.125} \rightarrow$ Real term \rightarrow -ve (plot originate from 3rd quadrant)
Imag term \rightarrow -ve

$$\omega = \sqrt{0.125}$$

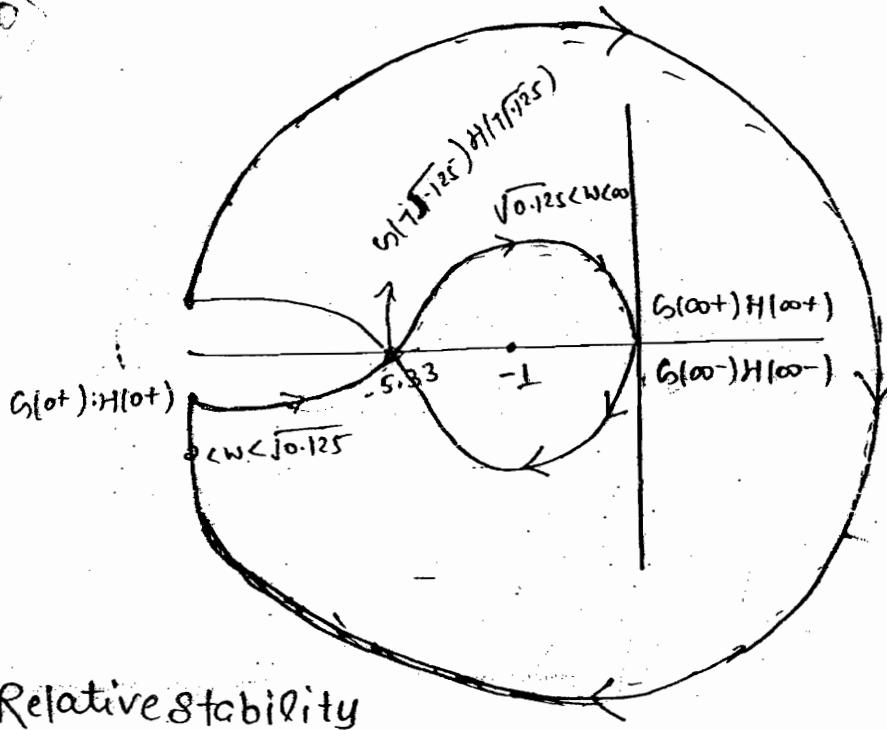
$Re = -5.33$ (Intersect ω real Axis)
 $Im = 0$

$$\sqrt{0.125} < \omega < \infty$$

Re +ve, Im +ve

\Rightarrow terminate 2nd quadrant

\Rightarrow exact plot is ①



Relative stability

$$P_+ = 0 \\ N = -2 \\ N = P_+ - Z_+$$

$$Z_+ = 2 \rightarrow \text{unstable}$$

This stability define in terms of pole so absolute stability

$$G_m = \frac{1}{|G(i\omega_p) \cdot H(i\omega_p)|} = \frac{1}{|5.33|} = 0.187 < 1 \text{ (unstable)}$$

$$\text{GM}_{AB} = 20 \log \frac{1}{|5.33|} = -14.56 \quad (-\text{ve GM}) \Rightarrow \text{unstable}$$

$$\frac{C(s)}{R(s)} = \frac{(s + 0.25)}{s^4 + 1.5s^3 + 0.5s^2 + s + 0.25} \quad (\text{closed loop T/F function})$$

$$1 + G(s)H(s) = s^4 + 1.5s^3 + 0.5s^2 + s + 0.25$$

| | | | |
|-------|-------|------|------|
| s^4 | 1 | 0.5 | 0.25 |
| s^3 | 1.5 | 1 | 0 |
| s^2 | -0.16 | 0.25 | 0 |
| s^1 | +3.2 | 0 | 0 |
| s^0 | +0.25 | 0 | 0 |

\Rightarrow 2 sign changes \Rightarrow unstable.

W FROM ROOT LOCUS

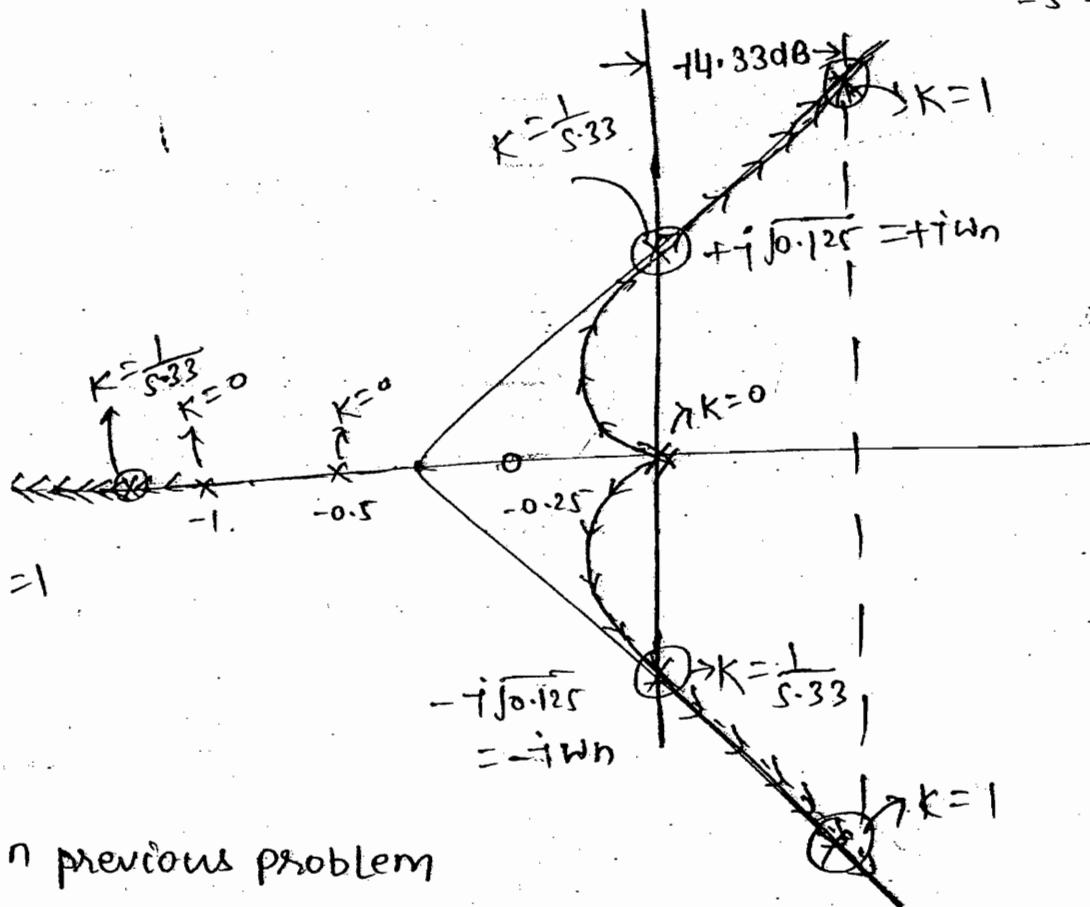
$$G(s)H(s) = \frac{K(s+0.25)}{s^2(s+0.5)(s+1)}$$

$$G(i\sqrt{0.125})H(i\sqrt{0.125}) \\ = -s \cdot 33K + 70$$

$$-s \cdot 33K + 70 = -1$$

$$\Rightarrow K = \frac{1}{s \cdot 33}$$

$$0 < K < \frac{1}{s \cdot 33}$$



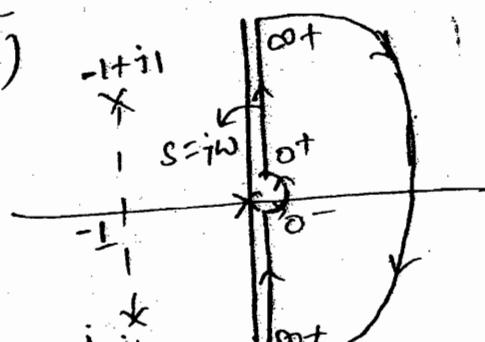
n previous problem

= 1 ω_T & at $K=1$ ω_T & pole on right side &
system unstable at $K=1$

The open loop T/F of a system is $G(s)H(s) = \frac{2 \cdot 2}{s(s+1)(s^2+2s+2)}$

Draw its Nyquist plot and determine both
absolute and relative stability also determine
the range of gain for closed loop ST to be stable

o $G(s)H(s) = \frac{2 \cdot 2}{s(s+1)(s^2+2s+2)}$



$$G(i\omega)H(i\omega) = \frac{2.2}{(i\omega)[1+i\omega][(i\omega)^2 + 2(i\omega) + 2]}$$

$$G(i0)H(i0) = \frac{2.2}{(i0)[1+i0]\underbrace{[(i0)^2 + 2(i0) + 2]}_{V_0}} = \frac{2.2}{i0 \times 2}$$

$$= \frac{1}{i0} = \infty \angle -90^\circ$$

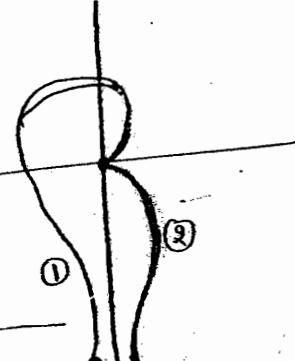
$$G(i\infty)H(i\infty) = \frac{2.2}{(i\infty)[1+i\infty]\underbrace{[(i\infty)^2 + 2(i\infty) + 2]}_{\text{neglect}}} = 0 \angle -360^\circ$$

Exact Analysis

$$G(i\omega)H(i\omega) = \frac{2.2}{i\omega(1+i\omega)[(i\omega)^2 + 2(i\omega) + 2]}$$

$$= \frac{-j^2 2.2 [1-i\omega][(2-\omega^2) - j2\omega]}{(i\omega)(1+i\omega)[(2-\omega^2) + j2\omega][(2-\omega^2) - j2\omega][1-i\omega]}$$

$$= \frac{-2.2[4-\omega^2]}{(1+\omega^2)[(2-\omega^2)^2 + 4\omega^2]} - \frac{j 2.2(2-3\omega^2)}{\omega[1+\omega^2][(2-\omega^2) + 4\omega^2]}$$



→ for Imaginary term.

$$\rightarrow 3\omega^2 < 2 \Rightarrow \omega < \sqrt{\frac{2}{3}} = 0.816$$

Imag term = -ve

$$\rightarrow 3\omega^2 = 2 \Rightarrow \omega = \pm \sqrt{\frac{2}{3}} = 0.816$$

$$G\left(j\sqrt{\frac{2}{3}}\right)H\left(j\sqrt{\frac{2}{3}}\right) = -\frac{2.2\left[4 - \frac{2}{3}\right]}{\left(1 + \frac{2}{3}\right)\left[\left(2 - \frac{2}{3}\right)^2 + 4 \times \frac{2}{3}\right]} + j0$$

$$= -0.99 + j0$$

$$3w^2 > 2 \Rightarrow w > \sqrt{\frac{2}{3}} \Rightarrow \text{Im term} = +\text{ve}$$

for Real term.

$$w^2 < 4 \Rightarrow w < 2, \text{ Re term} = -\text{ve}$$

$$w < 2$$

$$w^2 = 4 \Rightarrow w = \pm 2$$

$$G(i2) \cdot H(i2) = 0 - \frac{i2 \cdot 2(2-i2)}{2(1+4)[(2-i2)^2 + 4 \times 4]} = 0 + i0.11$$

$$\Rightarrow \text{Real term} = 0, \text{ Im} = +i0.11$$

$$w^2 > 4 \Rightarrow w > 2 \Rightarrow \text{Real term} +\text{ve}$$

$$0 < w < \sqrt{\frac{2}{3}} \quad \text{Im} = -\text{ve} \& \text{Real} = -\text{ve} (\Rightarrow \text{originate } 3^{\text{rd}} \text{ quadr})$$

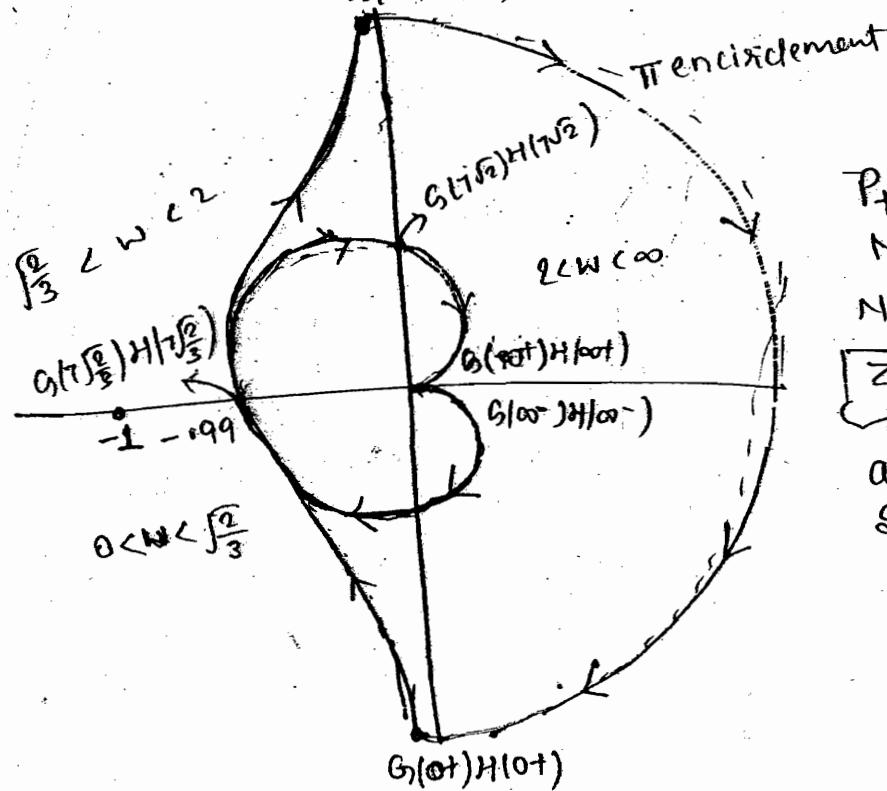
$$w = \sqrt{\frac{2}{3}} \quad \text{intersect at Negative real Axis}$$

$$\sqrt{\frac{2}{3}} < w < 2 \quad \text{Imag} = +\text{ve} \& \text{Real} = -\text{ve} \quad ②$$

$$w = 2 \quad \text{Imag} = -i0.11, \text{Re} = 0$$

$$2 < w < \infty \quad \text{Imag} = +\text{ve}, \text{Re} = +\text{ve} \quad ①$$

case I



$$P_+ = 0 \\ N = 0 \\ N = P_+ - Z_+$$

$$Z_+ = 0$$

absolute
stable st

Negative stability

$$G(i\omega_p)H(i\omega_p) = -0.99 + j0$$

$$G \cdot M = \frac{1}{|G(i\omega_p)H(i\omega_p)|} = \frac{1}{|0.99|} = 1.01 > 1$$

$G \cdot M = 20 \log 1.01 = +0.08 \text{ dB} \Rightarrow CL \text{ S/T will be stable}$

$$G(s)H(s) = \frac{\{0.2 \times \frac{1}{2+2}\}K}{s(s+1)(s^2+2s+2)}$$

$$G(i\omega_p)H(i\omega_p) = \frac{0.99 \times \frac{1}{2+2}}{2+2} + j0$$

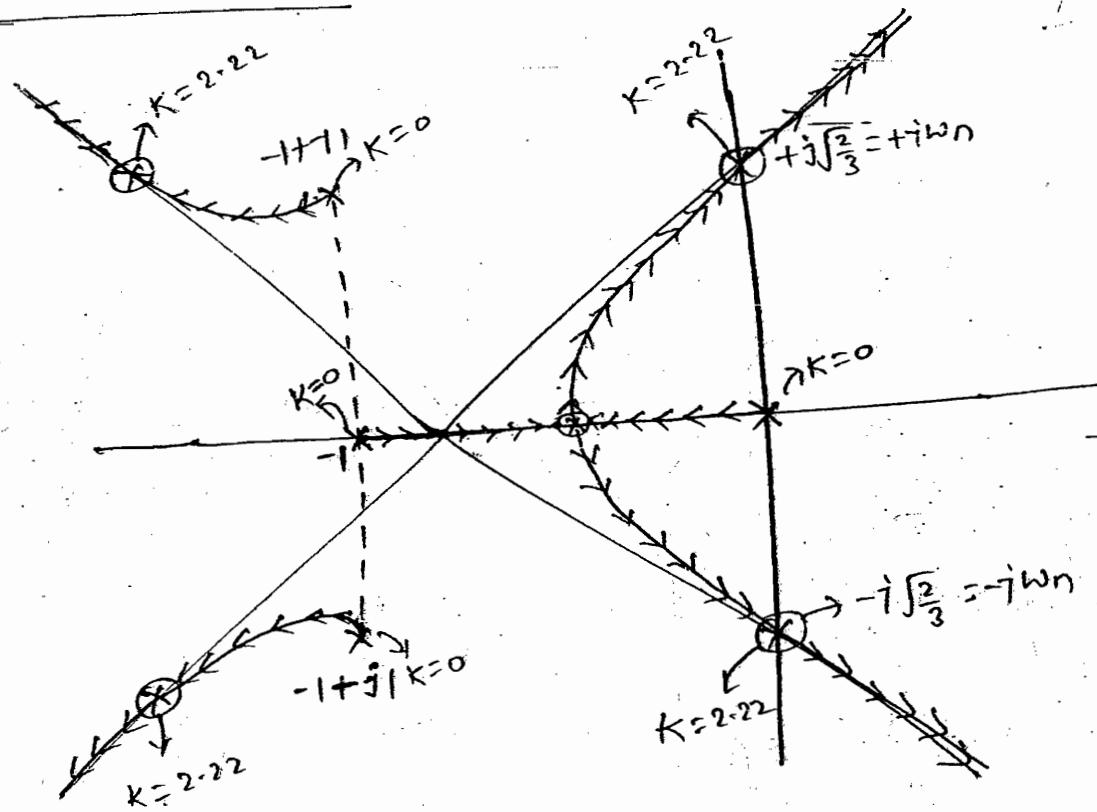
$$K_{MC} = \frac{2+2}{0.9} = 2.22$$

$$\omega_n = \omega_p = \sqrt{\frac{2}{3}} =$$

$$0 < K < 2.22$$

Root locus का gain, gain होता है।
hot dc gain $\Rightarrow G(s)H(s)$ standard
form से पा न से

From Root locus



The open loop T/F of a system is $G(s)H(s) = \frac{K}{s^3(Ts+1)}$

Determine gain margin of the system

$$1 + G(s)H(s) = 0 \Rightarrow Ts^4 + s^3 + K = 0 \quad -\text{unstable system}$$

minimum phase SFT 80

$$GM = -\infty$$

From root locus

$$Sp = 0, 0, 0, -\frac{1}{T}$$

$$1 + G(s)H(s) = 0$$

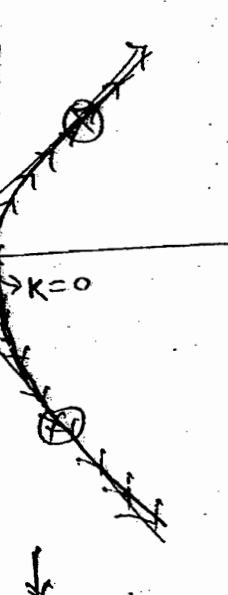
$$\frac{1+K}{s^3(Ts+1)} = 0$$

$$-K = Ts^4 + s^3 \Rightarrow \frac{dK}{ds} = 4Ts^3 + 3s^2$$

$$\frac{dK}{ds} = 0 \Rightarrow s^2[4Ts + 3] = 0 \Rightarrow s = 0, 0, -\frac{3}{4T}$$

$$\text{Centroid } x = \frac{\sum P - \sum Z}{P - Z} = -\frac{1}{4T}$$

$$\theta_0 = 90^\circ, \theta_1 = 135^\circ, \theta_2 = 225^\circ, \theta_3 = 315^\circ$$



↓
⇒ 2 poles always
right side
for SFT unstable.

| s^4 | T | 0 | K |
|-------|----|---|---|
| s^3 | 1 | 0 | 0 |
| s^2 | 0 | K | 0 |
| s^1 | -∞ | 0 | 0 |
| s^0 | +K | 0 | 0 |

for any value of K

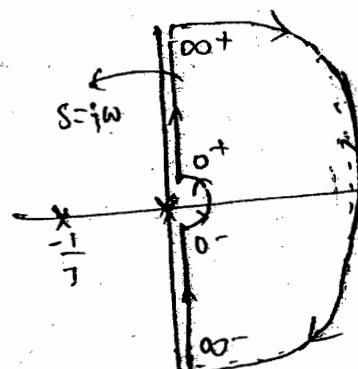
any odd now ≠ 0

from Nyquist plot

$$\text{Re}(j\omega) H(j\omega) = \frac{K}{(j\omega)^3 (1+j\omega T)}$$

$$\text{Im}(j\omega) H(j\omega) = \frac{K}{(j\omega)^3 (1+j\omega)} \quad \text{no infor}$$

$$= \frac{K}{j\omega^3} = \infty \angle -270^\circ + 90^\circ$$



$$G(j\omega)H(j\omega) = \frac{K}{(j\omega)^3(1+j\omega)} = \frac{K}{(j\omega)^4} = 0 \angle -360^\circ (0^\circ)$$

$$P_T = 0$$

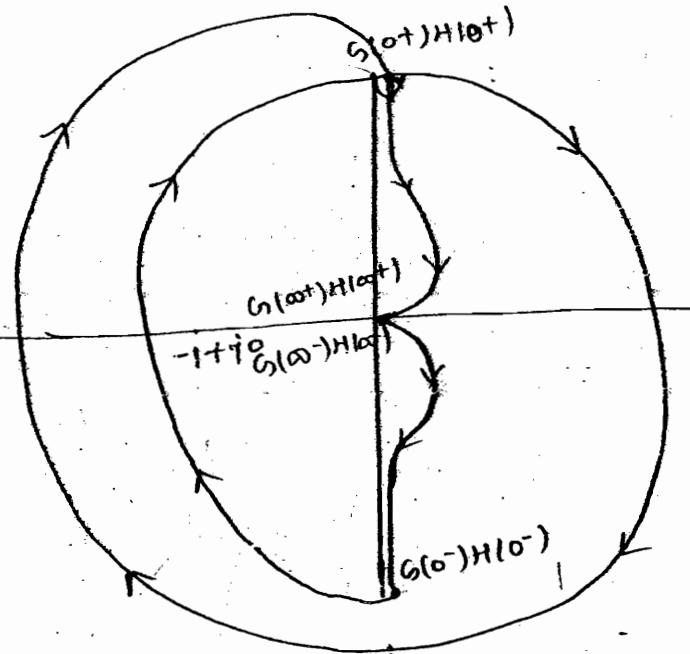
$$N = -2$$

$$N = P_T - Z_T$$

$$Z_T = 2$$

always unstable

$$\Rightarrow G \cdot m = -\infty$$



From exact analysis

$$G(j\omega)H(j\omega) = \frac{j^4 K [1-j\omega T]}{(j\omega)^3 [1+j\omega T] [1-j\omega T]} = \frac{K T}{\omega^2 [1+(\omega T)^2]^2} + j \frac{K}{\omega^3 [1+(\omega T)^2]}$$

for all values of ω (0 to $+\infty$) Real and Imaginary term $\neq 0$

$$G(j\omega)H(j\omega) = 0 + 90^\circ \quad \text{No phase cross-over freq}^\circ \exists \text{ so } G \cdot m \left[\begin{matrix} +\infty \\ -\infty \end{matrix} \right]$$

$G \cdot m \left[\begin{matrix} +\infty \\ -\infty \end{matrix} \right]$ depends on absolute stability.

Q $G(s)H(s) = \frac{K s^3}{(s+1)(s+2)}$ Draw its N.Plot and Determine Range of K for closed Loop s/T to be stable.

Solⁿ

$$G(j\omega)H(j\omega) = \frac{K (-j\omega)^3}{(1+j\omega)(2+j\omega)} =$$

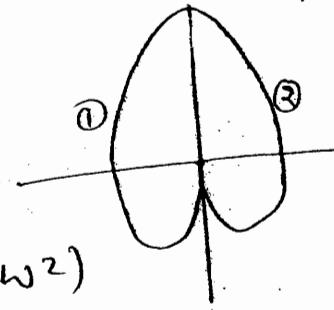
$$G(j\omega)H(j\omega) = \frac{K (j\omega)^3}{(1+j\omega)(2+j\omega)} = \frac{K j^3 \omega^3}{j^2 + 1 \times 2}$$

$$= 0 \angle +270^\circ (-90^\circ)$$

$$j(\omega)H(j\omega) = \frac{K(j\omega)^3}{(1+j\omega)(2+j\omega)} = \frac{K(j\omega)^3}{j\omega \times j\omega} \\ = \infty \angle \pm 90^\circ$$

$$j\omega H(j\omega) = \frac{-jK(\omega)^3 (1-j\omega)(2-j\omega)}{(1+j\omega)(2+j\omega)(1-j\omega)(2-j\omega)}$$

$$= \frac{-3K\omega^4}{(1+\omega^2)(4+\omega^2)} - \frac{jK\omega^3(2-\omega^2)}{(1+\omega^2)(4+\omega^2)}$$



for all positive values of ω real term will remain -ve
for imagi term

$$\omega^2 < 2 \Rightarrow \omega < \sqrt{2} \quad \text{Imag term} = -\text{ve}$$

$$\omega^2 = 2 \Rightarrow \omega_p = \pm\sqrt{2} \quad G(j\sqrt{2})H(j\sqrt{2}) = -\frac{3K \times (2)^2}{(1+2)(4+2)} + j0$$

$$\text{Real term} = -\frac{2}{3}K, \text{Imag term} = 0 = -\frac{2}{3}K + j0$$

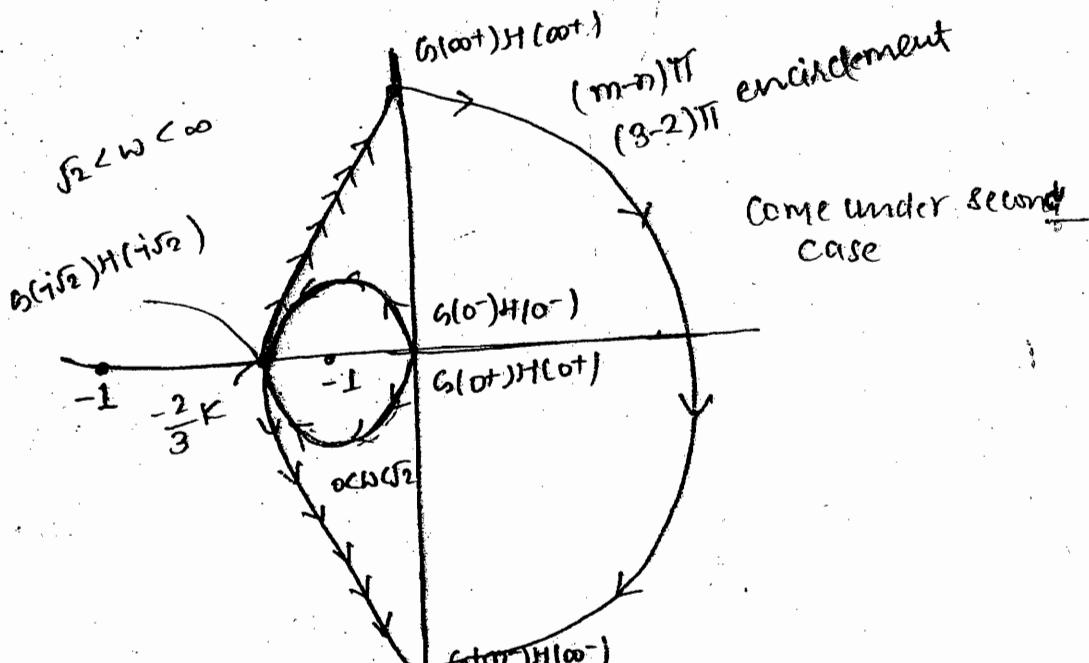
$$\omega^2 > 2 \Rightarrow \omega > \sqrt{2}$$

$$\text{Imag term} = +\text{ve}$$

$0 < \omega < \sqrt{2}$ Real term -ve } 3rd quadrant
Imag term -ve. } quadrant intersects

$$\omega = \sqrt{2}$$

$\sqrt{2} < \omega < \infty$ Real term +ve, Imag +ve



$$0 < K < 1.5$$

$$\frac{2}{3}K < 1, K < \frac{3}{2}$$

$$P_+ = 0 \\ N = 0$$

$$N = P_+ - Z_+ \Rightarrow Z_+ = 0$$

CLST stable for range of K.

$$K > 1.5$$

$$\frac{2}{3}K > 1, K > \frac{3}{2}$$

$$P_+ = 0 \\ N = -2$$

$$N = P_+ - Z_+ \Rightarrow Z_+ = 2$$

For this range of K in this case this is unstable.

Relative stability

$$G \cdot m = \frac{1}{|G(i\omega_p)H(i\omega_p)|} = \frac{1}{|\frac{2}{3}K|}$$

$$|G \cdot m|_{dB} = -\{20 \log |\frac{2}{3}K|\} \quad \frac{C(s)}{R(s)} = \frac{K s^3}{K s^3 + s^2 + 3s + 2}$$

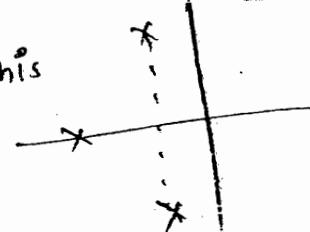
$$1 + G(s)H(s) = K s^3 + s^2 + 3s + 2$$

$$\text{Let } K=1 \quad s^3 + s^2 + 3s + 2 = 0 \Rightarrow s = -0.715, -0.14 \pm j1.66$$

$$Gm = -20 \log \left(\frac{2}{3} \times 1 \right) = +3.6 \text{ dB} \quad \text{stable for this}$$

for this (+ve G.m)

\Rightarrow stable SIT



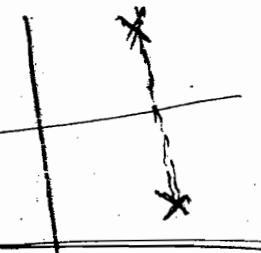
$$\text{Let } K=2 \quad 2s^3 + s^2 + 3s + 2 = 0 \Rightarrow s = -0.63, +0.06 \pm j1.25$$

$$G \cdot m = -20 \log \left(\frac{2}{3} \times 2 \right)$$

unstable SIT \Leftarrow

for this range of K

$$G \cdot m = -2.5 \text{ dB} (-\text{ve G.m}) \Rightarrow \text{unstable SIT}$$



$$\therefore G(i\omega_p) \cdot H(i\omega_p) = -\frac{2}{3}K + j0$$

\Rightarrow In Root locus imaginary axis

$$\text{root locus } -\frac{2}{3}K = -1 \Rightarrow K = \frac{3}{2} \text{ cut}$$

axis

From root locus

$$s_2 = 0, 0, 0, \quad \text{Sp} = -1, -2$$

$$1 + G(s)H(s) = 0 \Rightarrow -K = \frac{s^2 + 3s + 2}{s^3}$$

$$\frac{dK}{ds} = \frac{s^3(2s+3) - (s^2+3s+2) \times 3s^2}{(s^3)^2} \Rightarrow \frac{dK}{ds} = 0$$

$$s^2[-s^3 - 6s - 6] = 0 \Rightarrow s = 0, 0, -4.73, -1.26$$

$$x = \frac{\text{EP} - \text{EZ}}{P - Z} = \frac{-3 - 0}{2 - 3} = +3$$

$$\theta_K = \frac{(2K+1)180}{P - Z} \Rightarrow \theta_0 = 180^\circ$$

$$\text{i.m.s. } 1 + G(s)H(s) = Ks^3 + s^2 + 3s + 2 = 0$$

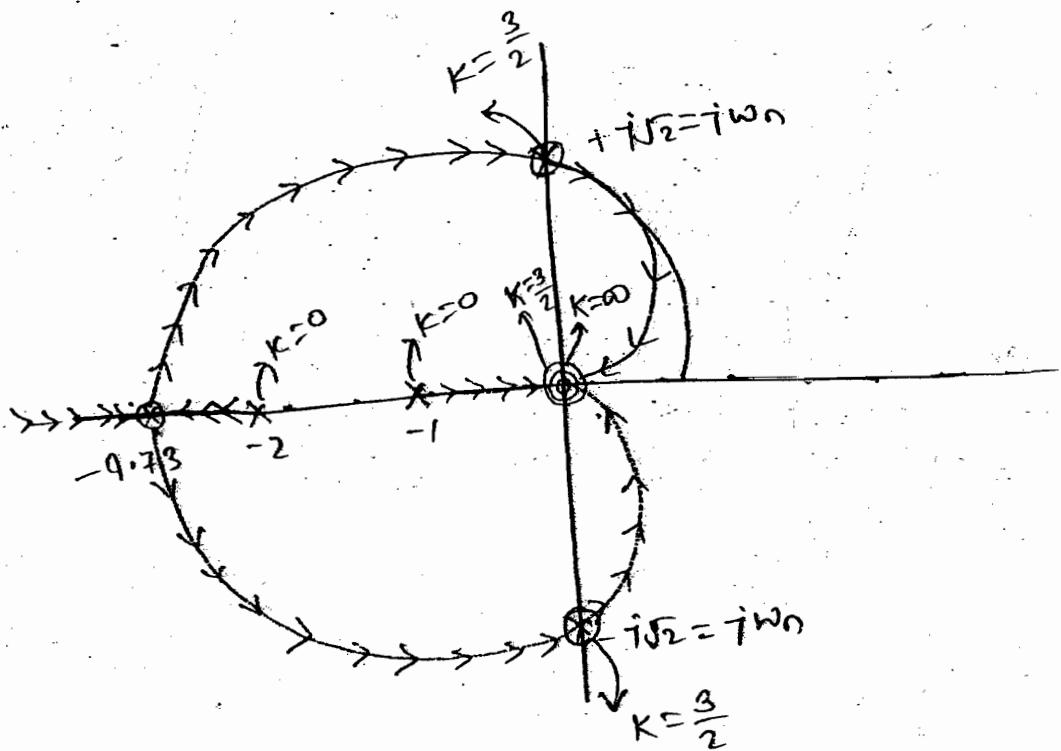
| | | |
|-------|----------|---|
| s^3 | K | 3 |
| s^2 | 1 | 2 |
| s^1 | $3-2K=0$ | |
| s^0 | 2 | |

for marginally stable odd poles
should be = 0 $\Rightarrow 3-2K=0$

$$K = \frac{3}{2}$$

$$s^2 + 2 = 0 \Rightarrow s = \pm i\sqrt{2} = \pm i\omega_n$$

$$\omega_n = \sqrt{2}$$



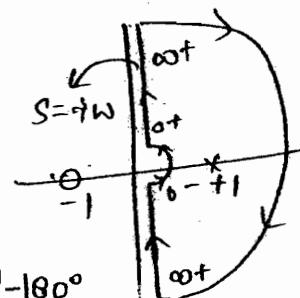
~~The OLTIF of SIT is $G(s)H(s) = \frac{K(s+1)}{(1-s)}$~~ DRAW IT
 Nyquist plot and determine range of K for CLSIT to be stable

Sol^h * When pole and zero locate at mirror image about imaginary axis that SIT is known as all pass SIT and Nyquist plot of all pass SIT will always be circular in shape

$$G(i\omega)H(i\omega) = \frac{K(1+i\omega)}{(1-i\omega)}$$

$$G(i0)H(i0) = K \angle 0^\circ$$

$$G(i\infty)H(i\infty) = \frac{K(1+i\infty)}{(1-i\infty)} = \frac{K}{-1} = \frac{1}{T^2} = K \angle -180^\circ$$

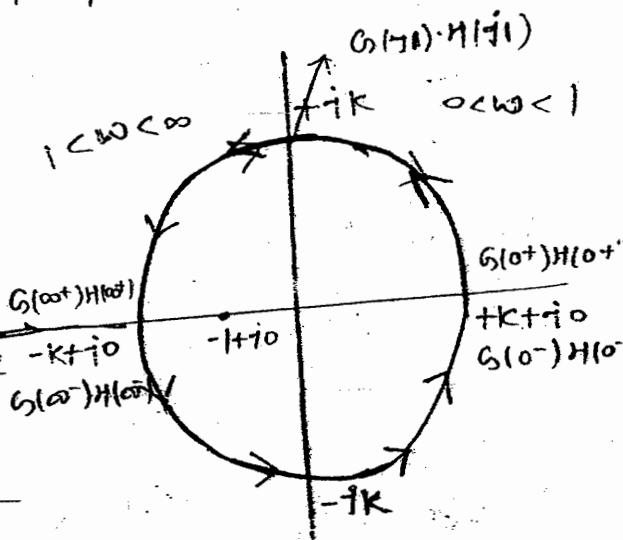


$$G(i\omega)H(i\omega) = +K + i\omega = K \angle 0^\circ$$

$$G(i\infty)H(i\infty) = -K + i0 = K \angle -180^\circ$$

$$G(i\omega)H(i\omega) = \frac{K[1+i\omega][1+i\omega]}{[1-i\omega][1+i\omega]}$$

$$= \frac{K[1-\omega^2]}{(1+\omega^2)} + i \frac{2\omega K}{(1+\omega^2)}$$



→ For all +ve values of ω real term remain +ve

→ $\omega < 1$ real term +ve

→ $\omega^2 = 1 \Rightarrow \omega = \pm 1$ Real term = 0

Imag term = K

$$\begin{aligned} G(i1)H(i1) &= 0 + i \frac{2K\pi}{2} \\ &= 0 + ik \end{aligned}$$

→ $\omega^2 > 1 \Rightarrow \omega > 1$ Real term → -ve

$0 < \omega < 1$ Imag term = +ve & Real term = +ve (1)

$\omega = 1$ Imag term = $+ik$, Real term = 0

$1 < \omega < \infty$ Imag term = +ve, Real term = -ve (2)

$$G \cdot m = \frac{1}{(G(s)H(s))} = \frac{1}{|K|} \quad \Delta |G \cdot m|_{dB} = -[20 \log |K|]$$

$\square P_+ = 1, N = 0 \Rightarrow N = P_+ - Z_+ \Rightarrow Z_+ = 1$ zero of c.eq = pole of CLS/T
CLS/T unstable

$\square P_+ = 1, N = 1 \Rightarrow Z_+ = 0 \Rightarrow$ stable closed loop system

$$\frac{(s)}{z(s)} = \frac{G(s)}{1 + G(s)H(s)} = \frac{K(s+1)}{-(1-K)s + (1+K)}$$

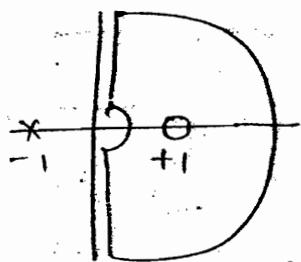
$$+ G(s)H(s) = 0 \Rightarrow -(1-K)s + (1+K) = 0$$

$$+ K = +0.5 \quad -0.5s + 1.5 = 0 \Rightarrow s = +3 \quad +3$$

$$G \cdot m = -[20 \log (0.5)] = +6.02 \text{ dB (unstable)}$$

$$+ K = 2 \quad s+3=0 \Rightarrow s = -3$$

$$G \cdot m = -[20 \log |2|] = -6.02 \text{ dB} \quad (\text{Non min ip. S/T})$$



If this case

This is No m.p.S/T but in right side no pole
so this is stable

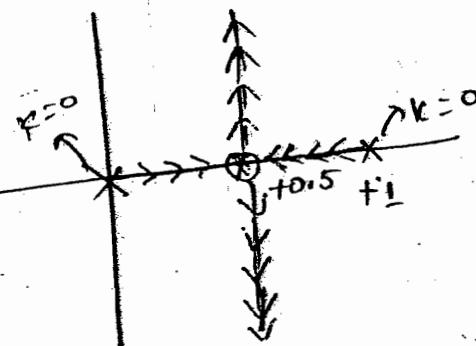
$(s)H(s) = \frac{K(1-s)}{(1+s)}$
so. for S/T $S/T \text{ } G \cdot m = +ve \text{ not } -ve$
because g dont bother about zero on
right side.

$$(G(s)H(s)) = \frac{5}{s(1-s)} \quad \text{if } = \frac{K}{s(1-s)}$$

gain margin

$$= +\infty$$

unstable S/T for all values
of K



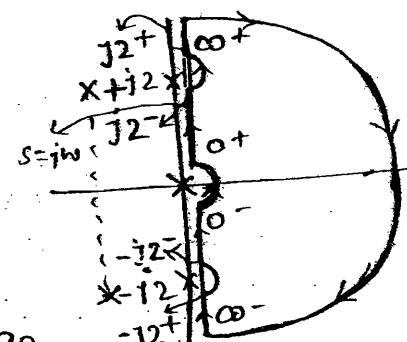
The OLTF of a SIT is $G(s)H(s) = \frac{100}{s(s^2+4)}$ Draw its Nyquist plot and determine G.M. of the system.

so

$$Z^+ = 2 + 0.00 \dots$$

$$Z^- = 2 - 0.00 \dots$$

$$G(i\omega)H(i\omega) = \frac{100}{i\omega(4+(i\omega)^2)}$$



$$G(j\omega)H(j\omega) = \frac{100}{j\omega[(j\omega)^2 + 4]} = \frac{1}{j\omega} = 00 \angle -90^\circ$$

$$G(j\omega)H(j\omega) = 00 \angle -90^\circ$$

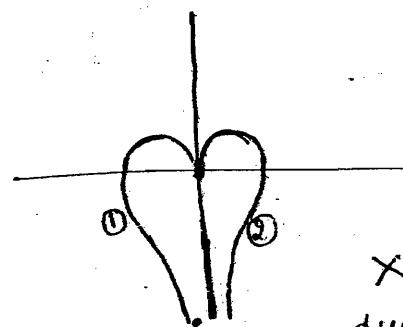
$$G(j\infty)H(j\infty) = \frac{100}{j\infty[(j\infty)^2 + 4]} = \frac{1}{j\infty} = 0 \angle -270^\circ (+90)$$

$$G(j\infty)H(j\infty) = 0 \angle -270^\circ$$

$$G(i\omega)H(i\omega) = -j^2 \frac{100}{1}$$

$$G(i\omega)H(i\omega) = 0 - j \frac{100}{(\omega)[4-\omega^2]}$$

\Rightarrow real term will always remain zero only imaginary term exists.



X bothar
not
due to imag
pole

$$G(j\omega)H(j\omega) = 0 - \frac{j 100}{0[4-0]} = 00 \angle -90^\circ = 0 - j\infty$$

$$G(j0.5)H(j0.5) = 0 - \frac{j 100}{0.5[4-(0.5)^2]} = 0 - j53.36$$

$$G(j1)H(j1) = 0 - \frac{j 100}{1[4-1]} = 0 - j33.33$$

$$G(j1.25)H(j1.25) = 0 - \frac{j 100}{1.25[4-(1.25)^2]} = 0 - j32.82$$

$$G(j1.5)H(j1.5) = 0 - \frac{j 100}{1.5[4-(2.25)]} = 0 - j38.09$$

$$G(j1.75)H(j1.75) = 0 - \frac{j 100}{1.75[4-(1.75)^2]} = 0 - j60.95$$

$$G(j2)H(j2) = 0 - \frac{j 100}{2[4-(2)^2]} = 0 - \frac{j}{1}$$

$$\begin{aligned} -(2^-)^2 &= 4 - 3.99 - - 9 = 0.00 - - 1 \\ -(2^+)^2 &= 4 - 4.000 - - 1 = - 0.00 - - 1 \end{aligned} \quad = 0 - i 100$$

$$q(2^+)H(i2^+) = 0 - i \frac{100}{(2^+)(+0.00 - - 1) \cdot [9 - 4.000 - - 1]}$$

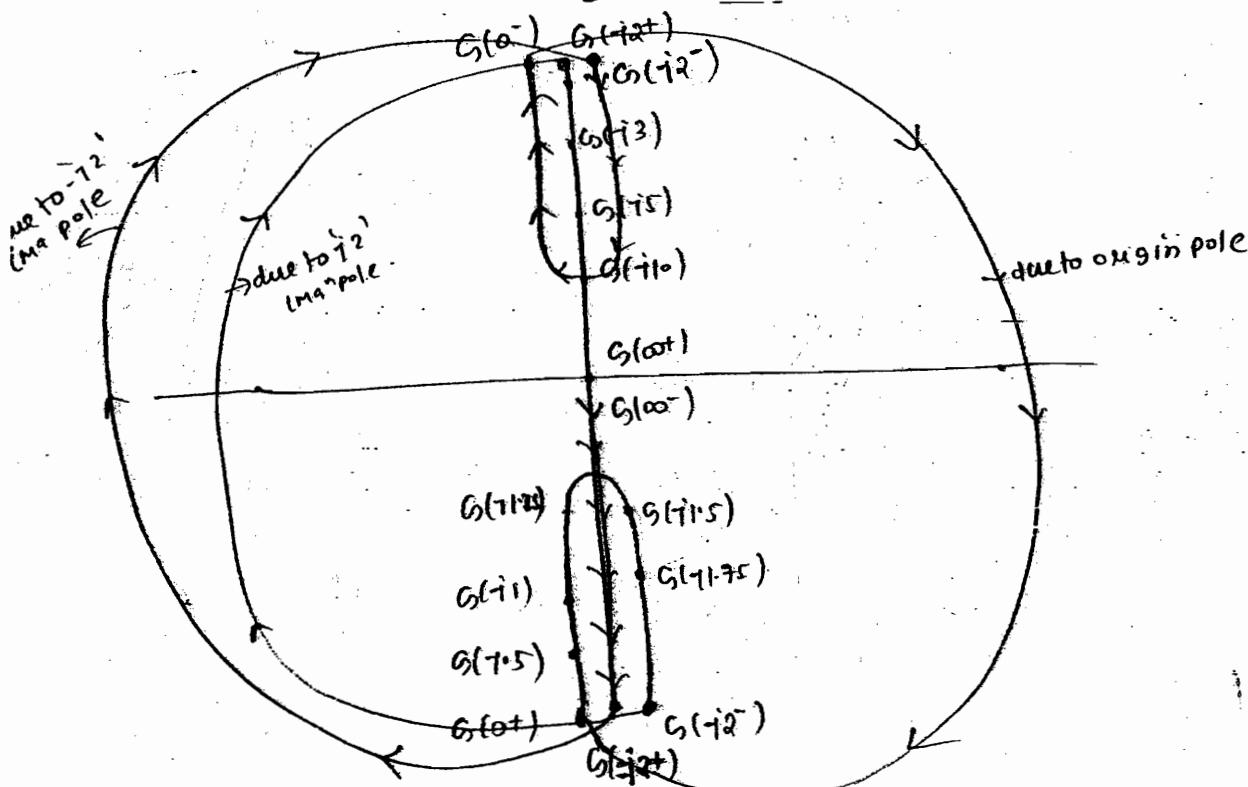
$$= 0 + \frac{i}{(2^+)[+0.00 - - 1]} = 0 + i 100$$

$$\begin{aligned} (-i3)H(-i3) &= 0 - \frac{-i100}{3[4 - 9]} = 0 - \frac{-i100}{3 \times (-5)} = 0 + \frac{i100}{3 \times (+5)} \\ &= 0 + i 6.66 \end{aligned}$$

$$(-i5)H(-i5) = 0 - \frac{-i100}{5[-19]} = 0 + i 10.95$$

$$(i10)H(i10) = 0 - \frac{-i100}{10[4 - 100]} = 0 + i 0.104$$

$$i(100)H(i100) = 0 - \frac{-i100}{\infty[4 - \infty]} = 0 + i 0$$



Given OLT/F Marginally
Stable

These three lines
are single line just for understanding

O

Exact plot

$$P_+ = 0$$

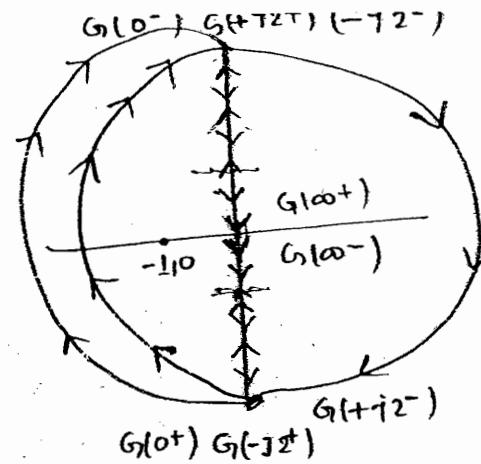
$N = -2$ (Always)

$$N = P_+ - Z_+$$

$$-2 = 0 - Z_+$$

$Z_+ = i2$ — always \Rightarrow always unstable δ_0

$$G \cdot H = -\infty$$



From Root locus:

$K_{\text{for } 100}$

$$G(s)H(s) = \frac{100}{s(s^2+4)} = \frac{K}{s(s^2+4)}$$

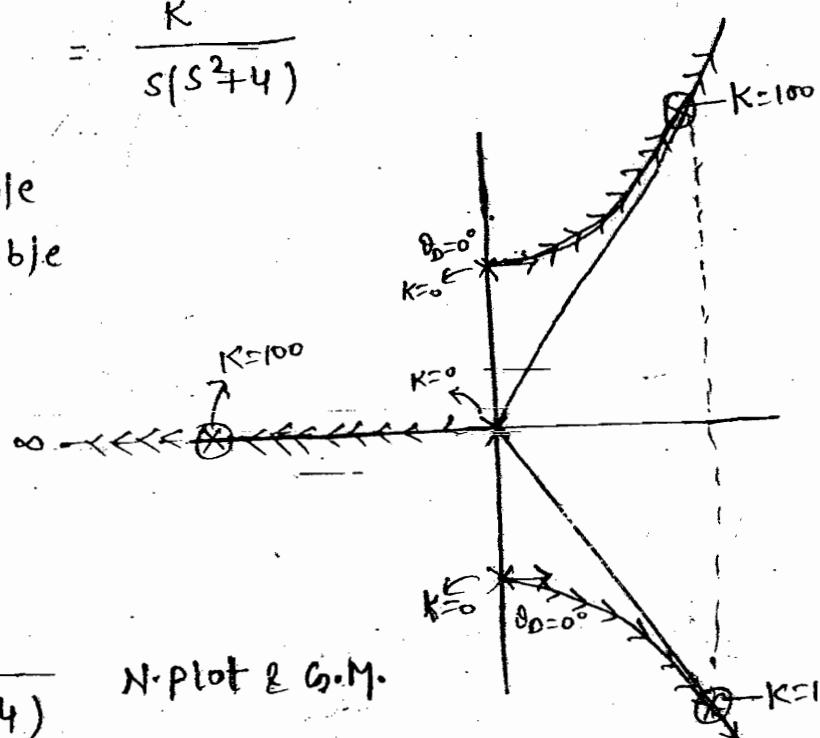
$K=0$ पर Marginally stable

$K=100$ पर Highly unstable

$$G \cdot M = -\infty \quad (\text{M.P.S/I.T})$$

No Breakpoint

Centroid=origin

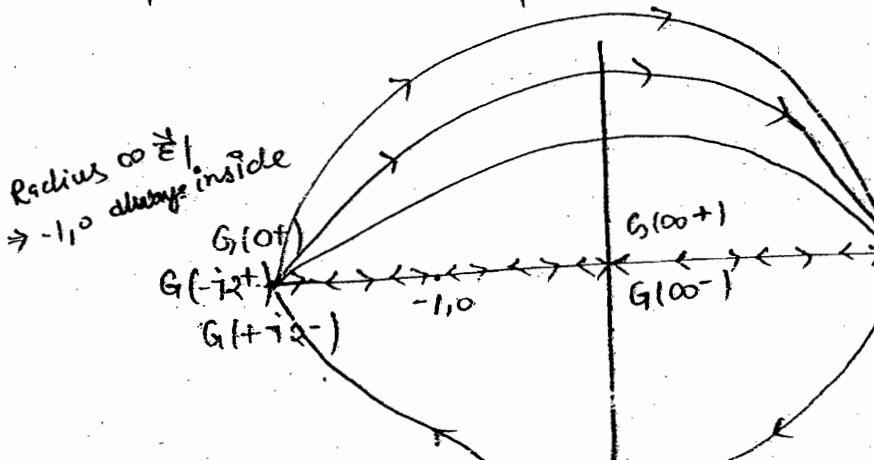


$$\underline{\underline{Q}} \quad G(s)H(s) = \frac{100}{s^2(s^2+4)} \quad N\text{-plot \& G.M.}$$

$$G(j\omega)H(j\omega) = 0 + \frac{100}{(-j\omega)^2[4-\omega^2]} = -\frac{100}{\omega^2[4-\omega^2]} + j0$$

real axis imaginary

\Rightarrow All points exists on real axis.



$$P_+ = 0$$

$$N = -2$$

$$\boxed{Z_+ = 2}$$

unstable

$$\Rightarrow G \cdot M = -\infty$$

From Root locus

poles always
right side
unstable

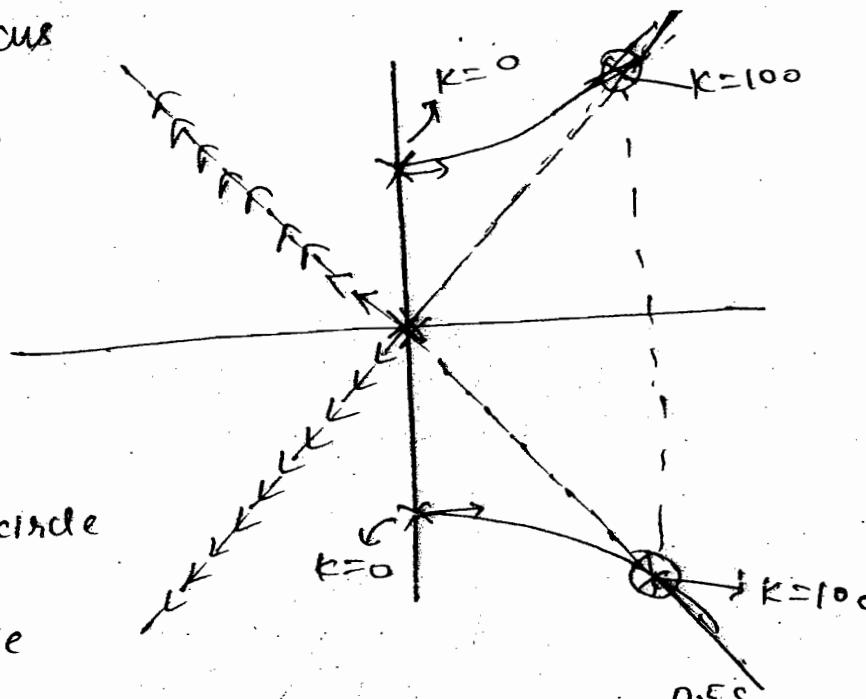
$$\sigma \cdot m = -\infty$$

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

\leftarrow N.P. if semicircle

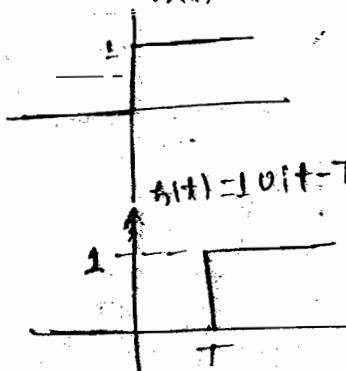
$$G(s)H(s) = \frac{1}{s^2}$$

\leftarrow N.P. if circle



The OLTF of a S/T is $G(s)H(s) = \frac{K \cdot e^{-0.5s}}{s+1}$ draw its N-plot and determine the range of K for close-loop system to be stable.

$$R(t) = 1 u(t) \quad H(s) = \frac{1}{s} \Rightarrow H(j\omega) = \frac{1}{j\omega} = \frac{1}{\omega} \angle -90^\circ$$



$$H(s) = \frac{e^{-st}}{s} \Rightarrow H(j\omega) = \frac{e^{-j\omega t}}{(j\omega)}$$

$$\therefore e^{-j\omega t} = \cos(\omega t) - j \sin(\omega t)$$

$$= \sqrt{\cos^2(\omega t) + \sin^2(\omega t)} \left(\tan^{-1} \left\{ \frac{-\sin(\omega t)}{\cos(\omega t)} \right\} \right)$$

$$= 1 \angle -\omega t$$

$$H(j\omega) = \frac{e^{-j(\omega t)}}{(j\omega)} = \frac{1}{\omega} \angle -90^\circ - (\omega t)$$

The Transportation lag S/T is non minimum phase S/T

NMPs \leftarrow if pole Right side then NMPs \rightarrow unstable

if zero is " " " NMPs \rightarrow not unstable.

$$G(s)H(s) = \frac{K \cdot e^{-0.5s}}{(s+1)}$$

$$G(i\omega)H(i\omega) = \frac{K \cdot e^{-0.5i\omega}}{1+i\omega}$$

$$G(i0)H(i0) = \frac{K \cdot e^{-i0}}{1+i0} = K \angle 0^\circ = K + i0$$

$$G(i\infty)H(i\infty) = \frac{K \cdot e^{-i\infty}}{1+i\infty} = \left(\frac{K}{\infty}\right) \cdot \frac{e^{-i\infty}}{i}$$

$$= 0 \angle -90^\circ$$

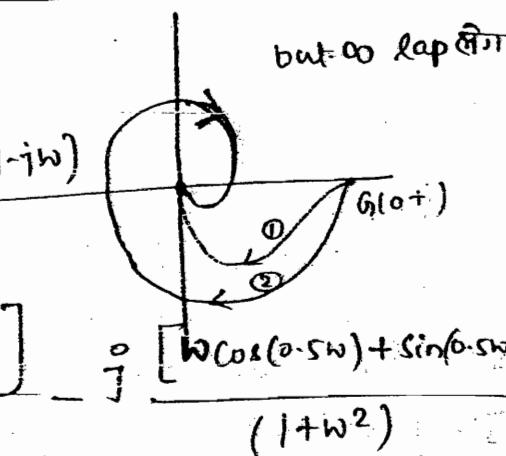
$$= 0 \angle -90 - \infty \times 360^\circ$$

$$= 0 \angle -90^\circ$$

$$G(i\omega)H(i\omega) = \frac{K \cdot e^{-0.5(i\omega)}}{(1+i\omega)(1-i\omega)}$$

$$= \frac{K [\cos(0.5\omega) - i\sin(0.5\omega)]}{(1+\omega^2)} [1-i\omega]$$

$$= \frac{K [\cos(0.5\omega) - \omega\sin(0.5\omega)]}{(1+\omega^2)}$$



for Imaginary term to be zero (ω_{pc})

$$\frac{\omega \cos(0.5\omega) + \sin(0.5\omega)}{1+\omega^2} = 0 \Rightarrow \tan^{-1}(-\omega) = 0.5\omega$$

$$\tan(\omega) = \omega - \frac{\omega^3}{3} + \frac{\omega^5}{5} - \frac{\omega^7}{7} + \dots$$

$$\tan^{-1}(-\omega) = -\omega + \frac{\omega^3}{3} - \frac{\omega^5}{5} + \frac{\omega^7}{7} + \dots$$

Neglect High degree term

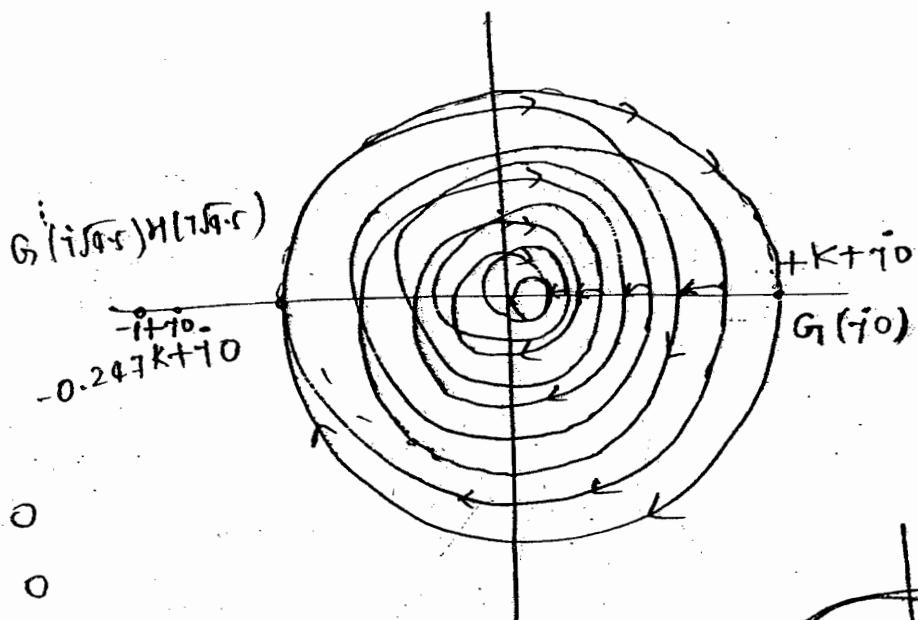
$$-\omega + \frac{\omega^3}{3} = 0.5\omega \Rightarrow \omega [1 - \frac{\omega^2}{4.5}] = 0$$

$$\omega = 0, \pm 2.12$$

$$G(i0)H(i0) = K + i0$$

$$= K \cos(0.5 \times 2.12) - \frac{1}{4.5} \sin(0.5 \times 2.12)$$

$$= -0.2475 + j0$$



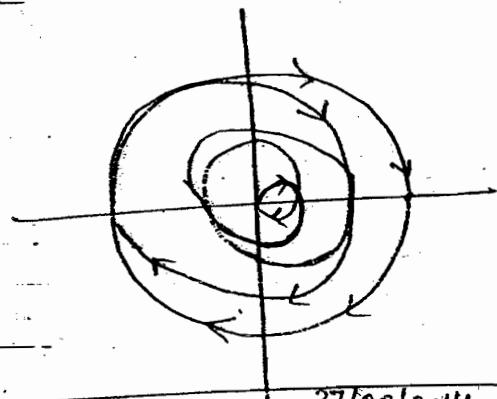
$$P_f = 0$$

$$Z_f = 0$$

$$l = P_f - Z_f = 0 - 0 = 0$$

For stability

$$0.247K < 1 \Rightarrow K < \frac{1}{0.247}$$



27/08/2014

M & N Circle

M circle give the information of Magnitude of closed loop system

N-circle gives information of phase angle of closed loop S/I and when M circle is superimposed on N-circle that chart is known as Nichols chart thus Nichols chart is used to calculate magnitude of closed loop and phase angle of closed loop S/I from its open loop plot

for Nichols chart implementation it is essential that close loop S/I should be of unity feedback.

M-Circle (Magnitude Circle)

given $G(i\omega)H(i\omega) = \text{Something}$ and By Rationalizing

$$G(i\omega)H(i\omega) = x + iy = G(i\omega) \quad \because H(i\omega) = 1$$

$$T(i\omega) = \frac{G(i\omega)}{1 + G(i\omega) \cdot H(i\omega)} = \frac{x + iy}{(1+x) + iy}$$

$$|T(i\omega)| = \frac{\sqrt{x^2 + y^2}}{\sqrt{(1+x)^2 + y^2}} = M \quad (\text{magnitude of CLT/F})$$

$$M^2 = \frac{x^2 + y^2}{(1+x)^2 + y^2} \Rightarrow M^2 [x^2 + 2x + 1 + y^2] = x^2 + y^2$$

$$x^2[1-M^2] - 2 \cdot x M^2 + y^2[1-M^2] = M^2 \quad \dots \textcircled{1}$$

$$x^2 - 2 \cdot x \frac{M^2}{1-M^2} + y^2 \cdot 1 = \frac{M^2}{1-M^2} + \left\{ \frac{M^2}{1-M^2} \right\}^2 = \frac{M^2(1-M^2) +}{(1-M^2)^2}$$

$$+ \left\{ \frac{M^2}{1-M^2} \right\}^2 = \frac{M^2 - M^4 + M^4}{(1-M^2)^2} = \left(\frac{M}{1-M^2} \right)^2$$

$$\left[x - \left(\frac{M^2}{1-M^2} \right) \right]^2 + (y-0)^2 = \left(\frac{M}{1-M^2} \right)^2 \quad \text{Equation of circle}$$

$$\text{Centre} \left\{ \frac{M^2}{1-M^2}, 0 \right\} = \left\{ \frac{M^2}{1-m^2}, 0 \right\} \quad \text{radius} = \left[\frac{M}{1-M^2} \right]$$

$$\boxed{\text{For } M=1} \quad -2x = 1 \Rightarrow x = -\frac{1}{2} \quad (\text{straight line})$$

for $M=1$ eqn of circle will be converted into eqn of line

$$\boxed{M=0} \quad \text{centre } [0,0], \text{ radius } = 0$$

$$\therefore \left[\frac{1}{1-M^2-1}, 0 \right]$$

$$\boxed{M=\infty} \quad \text{centre } [-1,0], \text{ radius } = 0$$

$$\Rightarrow 0 < M < 1 \\ 1 < M < \infty$$

case 1. $0 < M < 1$ * In this case with ↑ M centre of circle will shift toward ∞ at the x-axis and its corresponding radius will also increase so all the circle lie in right side of $M=1$ line lying this region $0 < M < 1$

case 2 $1 < M < \infty$ * In this case with ↑ the value of M centre of circle will shift toward $(1, 0)$ point and its corresponding radius will ↓ all circle lie in the left half side of $M=1$ line lying in this region

N-Circle

$$T(iw) = \frac{x+iy}{(1+x)+iy} \Rightarrow \angle T(iw) = \tan^{-1} \frac{y}{x} = \tan \frac{y}{1+x} = \theta$$

$$= \tan^{-1} \frac{\frac{y}{x} - \frac{y}{1+x}}{1 + \frac{y}{x} \times \frac{y}{1+x}} = \tan^{-1} \frac{y+xy-xy}{x^2+x+y^2}$$

$$\theta = \tan^{-1} \frac{y}{x^2+x+y^2} \Rightarrow \tan \theta = \frac{y}{x^2+x+y^2}$$

$$x^2+x+y^2 = \frac{y}{N} \Rightarrow x^2+x+y^2 - \frac{y}{N} = 0$$

$$x^2 + 2 \cdot x \left(\frac{1}{2}\right) + \left(\frac{1}{2}\right)^2 + y^2 - 2xy \times \frac{1}{2N} + \left(\frac{1}{2N}\right)^2 = \left(\frac{1}{2}\right)^2 + \left(\frac{1}{2N}\right)^2$$

$$\boxed{\left(x+\frac{1}{2}\right)^2 + \left(y-\frac{1}{2N}\right)^2 = \left(\sqrt{\frac{1}{4} + \frac{1}{4N^2}}\right)^2}$$

Centre $\left[\frac{1}{2}, \frac{1}{2N}\right]$, Radius $= \sqrt{\frac{1}{4} + \frac{1}{4N^2}}$

$\Rightarrow 90^\circ$ Centre $\left[-\frac{1}{2}, 0\right], \left[\frac{1}{2}\right]$

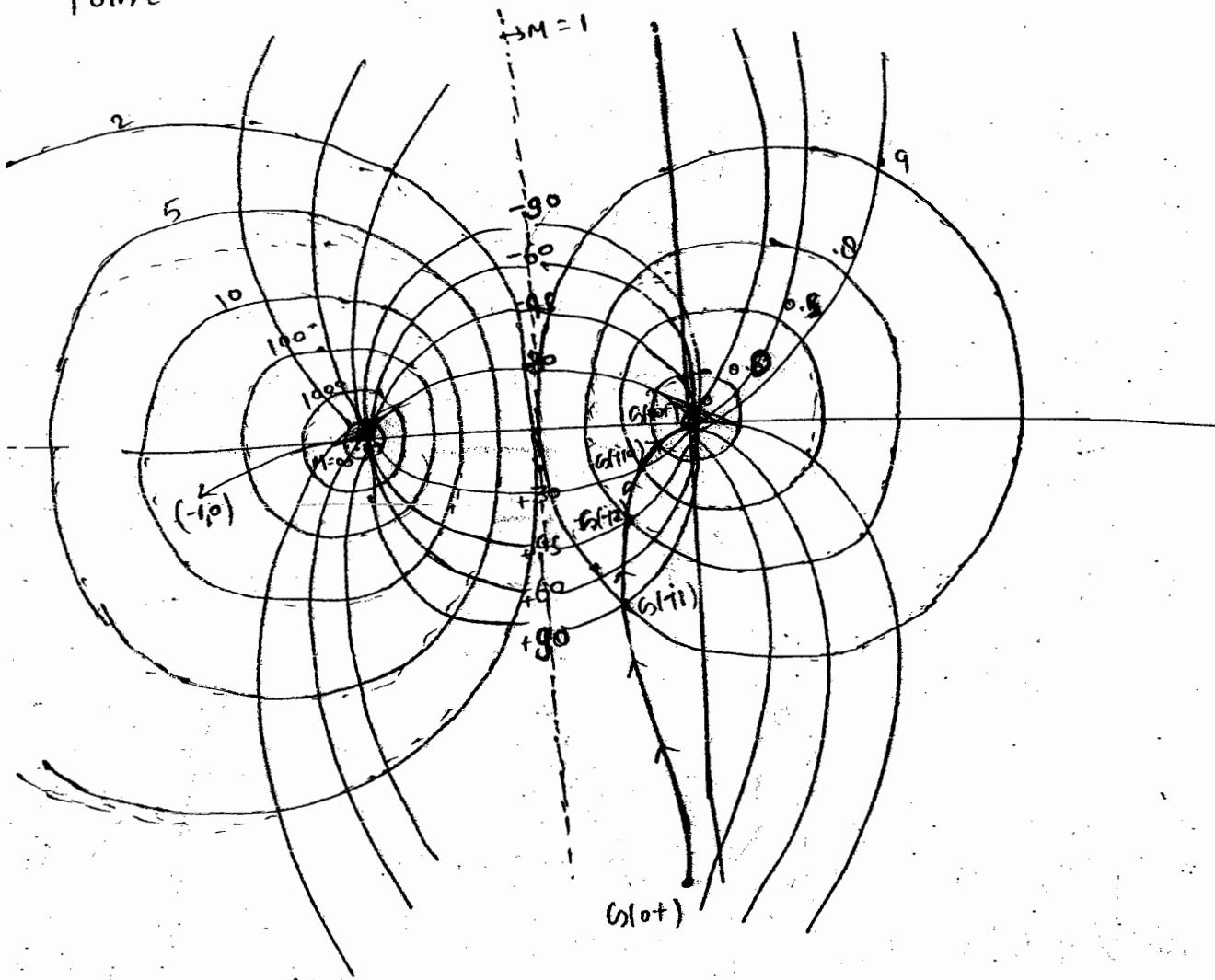
$\Rightarrow -90^\circ$ Centre $\left[-\frac{1}{2}, 0\right], \left[-\frac{1}{2}\right]$

$\theta = 0^\circ, N = 0^\circ$. Centre $(-\frac{1}{2}, \infty)$, radius $\infty \rightarrow x\text{-axis}$.

$\theta = +ve, N = +ve$ centre $(-\frac{1}{2}, +ve y)$

$\theta = -ve, N = -ve$ centre $(-\frac{1}{2}, -ve y)$

* The centre of N -circle will locate at $M=L$ line and all N -circle will pass through origin and $(-1, 0)$ Point.



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

$$G(iw) = \frac{K}{iw(1+iw)} = \frac{K}{w\sqrt{1+w^2}} \left[-90 - \tan^{-1} \frac{w}{1} \right]$$

$$G(i0)H(i0) = \infty \left[-90^\circ \right]$$

$$G(i1)H(i1) = \frac{K}{\sqrt{2}} \left[-135^\circ \right]$$

$$G(i2)H(i2) = \frac{K}{2\sqrt{5}} = \left[-153^\circ \right]$$

$$G(i\infty)H(i\infty) = 0 \left[-180^\circ \right]$$

$$T(i\omega) = \frac{G(i\omega)}{1 + G(i\omega)H(i\omega)}$$

$$T(i1) = 0.9 \angle +90^\circ, T(i2) = 0.8 \angle +45^\circ$$

$$T(i10) = 0.5 \angle 30^\circ$$

STATE SPACE Analysis

If any S/I has zero initial condition in that case overall o/p response will be zero state response and both space state space analysis and T/F will give same o/p response Hence for convenience of calculation we will follow T/F method to calculate o/p response.

If any S/I has finite initial condition in that case overall o/p response will be sum of zero state response and zero input response while T/F method will give only zero input response which is incorrect so we will follow state space analysis to calculate its o/p response.

State eqn is a differential eqn which contains only state variable and input. Holding property will exists only with state variable while input will have instantaneous effect capacitor voltage is a state variable while capacitor current is input for charging or discharging of state variable.

Inductor current is a state variable while inductor voltage is input for charging or discharging of inductor current.

- * state variable has non unique solution while output off has unique solution also eigen value on which is location of pole has unique identity
- * state matrix is in the form of

$$[\dot{x}] = [A]_{n \times n} [x] + [B]_{n \times l} [u]$$

$$[y] = [C]_{m \times n} [x] + [D]_{m \times l} [u]$$

where x is state variable, u = input, y = output

n = is total no of state variable,

l = is total no of input

m = is total no of output

① DIRECT DECOMPOSITION METHOD

$$\frac{Y(s)}{U(s)} = \frac{a_0 s^3 + a_1 s^2 + a_2 s + a_3}{s^3 + b_1 s^2 + b_2 s + b_3}$$

$$= \frac{a_0 + \frac{a_1}{s} + \frac{a_2}{s^2} + \frac{a_3}{s^3}}{1 + \left[-\frac{b_1}{s} - \frac{b_2}{s^2} - \frac{b_3}{s^3} \right]}$$

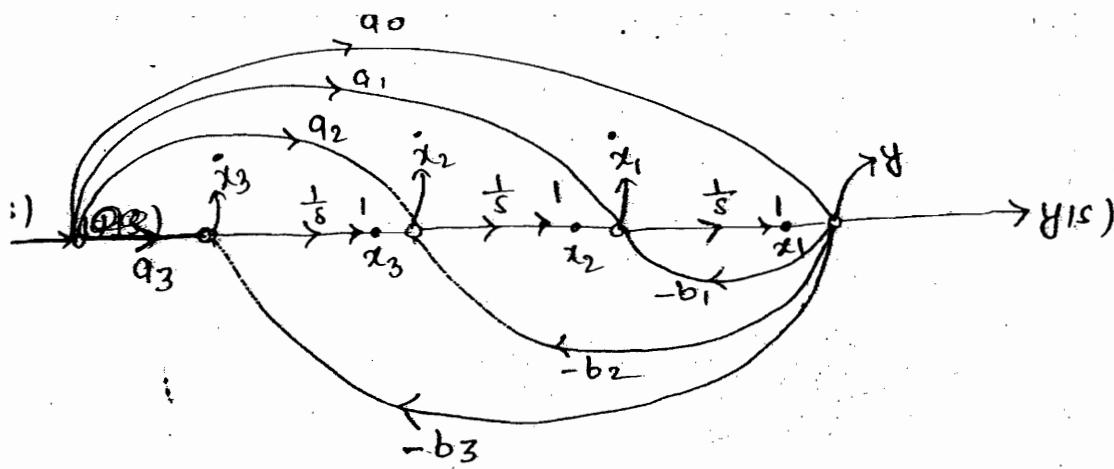
$$\text{Mason Gain formulae} = \frac{\sum P_k \Delta K}{\Delta}$$

| | | |
|--------|----------------|----------------------------|
| $Z(s)$ | $\frac{1}{s}$ | $X(s)$ |
| $X(s)$ | $\frac{1}{s}$ | $Z(s)$ |
| $Z(s)$ | $s \cdot X(s)$ | $Z(t) = \frac{d}{dt} x(t)$ |
| $Z(t)$ | \dot{x} | |

$$\Delta_K = 1 - [\text{sum of all loop not touching } k^{\text{th}} \text{ f.p. path}] + [\text{sum of product of two n.t. loop not touch } k^{\text{th}} \text{ f.p. path}] + \dots$$

$$\Delta = 1 - [\text{sum of all loop}] + [\text{S.O.P. of two non touching loop}] - [\text{S.O.P. of three non touching loop}]$$

$$= \frac{P_1 \Delta_1 + P_2 \Delta_2 + P_3 \Delta_3 + P_4 \Delta_4}{1 - [\text{sum of all loop}]} = \frac{P_1 + P_2 + P_3 + P_4}{1 - [L_1 + L_2 + L_3]}$$



equations from this SFG.

$$y = 1 \cdot x_1 + q_0 u, \quad \dot{x}_1 = 1 \cdot x_2 + q_1 u - b_1 y$$

$$\dot{x}_1 = 1 \cdot x_2 + q_1 u - b_1 [x_1 + q_0 u] \Rightarrow \dot{x}_1 = -b_1 x_1 + 1 x_2 + (q_1 - b_1 q_0) u$$

$$\dot{x}_2 = 1 \cdot x_3 + q_2 u - b_2 y \Rightarrow \dot{x}_2 = 1 \cdot x_3 + q_2 u - b_2 [x_1 + q_0 u]$$

$$\dot{x}_2 = -b_2 x_1 + 1 x_3 + (q_2 - b_2 q_0) u$$

$$\dot{x}_3 = q_3 u - b_3 y \Rightarrow \dot{x}_3 = q_3 u - b_3 [1 x_1 + q_0 u]$$

$$\Rightarrow \dot{x}_3 = -b_3 x_1 + (q_3 - b_3 q_0) u$$

state matrix and output matrix

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} = \begin{bmatrix} -b_1 & 1 & 0 \\ -b_2 & 0 & 1 \\ -b_3 & 0 & 0 \end{bmatrix}_{3 \times 3} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} q_1 - b_1 q_0 \\ q_2 - b_2 q_0 \\ q_3 - b_3 q_0 \end{bmatrix}_{3 \times 1} [u]$$

$$[y] = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix}_{1 \times 3} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} q_0 \end{bmatrix}_{1 \times 1} [u]$$

Phase-variable form:

In phase variable form all element of either first column or last row exists and element just above the diagonal element will be one while rest of the other element will be zero and by using direct decomposition method state variable will always be in state $\xrightarrow{\text{state matrix}}$ phase variable form.

$$[\dot{x}] = [A]_{n \times n} [x] + [B]_{n \times e} [u]$$

$$[y] = [C]_{m \times n} [x] + [D]_{m \times e} [u]$$

The rank of state matrix A will be equal to the total no of state variable.

Parallel decomposition method:

$$\frac{y(s)}{u(s)} = \frac{1}{(s+2)(s+3)(s+4)} = \frac{q_0}{s+2} + \frac{q_1}{s+3} + \frac{q_2}{s+4}$$

$$= \frac{(1|2)}{s+2} + \frac{(-1)}{s+3} + \frac{(1|2)}{s+4} = \cancel{x_1(s)} + \cancel{x_2(s)} + \cancel{x_3(s)}$$

$$x_1(s) = \frac{1|2}{s+2}$$

$$y(s) = \frac{1|2}{s+2} u(s) + \left(\frac{-1}{s+3}\right) u(s) + \frac{(1|2)}{s+4} u(s) = x_1(s) + x_2(s) + x_3(s)$$

$$x_1(s) = \frac{1|2}{s+2} u(s) \Rightarrow (s+2)x_1(s) = \frac{1}{2} u(s)$$

$$sx_1(s) + 2x_1(s) = \frac{1}{2} u(s) \Rightarrow sx_1(s) = -2x_1(s) + \frac{1}{2} u(s)$$

$$\dot{x}_1 = -2x_1 + \frac{1}{2} u$$

first state eqn

$$x_2(s) = \frac{-1}{s+3} u(s) \Rightarrow sx_2(s) + 3x_2(s) = -1 u(s)$$

$$sx_2(s) = -3x_2(s) + (-1)u(s) \Rightarrow \boxed{\dot{x}_2 = -3x_2 + (-1)u}$$
2nd

$$x_3(s) = \frac{1/2}{s+4} u(s) \Rightarrow s x_3(s) + 4 x_3(s) = \frac{1}{2} u(s)$$

$$x_3(s) = -4 x_3(s) + \frac{1}{2} u(s) \Rightarrow \dot{x}_3 = -4 x_3 + \frac{1}{2} u$$

3rd

$$y = x_1 + x_2 + x_3$$

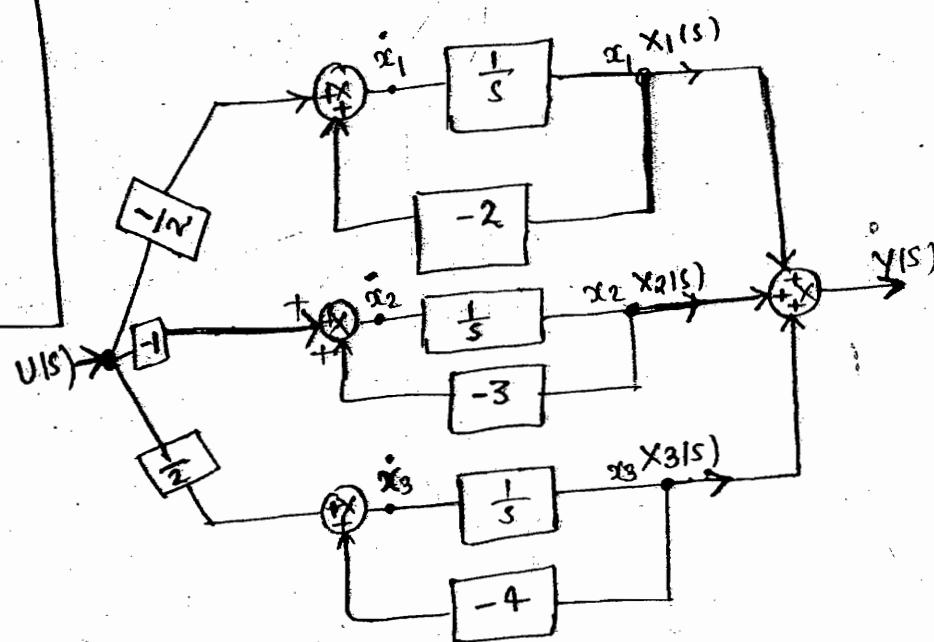
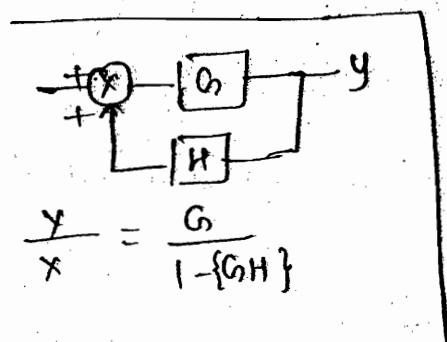
state matrix from these state equation -

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} = \begin{matrix} \nearrow A \\ \begin{bmatrix} -2 & 0 & 0 \\ 0 & -3 & 0 \\ 0 & 0 & -4 \end{bmatrix} \\ \searrow 3 \times 3 \end{matrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} (1/2) \\ (-1) \\ (1/2) \end{bmatrix} [u]$$

$$[y] = \begin{matrix} \downarrow C \\ \begin{bmatrix} 1 & 1 & 1 \end{bmatrix}_{1 \times 3} \end{matrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{matrix} \downarrow D \\ \begin{bmatrix} 0 \end{bmatrix}_{1 \times 1} \end{matrix} [u]$$

By using parallel decomposition method state matrix A will always be a diagonal matrix and its diagonal element represents eigen value which is location of pole.

$$\frac{x_1(s)}{u(s)} = \frac{1/2}{s+2} = \frac{1}{2} \times \left\{ \frac{\left(\frac{1}{s}\right)}{1 - \left[\left(\frac{1}{s}\right) \cdot (-2)\right]} \right\}$$

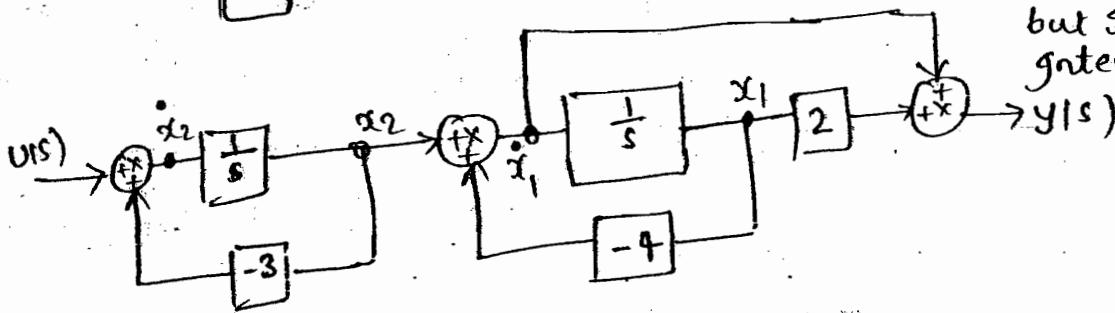
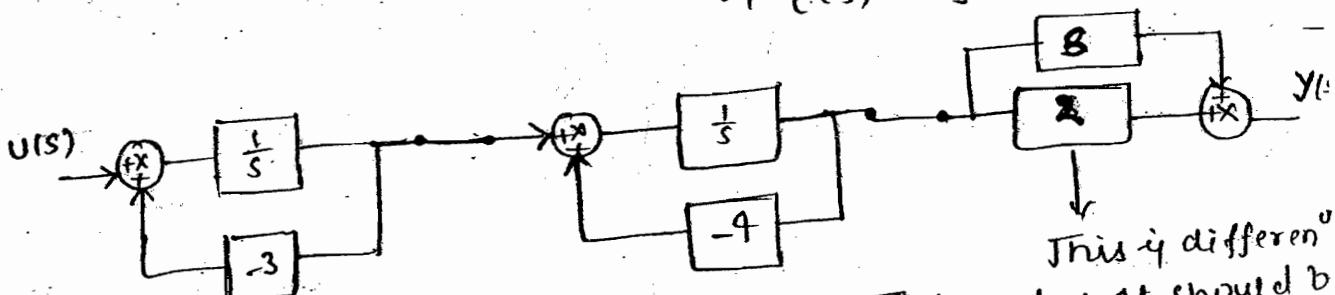


$$\frac{x_2(s)}{u(s)} = \frac{-1}{s+3} = (-1) \times \left\{ \frac{\frac{1}{s}}{1 - \left[\left(\frac{1}{s} \right) \times (-3) \right]} \right\}$$

$$\frac{x_3(s)}{u(s)} = \frac{1/2}{s+4} = \left(\frac{1}{2} \right) \times \left\{ \frac{\frac{1}{s}}{1 - \left[\left(\frac{1}{s} \right) \times (-4) \right]} \right\}$$

Cascade decomposition Method

$$\begin{aligned} \frac{y(s)}{u(s)} &= \frac{(s+2)}{(s+3)(s+4)} = (s+2) \times \frac{1}{(s+3)} \times \frac{1}{(s+4)} \\ &= (s+2) \times \left\{ \frac{\frac{1}{s}}{1 - \left[\left(\frac{1}{s} \right) \times (-3) \right]} \right\} \times \left\{ \frac{\frac{1}{s}}{1 - \left[\left(\frac{1}{s} \right) \times (-4) \right]} \right\} \end{aligned}$$



$$y = 2x_1 + \dot{x}_1, \quad \dot{x}_1 = -4x_1 + 1 \cdot x_2$$

$$y = 2x_1 - 4x_1 + 1 \cdot x_2 \Rightarrow y = -2x_1 + 1x_2$$

$$\dot{x}_2 = -3x_2 + u \cdot 1$$

total No. of pole = to No. of state variable
= rank of state matrix.

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} -4 & 1 \\ 0 & -3 \end{bmatrix}_{2 \times 2} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}_{2 \times 1} + \begin{bmatrix} 0 \\ 1 \end{bmatrix}_{2 \times 1} [u]$$

$$[y] = \begin{bmatrix} -2 & 1 \end{bmatrix}_{1 \times 2} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}_{2 \times 1} + \begin{bmatrix} 0 \end{bmatrix}_{1 \times 1} [u]$$

Rank of state matrix [A] = 2 = to No. of pole = total No. of state variables

By using cascade 'decom' method state matrix [A] will always be U.T.M and its diagonal element represents eigen value which is location of pole.

Solution of State Matrix

$$[\dot{x}] = [A][x] + [B][u] \quad \text{Laplace}$$

$$[sX(s) - x(0)] = [A]X(s) + [B]U(s)$$

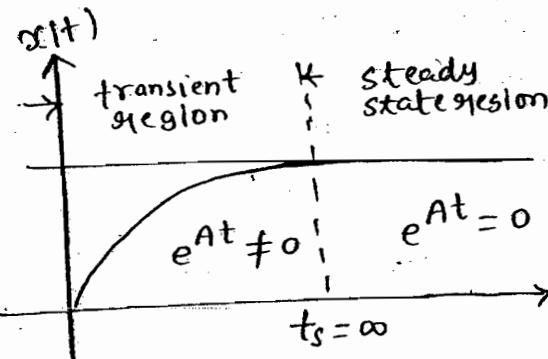
$$[sI-A]X(s) = x(0) + [B]U(s) \Rightarrow X(s) = \frac{1}{[sI-A]}x(0) + \frac{1}{[sI-A]}[B]U(s)$$

$$X(s) = [sI-A]^{-1}x(0) + [sI-A]^{-1}[B]U(s)$$

inverse Laplace

$$x(t) = e^{At}x(0) + B e^{At}U$$

↓
transient region



$[sI-A]^{-1} \rightarrow$ transient element in L.D.

$e^{At} \rightarrow$ transient element in T.D.

$[sI-A]^{-1} \rightarrow$ state transition Matrix.

$$[I]_{n \times n} = \begin{bmatrix} I & 0 \\ 0 & I \end{bmatrix}$$

$$[I]_{1 \times 1} = 1$$

$$X(s) = [sI-A]^{-1}x(0) + [sI-A]^{-1}[B]U(s)$$

↓
Zero input response ↳ zero state response

$$\boxed{\text{overall output response} = ZIR + ZSR}$$

↓
Transfer funⁿ
method

* If any S/T was zero initial condition then overall O/P response will be zero state response and T/F method also gave zero state response so in that case we will follow T/F method

calculate o/p response if any SIT was finite initial condⁿ in that case overall o/p response will be sum of zero state response and zero input response while TLF method will give only ZSR which will be less than overall o/p response while ZIR

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 1 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 1 \\ 0 \end{bmatrix} [u] \quad \begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix} = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$[y] = [1 \ 0] \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + [0] [u]$$

on the given state matrix obtain time dependent relation of state variable and o/p if input is unit step

Solⁿ first method $\dot{x}_1 = 1x_1 + 1u(t)$, $\dot{x}_2 = 1x_1 + 1x_2 + 1u(t)$

apply L.T. $[sx_1(s) - x_1(0)] = 1x_1(s) + \left(\frac{1}{s}\right)$

$$(s-1)x_1(s) = x_1(0) + \frac{1}{s} = 1 + \frac{1}{s} = \frac{(s+1)}{s} \Rightarrow x_1(s) = \frac{s+1}{s(s-1)}$$

$$x_1(s) = \frac{s+1}{s(s-1)} = \frac{90}{s} + \frac{91}{s-1} = \frac{-1}{s} + \frac{2}{(s-1)}$$

$$x_1(t) = -1 + 2e^t$$

$$[sx_2(s) - x_2(0)] = x_1(s) + x_2(s) + \frac{1}{s}$$

$$(s-1)x_2(s) = x_1(s) + x_2(0) + \frac{1}{s} = \frac{s+1}{s(s-1)} + 0 + \frac{1}{s}$$

$$(s-1)x_2(s) = \frac{s+1+s-1}{s(s-1)} = \frac{2}{s-1} \Rightarrow x_2(s) = \frac{2}{(s-1)^2}$$

$$x_2(t) = 2t e^t$$

$$\text{o/p } y = 1x_1 + 0x_2 + 0u = x_1 \Rightarrow y = x_1(t) = -1 + 2e^t$$

output

Diagonal form El eq use. प्रति ए

$$\text{econ. method} \quad [x(s)] = [sI - A]^{-1} \cdot [x(0)] + [sI - A]^{-1} [B][u(s)]$$

$$[I] = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \Rightarrow s[I] = \begin{bmatrix} s & 0 \\ 0 & s \end{bmatrix}$$

$$[sI - A] = \begin{bmatrix} s & 0 \\ 0 & s \end{bmatrix} - \begin{bmatrix} 1 & 0 \\ 1 & 1 \end{bmatrix} = \begin{bmatrix} (s-1) & 0 \\ -1 & (s-1) \end{bmatrix}$$

$$\text{Co-factor} = \begin{bmatrix} (-1)^{1+1}(s-1) & (-1)^{1+2}(-1) \\ (-1)^{2+1} \cdot 0 & (-1)^{2+2}(s-1) \end{bmatrix} = \begin{bmatrix} (s-1) & +1 \\ 0 & (s-1) \end{bmatrix}$$

$$\text{Adj} = \begin{bmatrix} (s-1) & 0 \\ +1 & (s-1) \end{bmatrix} \Rightarrow [sI - A]^{-1} = \frac{\text{Adj}}{|\text{Det}|} = \frac{\begin{bmatrix} (s-1) & 0 \\ 1 & (s-1) \end{bmatrix}}{(s-1)^2}$$

$$[sI - A]^{-1} = \frac{\begin{bmatrix} s-1 & 0 \\ 1 & s-1 \end{bmatrix}}{(s-1)^2} = \begin{bmatrix} \frac{1}{s-1} & 0 \\ \frac{1}{(s-1)^2} & \frac{1}{s-1} \end{bmatrix}$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s-1) & 0 \\ 1 & (s-1) \end{bmatrix}}{(s-1)^2} \begin{bmatrix} 1 \\ 0 \end{bmatrix} + \frac{\begin{bmatrix} (s-1) & 0 \\ 1 & (s-1) \end{bmatrix}}{(s-1)^2} \begin{bmatrix} 1 \\ 1 \end{bmatrix} \left(\frac{1}{s}\right)$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s-1) \\ 1 \end{bmatrix}}{(s-1)^2} + \frac{\begin{bmatrix} (s-1) \\ 1+s-1 \end{bmatrix}}{s(s-1)^2} = \begin{bmatrix} \frac{1}{s-1} \\ \frac{1}{(s-1)^2} \end{bmatrix} + \begin{bmatrix} \frac{1}{s(s-1)} \\ \frac{1}{s(s-1)^2} \end{bmatrix}$$

$$= \begin{bmatrix} \frac{1}{s-1} + \frac{1}{s(s-1)} \\ \frac{2}{(s-1)^2} \end{bmatrix} = \begin{bmatrix} \frac{s+1}{s(s-1)} \\ \frac{2}{(s-1)^2} \end{bmatrix}$$

$$\Rightarrow x_1(s) = \frac{s+1}{s(s-1)}, \quad x_2(s) = \frac{2}{(s-1)^2}$$

$$x_1(s) = \frac{q_0}{s} + \frac{q_1}{s-1} = \frac{-1}{s} + \frac{2}{s-1}$$

$$x_1(t) = -1 + 2e^{+1t}$$

$$x_2(t) = 2 \cdot t e^{+1t}$$

If g used T/F method then initial condition = $x(0) = 0$.

$$x_1(s) = \frac{1}{s(s-1)} = \frac{-1}{s} + \frac{1}{s-1}, x_2(s) = \frac{1}{(s-1)^2}$$
$$\text{Hence } x_1(t) = -1 + 1 \cdot e^{+1t} \quad x_2(t) = t e^{+1t}$$

Diagonalizing process

* If given state matrix $[A]$ is not in diagonal form then by using diagonalization process we will convert state matrix $[A]$ into diagonal M and its diagonal element represents its eigenvalue which is location of pole.

Case 1 If state matrix $[A]$ is not in phase variable for

In this case we use $[1I-A]=0$ to calculate eigen value if we replace 1 by s then this will be characteristic eqn of given T/F or system then we will use this relation $[1I-A][x]=0$ to calculate eigen vector and from that eigen vector we will construct model matrix $[M]$ then by variable transformation we will transform state variable x into new state variable z .

$$[x] = [M][z], [\dot{x}] = [M][\dot{z}], z(0) = [M]^{-1}x(0)$$

if \nearrow Non diagonal Matrix

$$[\dot{x}] = [A][x] + [B][u]$$

$$[y] = [C][x] + [D][u]$$

Note $[M][\dot{z}] = [A][M][z] + [B][u]$

$$[y] = [C][M][z] + [D][u] \rightarrow B$$

$$[\dot{z}] = \left\{ [M]^{-1} \overbrace{[A][M]}^A \right\} [z] + \left\{ [M]^{-1}[B] \right\} [u]. \longrightarrow (A)$$

case 2 if given state Matrix $[A]$ is in phase variable form in this case we use $[I - A] = 0$ to calculate eigen value and this eigen value itself will be location of pole then from this eigen value we will construct vandermonde Matrix.

$$[V] := \begin{bmatrix} 1 & 1 \\ 1 & \lambda_2 \end{bmatrix} \text{ where } \lambda_1 \text{ and } \lambda_2 \text{ are eigen value}$$

then by variable transformation we will transform state variable x into new state variable z

$$[x] = [V][z] \Rightarrow [\dot{x}] = [V][\dot{z}]$$

$$z(0) = [V]^{-1}x(0)$$

$$[\dot{x}] = [A][x] + [B][u]$$

$$[y] = [C][x] + [D][u]$$

$$[\dot{z}] = \left\{ [M^{-1}]^{-1} \overbrace{[A][M]}^A \right\} [z] + \left\{ [V]^{-1} \overbrace{[B]}^B \right\} [u]$$

$$[y] = \left\{ [C][V] \right\} [z] + [D][u]$$

for the given state matrix, obtain time dependent relation of state variable and output if input is unit step input

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \underbrace{\begin{bmatrix} 1 & 4 \\ -2 & -5 \end{bmatrix}}_{[A]} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 1 \end{bmatrix} [u]$$

$$\begin{bmatrix} z_1(0) \\ z_2(0) \end{bmatrix} = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$[y] = \underbrace{\begin{bmatrix} 1 & 0 \end{bmatrix}}_{[C]} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \end{bmatrix} [u]$$

This matrix is not in diagonal form & not in p.v.form

so it's case 1

$$[A - I] = \begin{bmatrix} 1-1 & -4 \\ 2 & 1+5 \end{bmatrix} \Rightarrow |A - I| = (1-1)(1+5) + 8$$

$(1+1)(1+3) = 0 \Rightarrow \lambda = -1, -3$ (\Rightarrow location of pole)

$$[A - I] [x] = 0 \Rightarrow \begin{bmatrix} 1-1 & -4 \\ 2 & 1+5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = 0$$

For $\lambda = -1$

$$\begin{bmatrix} -2 & -4 \\ 2 & 4 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = 0 \Rightarrow -2x_1 - 4x_2 = 0 \Rightarrow \boxed{x_1 + 2x_2 = 0}$$

$$2x_1 + 4x_2 = 0 \Rightarrow \boxed{x_1 + 2x_2 = 0} \quad \text{if } x_1 = 1 \text{ then } x_2 = -0.5$$

For $\lambda = -3$

$$\begin{bmatrix} -4 & -4 \\ 2 & 2 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = 0 \quad \begin{array}{l} -4x_1 - 4x_2 = 0 \Rightarrow \boxed{x_1 + x_2 = 0} \\ 2x_1 + 2x_2 = 0 \Rightarrow \boxed{x_1 + x_2 = 0} \end{array} \quad \begin{array}{l} \text{if } x_1 = 1 \\ \text{then } x_2 = -1 \end{array}$$

$$[M] = \begin{bmatrix} 1 & 1 \\ -0.5 & 1 \end{bmatrix} \Rightarrow M^{-1} = \begin{bmatrix} 2 & 2 \\ -1 & -2 \end{bmatrix}$$

Note

$$[M]^{-1} \cdot [A] \cdot [M] = \begin{bmatrix} 2 & 2 \\ -1 & -2 \end{bmatrix} \begin{bmatrix} 1 & 4 \\ -2 & -5 \end{bmatrix} \begin{bmatrix} 1 & 1 \\ -0.5 & 1 \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & -3 \end{bmatrix}$$

$$[M]^{-1} [B] = \begin{bmatrix} 2 & 2 \\ -1 & -2 \end{bmatrix} \begin{bmatrix} 0 \\ 1 \end{bmatrix} = \begin{bmatrix} 2 \\ -2 \end{bmatrix}$$

$$[C][M] = \begin{bmatrix} 1 & 0 \\ -0.5 & 1 \end{bmatrix} \begin{bmatrix} 1 & 1 \\ -0.5 & 1 \end{bmatrix} = \begin{bmatrix} 1 & 1 \end{bmatrix}$$

$$\begin{bmatrix} z_1(0) \\ z_2(0) \end{bmatrix} = [M]^{-1} \begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix} = \begin{bmatrix} 2 & 2 \\ -1 & -2 \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix} = \begin{bmatrix} 2 \\ -1 \end{bmatrix}$$

Now substitute these all in eqn (A)

$$\begin{bmatrix} \dot{z}_1 \\ \dot{z}_2 \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & -3 \end{bmatrix} \begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + \begin{bmatrix} 2 \\ -2 \end{bmatrix} [U]$$

$$[Y] = [1 \ 1] \begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + [0] [U]$$

$$\text{solution} \quad \dot{z}_1 = -z_1 + 2u, \quad \dot{z}_2 = -3z_2 - 2u$$

King L.T.

$$sz_1(s) - z_1(0) = -z_1(s) + \frac{2}{s} \Rightarrow (s+1)z_1(s) = z_1(0) + \frac{2}{s}$$

$$\downarrow$$

$$\Rightarrow z_1(s) = \frac{2}{s}, \quad [z_1(t) = 2u(t)]$$

$$z_2(s) - z_2(0) = -3z_2(s) - \frac{2}{s} \Rightarrow (s+3)z_2(s) = z_2(0) - \frac{2}{s}$$

$$z_2(s) = \frac{-(s+2)}{s(s+3)} \Rightarrow z_2(s) = \frac{q_0}{s} + \frac{q_1}{s+3} = \frac{-2/3}{s} - \frac{1/3}{s+3}$$

$$[z_2(t) = -\frac{2}{3}u(t) - \frac{1}{3}e^{-3t}]$$

$$[x] = [M][z]$$

$$\begin{bmatrix} x_1(t) \\ x_2(t) \end{bmatrix} = \begin{bmatrix} 1 & 1 \\ -0.5 & -1 \end{bmatrix} \begin{bmatrix} z_1(t) \\ z_2(t) \end{bmatrix} \Rightarrow \begin{bmatrix} x_1(t) \\ x_2(t) \end{bmatrix} = \begin{bmatrix} 1 & 1 \\ -0.5 & -1 \end{bmatrix} \begin{bmatrix} 2u(t) \\ -\frac{2}{3} - \frac{1}{3}e^{-3t} \end{bmatrix}$$

$$= \begin{bmatrix} 2 - \frac{2}{3} - \frac{1}{3}e^{-3t} \\ -1 + \frac{2}{3} + \frac{1}{3}e^{-3t} \end{bmatrix} = \begin{bmatrix} \frac{4}{3} - \frac{1}{3}e^{-3t} \\ -\frac{1}{3} + \frac{1}{3}e^{-3t} \end{bmatrix}$$

$$[x_1(t) = \frac{4}{3} - \frac{1}{3}e^{-3t}], \quad [x_2(t) = -\frac{1}{3} + \frac{1}{3}e^{-3t} = -\frac{1}{3} + \frac{1}{3}e^{-3t}]$$

$$y(t)$$

for the given state matrix obtain its soln by using diagonalization method if input is unit step.

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ -6 & -5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 1 \end{bmatrix} [u]$$

$$[y] = \begin{bmatrix} 6 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \end{bmatrix} [u]$$

$$\begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix} = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

Q1 This is case 2

$$P(I-A) = \begin{bmatrix} 1 & -1 \\ 6 & 1+5 \end{bmatrix}, |(I-A)| = \lambda^2 + 5\lambda + 6 = 0$$

$$\Rightarrow \lambda = -2, -3$$

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

$$\begin{bmatrix} z_1 \\ z_2 \end{bmatrix} = \begin{bmatrix} -2 & 0 \\ 0 & -3 \end{bmatrix} \begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \end{bmatrix} [0]$$

$$y = [4, 3] \begin{bmatrix} z_1 \\ z_2 \end{bmatrix} + [0] [0]$$

\downarrow poln

TRANSFER FUNCTION FROM STATE MATRIX

$$\frac{Y(s)}{U(s)} = [C][SI-A]^{-1}[B] + [D] \rightarrow \text{overall T/F}$$

\rightarrow unique solution

$$\frac{x_1(s)}{U(s)} = [SI-A]^{-1}[B] \rightarrow \text{T/F of state variable}$$

\rightarrow non unique solution

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} 1 & -2 \\ +4 & -5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 2 \\ 1 \end{bmatrix} [U]$$

obtain sts overall T/F
and T/F of state variable

$$[y] = [1 \ 1] \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + [0] [U]$$

$$[SI-A] = \begin{bmatrix} (s-1) + 2 \\ -4 \quad (s+5) \end{bmatrix}, \text{cofactor} = \begin{bmatrix} s+5 & -2 \\ +4 & s-1 \end{bmatrix}$$

$$\frac{\text{Adj}}{| \det |} = \frac{\begin{bmatrix} (s+5) & -2 \\ +4 & s-1 \end{bmatrix}}{(s^2+4s+3)} \Rightarrow [SI-A]^{-1} = \frac{\begin{bmatrix} (s+5) & -2 \\ 4 & (s-1) \end{bmatrix}}{(s+1)(s+3)}$$

char eq we can find pole from there

$$\frac{Y(s)}{U(s)} = [1 \ 1] \frac{\begin{bmatrix} (s+5) & -2 \\ 4 & (s-1) \end{bmatrix}}{(s+1)(s+3)} \begin{bmatrix} 2 \\ 1 \end{bmatrix} + [0]$$

$$\frac{Y(s)}{U(s)} = [1 \ 1] \frac{\begin{bmatrix} 2s+10-2 \\ 8+s-1 \end{bmatrix}}{s^2+4s+3} = [1 \ 1] \frac{\begin{bmatrix} 2s+8 \\ s+7 \end{bmatrix}}{s^2+4s+3}$$

$$\frac{Y(s)}{U(s)} = \frac{2s+8+s+7}{s^2+4s+3} = \frac{3s+15}{(s+1)(s+3)} \Rightarrow \boxed{\frac{Y(s)}{U(s)} = \frac{3(s+5)}{(s+1)(s+3)}}$$

$$\begin{bmatrix} \frac{x_1(s)}{U(s)} \\ \frac{x_2(s)}{U(s)} \end{bmatrix} = \frac{\begin{bmatrix} (s+5) & -2 \\ 4 & (s-1) \end{bmatrix} \begin{bmatrix} 2 \\ 1 \end{bmatrix}}{(s+1)(s+3)} = \frac{\begin{bmatrix} 2s+10-2 \\ 8+s-1 \end{bmatrix}}{(s+1)(s+3)} = \frac{\begin{bmatrix} 2s+8 \\ s+7 \end{bmatrix}}{(s+1)(s+3)}$$

$$\begin{bmatrix} \frac{x_1(s)}{U(s)} \\ \frac{x_2(s)}{U(s)} \end{bmatrix} = \frac{\begin{bmatrix} 2s+8 \\ s+7 \end{bmatrix}}{(s+1)(s+3)} \Rightarrow \boxed{\frac{x_1(s)}{U(s)} = \frac{2s+8}{(s+1)(s+3)}}$$

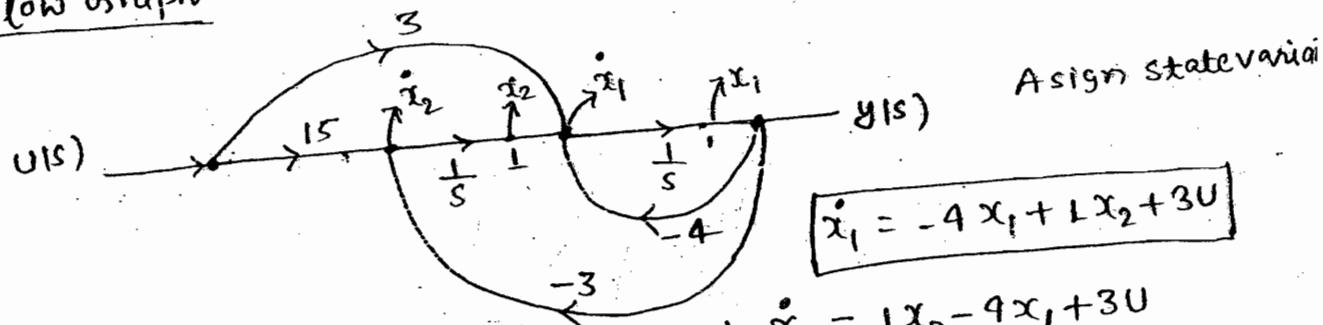
$$\frac{Y(s)}{U(s)} = \frac{x_1(s) + x_2(s)}{U(s)} \Rightarrow \frac{Y(s)}{U(s)} = \frac{x_1(s)}{U(s)} + \frac{x_2(s)}{U(s)}$$

$$\frac{Y(s)}{U(s)} = \frac{2s+8}{(s+1)(s+3)} + \frac{s+7}{(s+1)(s+3)} = \frac{3s+15}{(s+1)(s+3)} = \frac{3(s+5)}{(s+1)(s+3)}$$

Now

$$\frac{Y(s)}{U(s)} = \frac{3s+15}{(s+1)(s+3)} = \frac{\frac{3}{s} + \frac{15}{s^2}}{1 - \left[-\frac{4}{s} - \frac{3}{s^2} \right]} \quad \text{2. integrator}$$

S.
Flow Graph



$$y = 1x_1$$

$$\dot{x}_1 = 1x_2 - 4y + 3u \Rightarrow \dot{x}_1 = 1x_2 - 4x_1 + 3u$$

$$\dot{x}_2 = -3y + 15u = -3x_1 + 15u \Rightarrow \dot{x}_2 = -3x_1 + 15u$$

stateMatrix

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} -4 & 1 \\ -3 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 3 \\ 15 \end{bmatrix} [u] \quad \Rightarrow \text{different state matrix come:}$$

$$\begin{bmatrix} y \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 0 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \end{bmatrix} [u]$$

Now T/F from this

$$\frac{Y(s)}{U(s)} = [C][SI-A]^{-1}[B] + [D] = \frac{3s+15}{(s+1)(s+3)} \quad ? \text{ at same but}$$

$$\frac{x_1(s)}{U(s)} = \frac{3s+15}{(s+1)(s+3)}, \quad \frac{x_2(s)}{U(s)} = \frac{1}{(s+1)(s+3)}$$

\Rightarrow If SFG change
The state variab
change so
T/F of statevar
change.

and SFG can be
different -2

Controllability and Observability

Controllability define that all state variables are input dependent and by applying appropriate input we can obtain any desirable output of state variable. Controllability is checked by controllability test matrix Q_c .

$$[Q_c] = [B : AB : A^2B : \dots : A^nB]$$

where n = total No. of state variable which itself is rank of state Matrix $[A]$

and for system to be controllable the essential requirement is that determinant of $[Q_c]$ should not be '0'

$|Q_c| \neq 0 \Rightarrow \{ \text{Rank of } [Q_c] = \text{Rank of s.M. } [A] = n \}$

\Rightarrow all n no. of state variable are input dependent

but if $|Q_c| = 0 \Rightarrow \{ \text{Rank of } [Q_c] < \text{Rank of s.M. } [A] = n \}$

\Rightarrow some out of n no. of state variable

is independent of input

Observability * Observability define that output is dependent on all n no. of state variable observability is checked by observability test Matrix

$$[Q_o] = [C^T : A^T C^T : (A^T)^2 C^T : \dots : (A^T)^{n-1} C^T]$$

n = total no. of state variable = Rank of state Matrix $[A]$

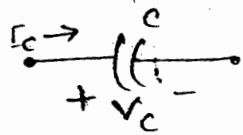
or S/I to be observable, then determinant of obsr $[Q_o]$ should not be = 0 → observable

$|Q_o| \neq 0 \Rightarrow \{ \text{Rank of } [Q_o] = \text{Rank of } [A] = n \rightarrow$ all n no. of state variable
the output depends on

$\{ \text{Rank of } [Q_o] < \text{Rank of } [A] = n \Rightarrow \text{output will be } \}$

State space representation of Electrical N/W

Capacitor: * In case of capacitor its voltage is a state variable while current across capacitor is input for charging or discharging of state variable.



$$\left[\frac{dx}{dt} \right] = [A][x] + [B][u] \Rightarrow$$

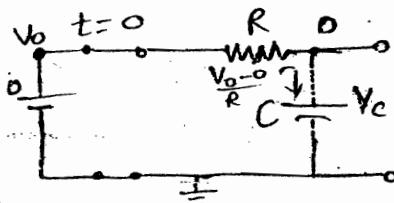
$$C \frac{dV_C}{dt} = I_C \Rightarrow \frac{dV_C}{dt} = \frac{I_C}{C} \Rightarrow \left[\frac{dV_C}{dt} \right] = [0][V_C] + \left[\frac{1}{C} \right][I_C]$$

↓ state variable ↓ input

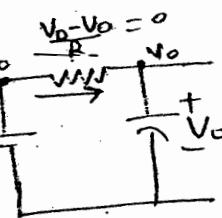
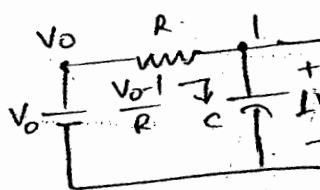
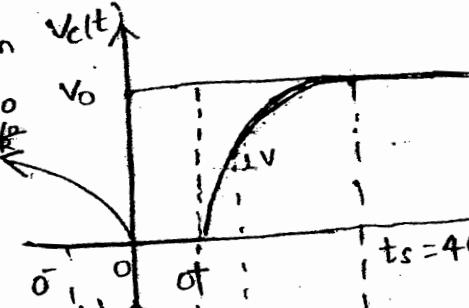
$$\boxed{V_C(t^-) = V_C(t) = V_C(t^+)} \quad \boxed{I_C(t^-) \neq I_C(t^+)}$$

at $t=0$

$$\boxed{V_C(0^-) = V_C(0) = V_C(0^+)} , \boxed{I_C(0^-) \neq I_C(0^+)}$$



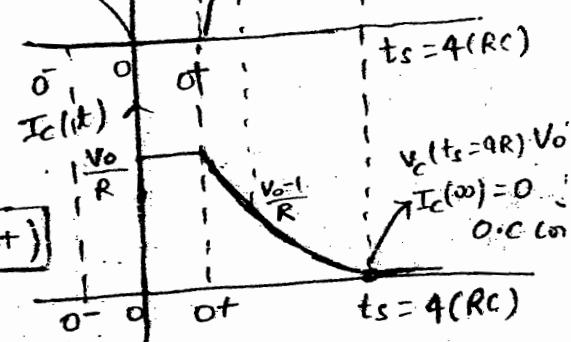
s.t. condn
 $\begin{cases} V_o(0) = 0 \\ I_C(0) = \frac{V_o}{R} \end{cases}$



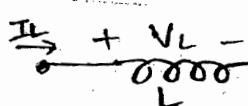
$$\boxed{V_C(0^-) = V_C(0) = V_C(0^+)} \quad \boxed{I_C(0^-) = 0}$$

$$I_C(0^+) = \frac{V_o}{R} \Rightarrow \boxed{I_C(0^-) \neq I_C(0^+)}$$

from figure



2 Inductor * in case of Inductor its current is a state variable while voltage is input for charging(or) discharging of state variable.



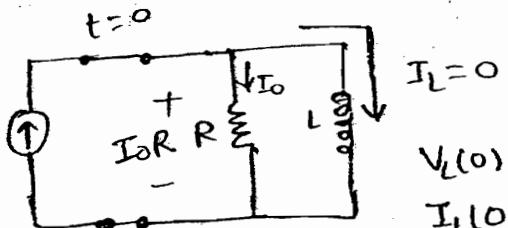
$$V_L = L \frac{dI_L}{dt} \Rightarrow \left[\frac{dI_L}{dt} \right] = [0][I_L] + \left[\frac{1}{L} \right][V_L]$$

↓ state variable ↓ input

$$\boxed{I_L(t^-) = I_L(t) = I_L(t^+)} \Rightarrow \text{while } \boxed{V_L(t) \neq V_L(t^+)}$$

at $t=0$

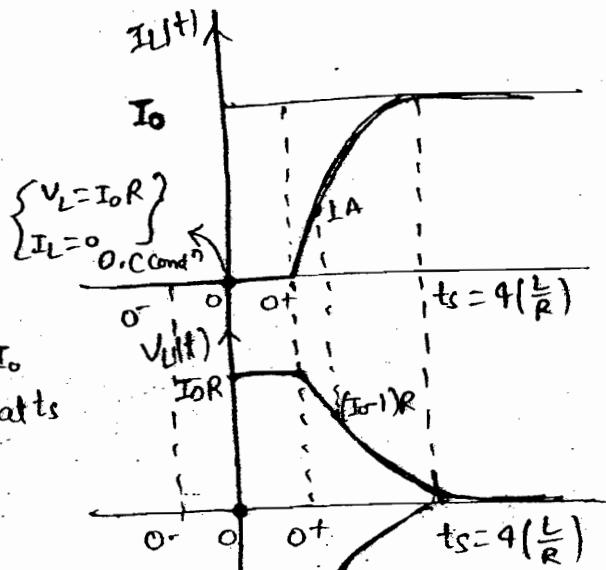
$$\boxed{T_L(0^-) = T_L(0^+) = I_L(0^+)} \text{ and } \boxed{V_L(0^-) \neq V_L(0^+)}$$



$$I_L = 0$$

$$V_L(0) = I_0 R$$

$$I_L(0) = 0$$

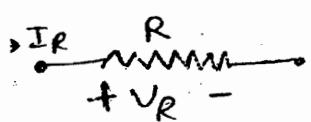


$$I_L(0^-) = I_L(0) = I_L(0^+)$$

$$I_L(0^-) = 0, V_L(0^+) = I_0 R \Rightarrow V_L(0^-) \neq V_L(0^+) \quad \text{s.c.r}$$

$$\text{condn} \quad \begin{cases} I_L(t_s = 4\frac{L}{R}) = I_0 \\ V_L(t_s = 4\frac{L}{R}) = 0 \end{cases}$$

) Resistor

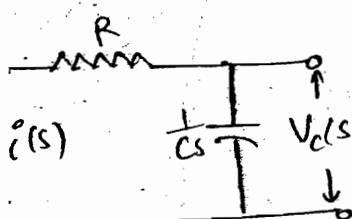


$$[V_R] = [R][I_R], [I_R] = [\frac{1}{R}][V_R]$$

No any eqn in differential form w.r.t. No. state variable.

Block representation of electrical Network

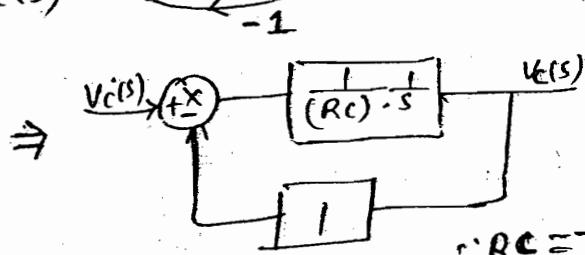
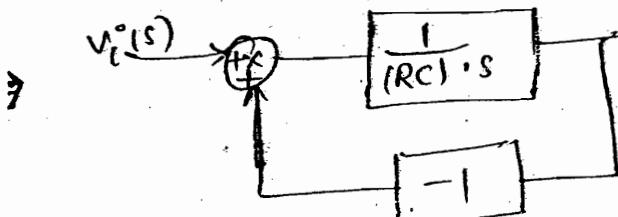
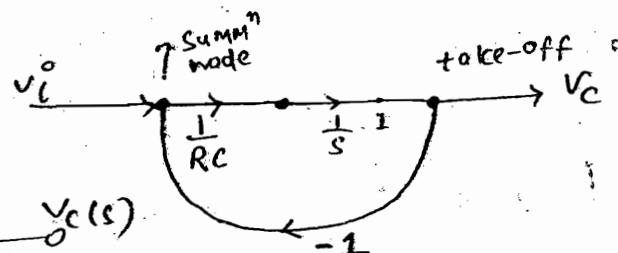
z-c circuit



$$\frac{V_c(s)}{i(s)} = \frac{\frac{1}{Cs}}{R + \frac{1}{Cs}} = \frac{1}{RC} = \frac{1}{s + \frac{1}{RC}}$$

$\frac{1}{s(s-5)} \Rightarrow$
 $s-5$ की वजह से
 जो K आयेगा उसी
 से F/B decide

$$\frac{V_c(s)}{V_i(s)} = \frac{(1/RC) \cdot \frac{1}{s}}{1 - [-\frac{1}{RC} \times \frac{1}{s}]} \Rightarrow$$



$$\therefore RC = T$$

ω -Bode plot from block diagram

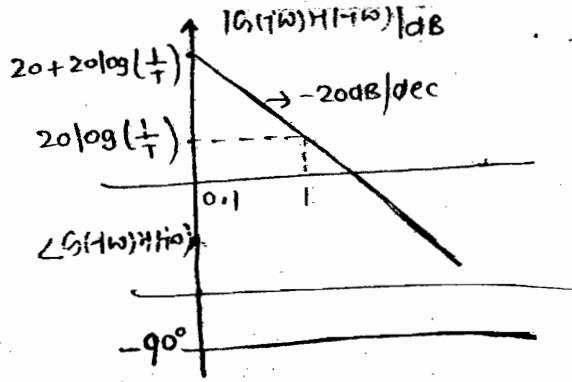
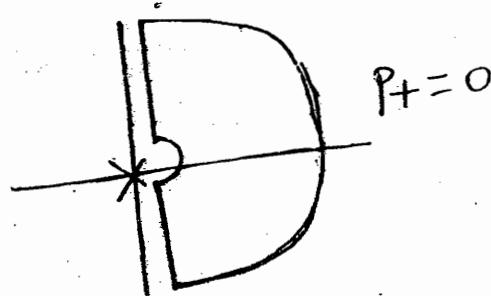
$$G(s)H(s) = \frac{1}{Ts} = \frac{1/T}{s}$$

* Now Root locus

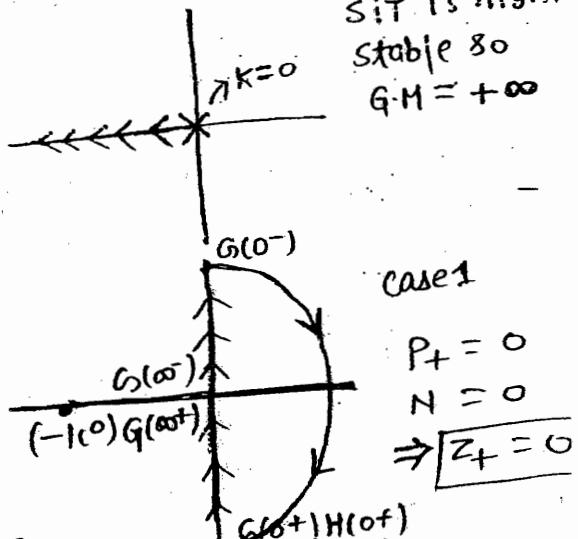
$$G(s)H(s) = \frac{1}{Ts} = \frac{1/T}{s}$$

* Now Nyquist Plot

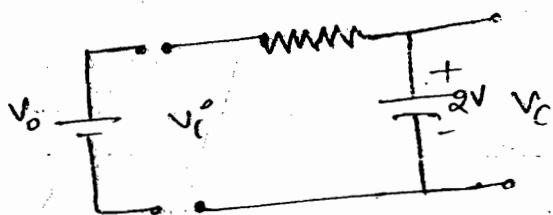
$$G(s)H(s) = \frac{1}{Ts} = \frac{\left(\frac{1}{T}\right)}{s}$$



SIT is High!
stable 80
 $G \cdot M = +\infty$



Now Initial Voltage across Capacitor given



$$\begin{aligned} v_i^o(t) &= V_0 U(t) \\ v_i^o(s) &= \frac{V_0}{s} \\ v_c(0) &= 2V \end{aligned}$$

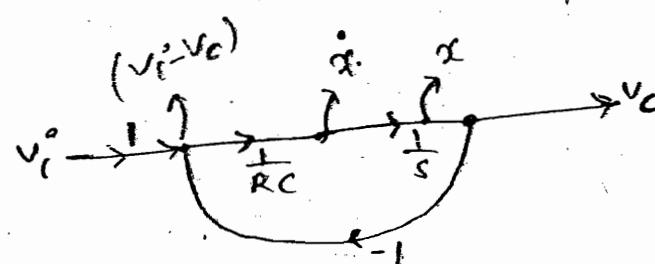
$$\frac{v_c(s)}{v_i^o(s)} = \frac{\frac{1}{Cs}}{R + \frac{1}{Cs}} = \frac{1/RC}{s + \frac{1}{RC}}$$

$$\Rightarrow v_c(s) = \frac{\frac{1}{RC}}{s(s + \frac{1}{RC})} = \frac{\frac{1}{RC}}{s} + \frac{\frac{1}{RC}}{s + \frac{1}{RC}}$$

$$v_c(t) = V_0 [1 - e^{-t/RC}]$$

at $t=0$ $v_c(0) = 0$ → which wrong so now we use state sp

$$\frac{v_c(s)}{v_i^o(s)} = \frac{\frac{1}{RC} \times \frac{1}{s}}{1 - \left[-\frac{1}{RC} \times \frac{1}{s} \right]}$$



$$\boxed{x} \quad \dot{x} = \frac{1}{RC} [v_i - v_c] = \frac{1}{RC} [v_i^o - x]$$

$$[\dot{x}] = \left[-\frac{1}{RC} \right] [x] + \left[\frac{1}{RC} \right] [v_i^o] \quad \left\{ [\dot{x}] = [A][x] + [B][v] \right\}$$

solution of this

$$x] = [sI - A]^{-1} [x(0)] + [sI - A]^{-1} [B][v]$$

$$x] = [s - A]^{-1} x(0) + (s - A)^{-1} B \cdot [v_i^o] \quad \left\{ \begin{array}{l} I = 1 \\ A = -\frac{1}{RC} \\ B = \frac{1}{RC} \end{array} \right\}$$

$$x] = \frac{1}{(s - A)} x(0) + \frac{1}{(s - A)} \cdot B \cdot [v_i^o] \quad \left\{ \begin{array}{l} I = 1 \\ A = -\frac{1}{RC} \\ B = \frac{1}{RC} \end{array} \right\}$$

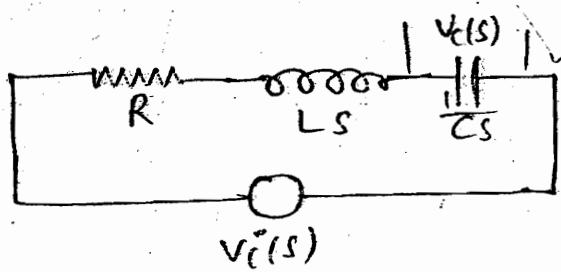
$$[x] = \frac{x(0)}{(s + \frac{1}{RC})} + \frac{\left(\frac{1}{RC}\right) \left[\frac{v_o}{s}\right]}{(s + \frac{1}{RC})} \Rightarrow [x(s)] = \frac{x(0)}{(s + \frac{1}{RC})} + \frac{\frac{v_o}{RC}}{(s(s + \frac{1}{RC}))}$$

$$[x(s)] = \frac{x(0)}{s + \frac{1}{RC}} + \left\{ \frac{v_o}{s} - \frac{v_o}{(s + \frac{1}{RC})} \right\} \Rightarrow x(t) = x(0)e^{-t/RC} + \{v_o - v_o e^{-t/RC}\}$$

$$x(t) = v_c(t) = [2e^{-t/RC} + \{v_o \{1 - e^{-t/RC}\}\}]$$

now at $t=0$ $v_c(0) = 2V$ this is write
 ZIR \downarrow ZSR \leftarrow

block representation of series RLC circuit

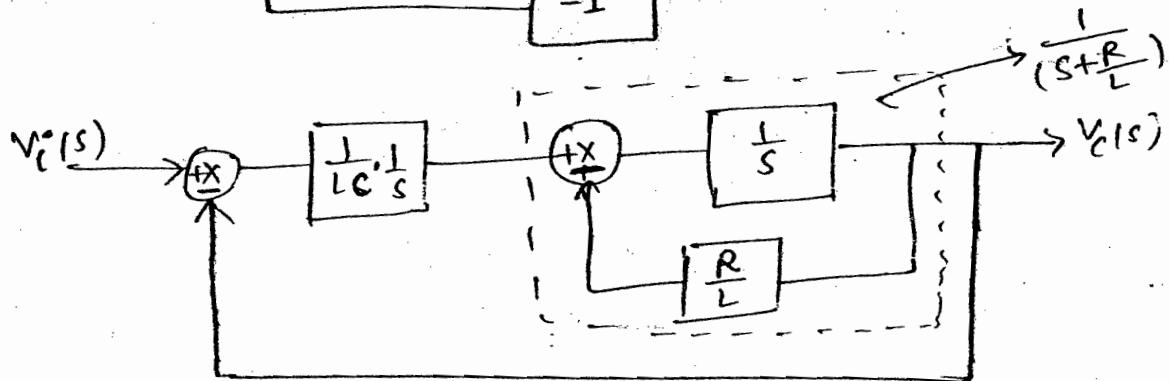
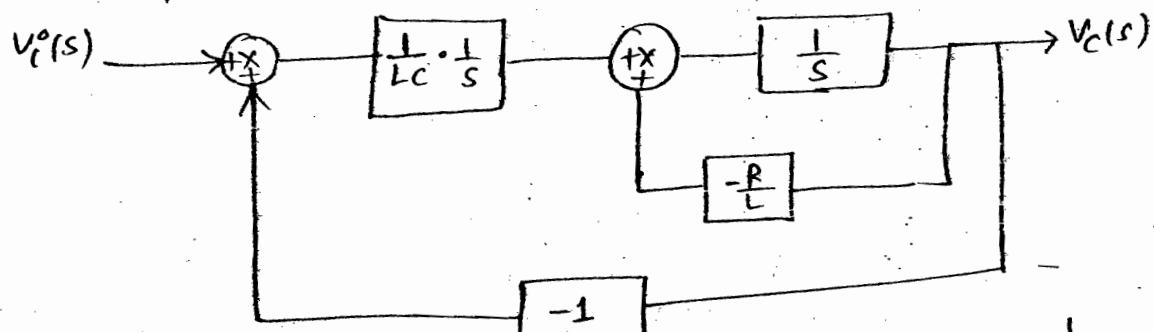
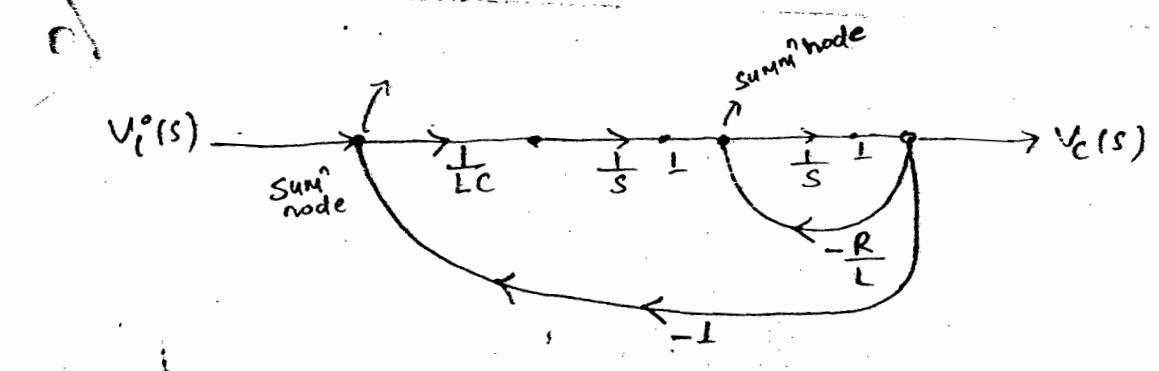


$$\frac{V_c(s)}{V_c^o(s)} = \frac{\frac{1}{Cs}}{R + Ls + \frac{1}{Cs}}$$

$$\frac{V_c(s)}{V_c^o(s)} = \frac{\frac{1}{LC}}{LCs^2 + RCS + 1} = \frac{\left(\frac{1}{LC}\right)}{s^2 + \frac{R}{L}s + \frac{1}{LC}}$$

$$\frac{V_c(s)}{V_c^o(s)} = \frac{\left(\frac{1}{LC}\right) \times \frac{1}{s^2}}{1 - \left[-\frac{R}{s} - \frac{\left(\frac{1}{LC}\right)}{s^2}\right]}$$

Highest powers
 in Numerator of
 Denominator divide
 for SFS Mason
 formula.



$$\frac{V_C(s)}{V_i^o(s)} = \frac{\left(\frac{1}{LC}\right)}{s(s + \frac{R}{L})}$$

\therefore In time response $\frac{R(s)}{V_i^o(s)} \rightarrow$

$$\frac{V_C(s)}{R(s)} = \frac{\omega_n^2}{s(s + 2\zeta\omega_n)}$$

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

on comparing $\omega_n^2 = \frac{1}{LC}$, $2\zeta\omega_n = \frac{R}{L} \Rightarrow \omega_n = \frac{1}{\sqrt{LC}}$, $\zeta = \frac{R}{2\sqrt{LC}}$

open loop T/F (after remove summation)

$$G(s)H(s) = \frac{\left(\frac{1}{LC}\right) K(\text{variable})}{s(s + \frac{R}{L})}$$

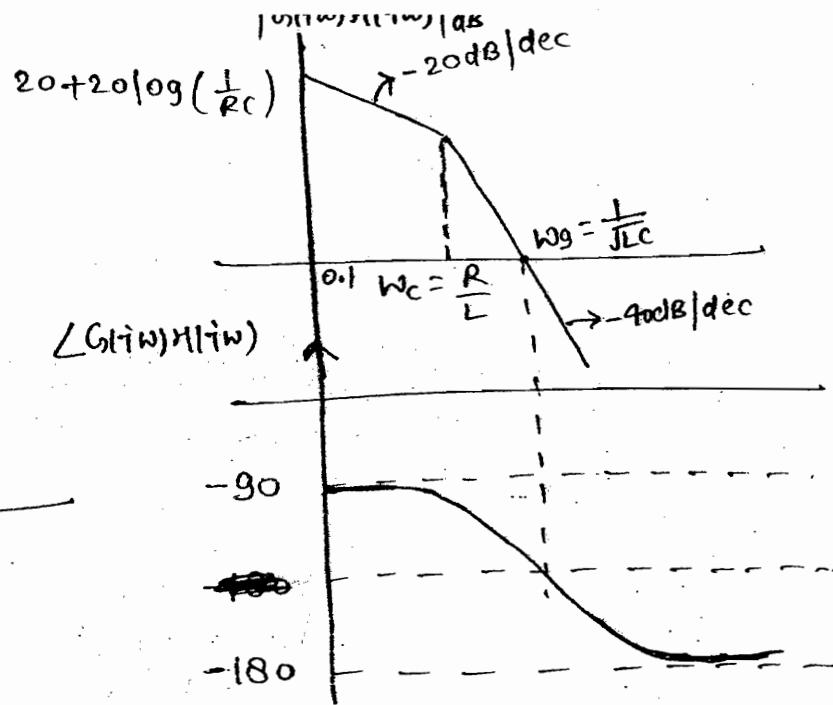
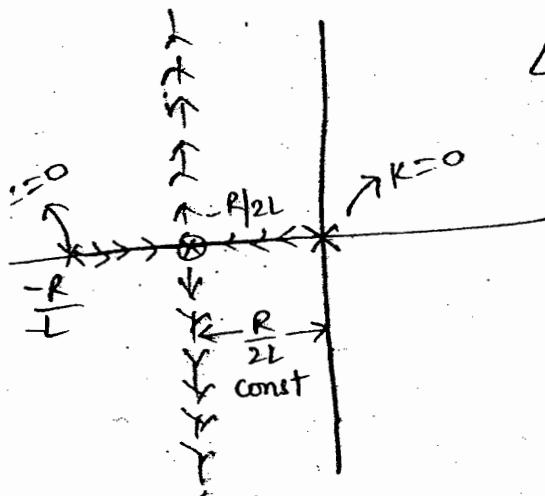
const

K variable होगा

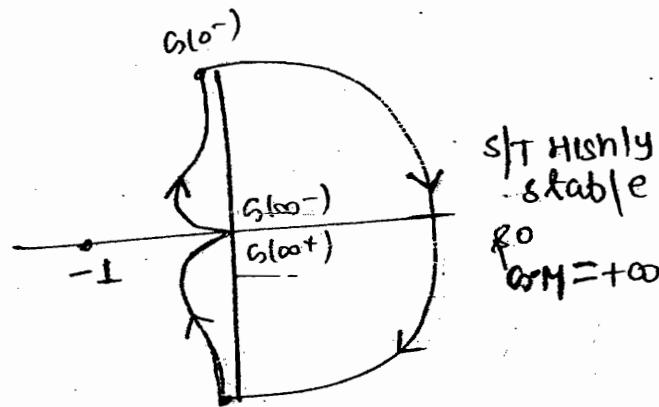
'e' की change करने से

- From this, ① Bode plot
② Nyquist plot
③ Root locus

3ode plot



$$\begin{aligned} P_f &= 0 \\ N &= 0 \text{ (always)} \\ \boxed{Z_f = 0} &\text{ always} \end{aligned}$$



If we take output across inductor $G(0+)$

so we find T/F for that and further same process.

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} -2 & 1 \\ 0 & -3 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 1 \\ 0 \end{bmatrix} [U]$$

A certain LTI S/T has state representn given above

$$[U] = \begin{bmatrix} 1 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + [0] [U]$$

(i) Find eigenvalue of S/T

(ii) If $U(t) = 18(t)$ and $x_1(0) = x_2(0) = 0$ calculate $x_1(t)$ & $x_2(t)$.

(iii) If $U(t) = 0$ calculate $x_1(t)$ & $x_2(t)$ so that $\lim_{t \rightarrow \infty} x_1(t) = A e^{-2t}$

$$\text{S.I.} \quad [A\mathbf{I} - \mathbf{A}] = \begin{bmatrix} 1+2 & -1 \\ 0 & 1+3 \end{bmatrix} \Rightarrow |A\mathbf{I} - \mathbf{A}| = 0$$

$\lambda = -2, -3$ (location of pole)

\Rightarrow stable S/T

$$[X(s)] = [SI - A]^{-1}[x(0)] + [SI - A]^{-1}[B][u(s)] \quad \dots \quad ①$$

$$[SI - A] = \begin{bmatrix} s+2 & -1 \\ 0 & s+3 \end{bmatrix} \Rightarrow [SI - A]^{-1} = \frac{1}{(s+2)(s+3)} \begin{bmatrix} s+3 & 1 \\ 0 & s+2 \end{bmatrix}$$

$$\text{Cofactor} = \begin{bmatrix} (s+3) & 0 \\ 0 & (s+2) \end{bmatrix} \Rightarrow [SI - A]^{-1} = \frac{\text{Adj}}{|\det|} = \frac{(s+3)}{(s+2)(s+3)} \begin{bmatrix} 1 & 0 \\ 0 & s+2 \end{bmatrix}$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & (s+2) \end{bmatrix} \begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix}}{(s+2)(s+3)} + \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & (s+2) \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix} u(s)}{(s+2)(s+3)}$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & (s+2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \end{bmatrix}}{(s+2)(s+3)} + \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & s+2 \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix} \cdot 1}{(s+2)(s+3)} = \frac{(s+3)}{(s+2)(s+3)} \cdot 1$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+3) \\ 0 \end{bmatrix} \cdot 1}{(s+2)(s+3)} = \begin{bmatrix} \frac{1}{(s+2)} \\ 0 \end{bmatrix} \Rightarrow x_1(s) = \frac{1}{s+2}, x_2(s) = 0$$

$$x_1(t) = e^{-2t}, x_2(t) = 0$$

$$\text{iii) } \begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & (s+2) \end{bmatrix} \begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix}}{(s+2)(s+3)} + \frac{\begin{bmatrix} (s+3) & 1 \\ 0 & (s+2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \end{bmatrix}}{(s+2)(s+3)} \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+3)x_1(0) + x_2(0) \\ (s+2)x_2(0) \end{bmatrix}}{(s+2)(s+3)} = \frac{\begin{bmatrix} x_2(0) + x_1(0)(s+3) \\ (s+2)(s+3) \end{bmatrix}}{(s+2)(s+3)}$$

$$x_1(s) = \frac{x_1(0)(s+3) + x_2(0)}{(s+2)(s+3)} \quad \& \quad x_2(s) = \frac{x_2(0)(s+2)}{(s+2)(s+3)}$$

$$y(s) = x_1(s) + x_2(s) \Rightarrow y(s) = \frac{(s+3)x_1(0) + x_2(0)}{(s+2)(s+3)} + \frac{(s+2)x_2(0)}{(s+2)(s+3)}$$

$$y(s) = \frac{(s+3)x_1(0) + (s+3)x_2(0)}{(s+2)(s+3)} = \frac{x_1(0) + x_2(0)}{(s+2)} = \frac{A}{s+2}$$

$$\boxed{x_1(0) + x_2(0) = A}$$

If $x_1(0) = 0$ then $x_2(0) = A$

If $x_2(0) = 0$ then $x_1(0) = A$

$$2 \quad \frac{d^2y}{dt^2} + \frac{dy}{dt} - 2y = z(t)$$

$$y(0) = \dot{y}(0) = 0, z(t) = e^{Lt}$$

initial condⁿ given \Rightarrow इसकी को state variable लेना है।
so calculate its solⁿ by both method state space & T/F method

\therefore two state variable $y = x_1 \quad x_1(0) = y(0) = 0$

$$\boxed{\dot{x}_1 = x_2} \quad \text{--- (1)} \quad \leftarrow \frac{dx_1}{dt} = \frac{dy}{dt} = x_2 \quad x_2(0) = \dot{y}(0) = 0$$

$$\frac{d}{dt} \left[\frac{dy}{dt} \right] + L \left[\frac{dy}{dt} \right] - 2[y] = z(t)$$

$$\frac{d}{dt} [x_2] + L[x_2] - 2[x_1] = z(t) \quad \Rightarrow \quad \boxed{\dot{x}_2 = 2x_1 - Lx_2 + 1z(t)}$$

now state matrix from state eqⁿ:

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ 2 & -1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 1 \end{bmatrix} \begin{bmatrix} z(t) \end{bmatrix} \rightarrow \text{state matrix}$$

$$[y] = [L \ 0] \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + [0] \begin{bmatrix} z(t) \end{bmatrix} \rightarrow \text{output matrix}$$

$$SI - A = \begin{bmatrix} (s+2) & -1 \\ -2 & (s+1) \end{bmatrix}$$

$$\text{Co-factor} = \begin{bmatrix} (s+1) & 1 \\ 2 & s \end{bmatrix}$$

$$SI - A = \begin{bmatrix} (s+1) & 2 \\ 1 & s \end{bmatrix} = \frac{(s+2)(s-1)}{s^2+s-2}$$

$$\text{adj} = \begin{bmatrix} s+1 & 2 \\ 1 & s \end{bmatrix}$$

$$[x(s)] = [SI - A]^{-1} [x(0)] + [SI - A]^{-1} [B] [z(s)]$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} (s+1) & 1 \\ 2 & s \end{bmatrix} \begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix} + \begin{bmatrix} (s+1) & 1 \\ 2 & s \end{bmatrix} \begin{bmatrix} 0 \\ 1 \end{bmatrix}}{(s+2)(s-1)} \frac{1}{(s+1)}$$

$$\begin{bmatrix} x_1(s) \\ x_2(s) \end{bmatrix} = \frac{\begin{bmatrix} 0 \\ 0 \end{bmatrix} + \begin{bmatrix} 1 \\ s \end{bmatrix}}{(s+1)(s+2)(s-1)}$$

$$= \begin{bmatrix} \frac{1}{(s+1)(s+2)(s-1)} \\ \frac{s}{(s+1)(s+2)(s-1)} \end{bmatrix}$$

For the given diffⁿ eqⁿ obtain
its solⁿ by using state
space representation

$$x_1(s) = \frac{1}{(s+a)(s+1)(s-1)} \quad x_2(s) = \frac{s}{(s+a)(s+1)(s-1)} = s\{x_1(s)\}$$

$$x_1(s) = \frac{q_0}{s+1} + \frac{q_1}{s+2} + \frac{q_2}{s-1} = \frac{(-1)}{s+1} + \frac{(1/3)}{s+2} + \frac{(1/6)}{s-1}$$

$$x_1(t) = -\frac{1}{2}e^{-t} + \frac{1}{3}e^{-2t} + \frac{1}{6}e^{+t} \Rightarrow x_2(t) = \frac{d}{dt}x_1(t)$$

$$x_2(t) = \frac{1}{2}e^{-t} - \frac{2}{3}e^{-2t} + \frac{1}{6}e^{+t} \Rightarrow y(t) = x_1(t) \quad \text{Ans}$$

From T/F method because initial conditions are zero.

$$\{s^2y(s) - s\dot{y}(0) - y(0)\} + \{sy(s) - y(0)\} - 2y(s) = z(s)$$

$$s^2y(s) + sy(s) - 2y(s) = z(s) \Rightarrow \frac{y(s)}{z(s)} = \left[\frac{1}{s^2 + s - 2} \right]$$

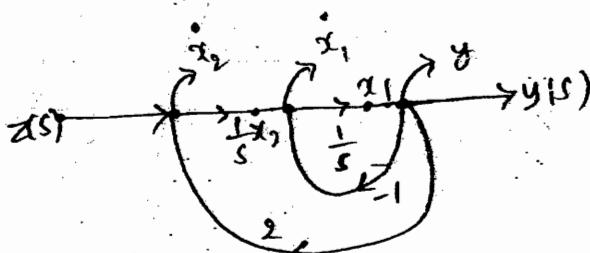
$$y(s) = \frac{1}{(s+1)(s+1)(s-2)} \quad \left\{ z(s) = \frac{1}{s+1} \right\} = \frac{q_0}{s+1} + \frac{q_1}{s+2} + \frac{q_2}{s-1}$$

$$y(s) = -\frac{1}{2} + \frac{1/3}{s+2} + \frac{1/6}{s-1} \Rightarrow y(t) = -\frac{1}{2}e^{-t} + \frac{1}{3}e^{-2t} + \frac{1}{6}e^{+t}$$

Now from T/F से solⁿ

$$\frac{y(s)}{z(s)} = \frac{1}{s^2 + s - 2} = \frac{\frac{1}{s^2}}{1 - \left[-\frac{1}{s} + \frac{2}{s^2} \right]}$$

Here gain = 1 & 0. No require
of additional branch.



$$y = x_1 \quad \text{output eqn.}$$

$$\dot{x}_1 = -1/y + 1/x_2 = -1x_1 + x_2$$

$$\dot{x}_2 = -1/x_1 + x_2$$

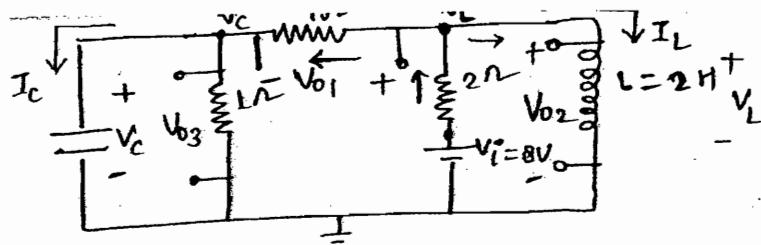
$$\dot{x}_2 = 2y + z \Rightarrow \dot{x}_2 = 2x_1 + z$$

state matrix

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} -1 & 1 \\ 2 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 1 \end{bmatrix} [z], \quad [y] = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \end{bmatrix} [z]$$

Now previous Matrix and this matrix are different due to different state variable but solⁿ will be same y(t) but x_2(t) will be different

$$y(t) = -\frac{1}{2}e^{-t} + \frac{1}{3}e^{-2t} + \frac{1}{6}e^{+t} = x_1(t) \quad \text{Op} \rightarrow \text{unique soln}$$



For the given electrical circuit obtain its state matrix as well as O/P Matrix

$$\frac{V_i^o - V_L}{2} = \frac{V_L - V_C}{L} + I_L \quad \left\{ \because V_L = L \frac{dI_L}{dt} = 2 \frac{dI_L}{dt} \right\}$$

$$\frac{3}{2} V_L = V_C - I_L + \frac{V_i^o}{2} \Rightarrow \frac{3}{2} \times 2 \frac{dI_L}{dt} = V_C - I_L + \frac{V_i^o}{2}$$

$$\frac{dI_L}{dt} = \frac{1}{3} V_C - \frac{1}{3} I_L + \frac{1}{6} V_i^o \Rightarrow \boxed{\frac{dI_L}{dt} = \left(\frac{1}{3}\right) V_C + \left(-\frac{1}{3}\right) I_L + \left(\frac{1}{6}\right) V_i^o}$$

apply KCL

$$\frac{V_L - V_C}{1} = \frac{V_C}{1} + I_C \quad \left\{ \because I_C = C \frac{dV_C}{dt} = 1 \times \frac{dV_C}{dt} \right\}$$

$$I_C = -2V_C + V_L \Rightarrow \frac{dV_C}{dt} = -2V_C + 2 \left\{ \frac{dI_L}{dt} \right\}$$

$$\frac{dV_C}{dt} = -2V_C + 2 \left\{ \frac{1}{3} V_C - \frac{1}{3} I_L + \frac{1}{6} V_i^o \right\}$$

$$\boxed{\frac{dV_C}{dt} = \left(-\frac{4}{3}\right) V_C + \left(-\frac{2}{3}\right) I_L + \left(\frac{1}{3}\right) V_i^o} \quad \text{contain state variable and input } \Rightarrow \text{this is state eqn.}$$

$$\begin{bmatrix} I_L \\ V_C \end{bmatrix} = \begin{bmatrix} \frac{1}{3} & \frac{1}{3} \\ -\frac{2}{3} & \frac{4}{3} \end{bmatrix} \begin{bmatrix} I_L \\ V_C \end{bmatrix} + \begin{bmatrix} \frac{1}{6} \\ \frac{1}{3} \end{bmatrix} \begin{bmatrix} V_i^o \end{bmatrix} \quad \left\{ \begin{array}{l} \boxed{[x] = [A]_{m \times n} [x] + [B]_{m \times 1} [u]} \\ \boxed{[y] = [C]_{m \times n} [x] + [D]_{m \times 1} [u]} \end{array} \right. \quad \begin{array}{l} m \times n \\ m \times 1 \end{array}$$

If O/P not defined then we can't write O/P equation.

$$V_{O1} = V_L - V_C = \left\{ \frac{2}{3} V_C - \frac{2}{3} I_L + \frac{1}{3} V_i^o \right\} - V_C \Rightarrow \boxed{V_{O1} = -\frac{1}{3} V_C - \frac{2}{3} I_L + \frac{1}{3} V_i^o}$$

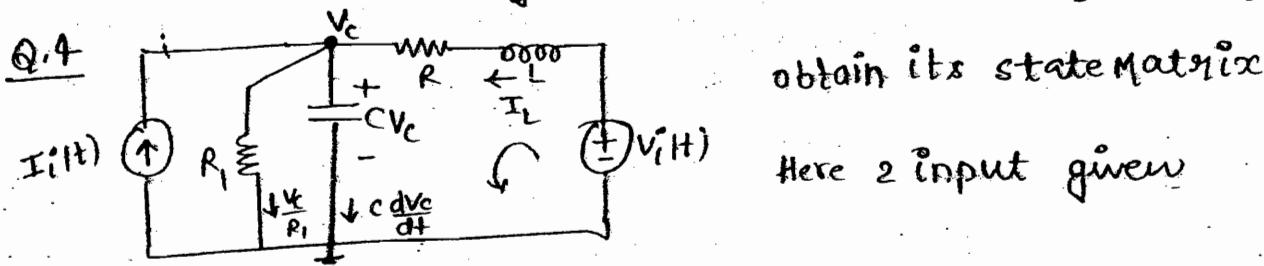
$$\begin{bmatrix} V_{O1} \\ V_{O2} \\ V_{O3} \end{bmatrix} = \begin{bmatrix} -\frac{2}{3} & \frac{1}{3} \\ -\frac{2}{3} & \frac{2}{3} \\ 0 & 1 \end{bmatrix} \begin{bmatrix} I_L \\ V_C \end{bmatrix} + \begin{bmatrix} \frac{1}{3} \\ \frac{1}{3} \\ 0 \end{bmatrix} \begin{bmatrix} V_i^o \end{bmatrix} \quad \text{output arises across } L/R \text{ resistors.}$$

$$\begin{bmatrix} V_{O1}(s) \\ V_{O2}(s) \\ V_{O3}(s) \\ V_L(s) \end{bmatrix} = \begin{bmatrix} C \\ 1 \times 2 \\ 2 \times 2 \\ 2 \times 2 \end{bmatrix} \begin{bmatrix} SI - A \end{bmatrix}_{2 \times 2}^{-1} \begin{bmatrix} B \\ 2 \times 1 \\ 2 \times 1 \\ 2 \times 1 \end{bmatrix} + \begin{bmatrix} D \end{bmatrix}_{1 \times 1} \begin{bmatrix} V_i^o \end{bmatrix}_{2 \times 1} \quad \begin{array}{l} 2 \times 2 \\ 2 \times 1 \\ 2 \times 1 \\ 2 \times 1 \end{array}$$

$$Q.3 \quad v_2 = v_L = \frac{2}{3}v_C - \frac{2}{3}I_L + \frac{1}{3}V_i \quad \text{second o/p across inductor}$$

$$v_{03} = L v$$

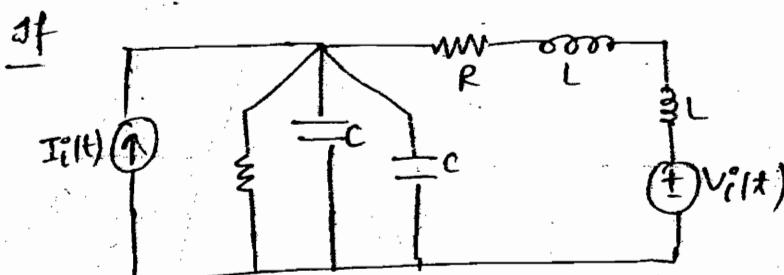
* We can calculate T/F simultaneously across every or any component in a single array. change only [C] & [D] matrix.



Sol $C \frac{dv_c}{dt} + \frac{v_c}{R_1} = I_i^o(t) + I_L \Rightarrow \frac{dv_c}{dt} = \left(-\frac{1}{R_1 C}\right) \cdot v_c + \left(\frac{1}{C}\right) I_L + \left(\frac{1}{C}\right) I_i^o(t)$

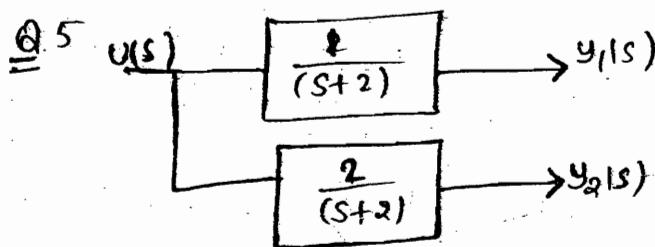
$$v_i^o(t) - L \frac{dI_L}{dt} - RI_L - v_c = 0 \Rightarrow \frac{dI_L}{dt} = \left(-\frac{1}{L}\right) \cdot v_c - \left(\frac{R}{L}\right) I_L + \frac{1}{L} V_i$$

$$\begin{bmatrix} \dot{i}_L \\ \dot{v}_c \end{bmatrix} = \begin{bmatrix} -\frac{R}{L} & -\frac{1}{L} \\ \frac{1}{C} & -\frac{1}{RC} \end{bmatrix} \begin{bmatrix} I_L \\ v_c \end{bmatrix} + \begin{bmatrix} 0 & \frac{1}{L} \\ \frac{1}{C} & 0 \end{bmatrix} \begin{bmatrix} I_i^o(t) \\ v_i^o(t) \end{bmatrix} \xrightarrow{\text{Ans}} \text{state matrix}$$

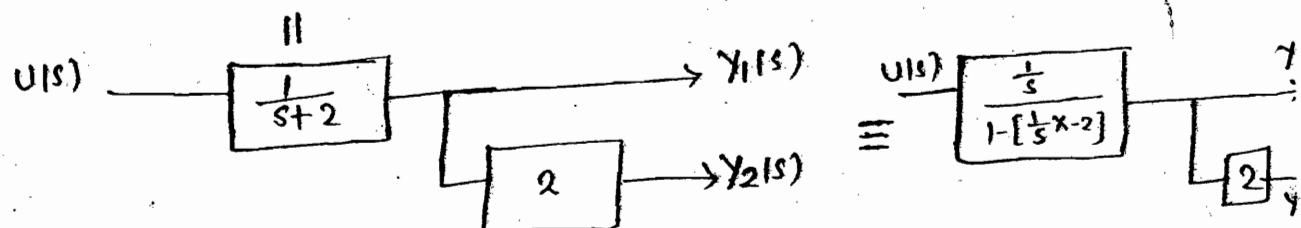


पर्याप्त भी 2 ही state variable हैं।

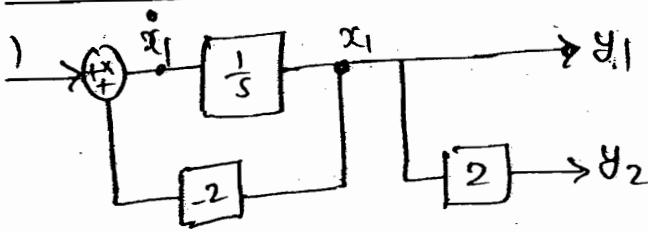
C & C in parallel where Voltage same
L & L in series where current same.



for the given block obtain its state matrix



from this block is,



Here 2 output
state variable = 1
input = 1

$$\therefore y_1 = 1x_1$$

$$y_2 = 2x_1$$

$$\dot{x}_1 = [-2] \begin{bmatrix} x_1 \end{bmatrix} + [1] \begin{bmatrix} u \end{bmatrix}$$

$$\begin{bmatrix} \dot{x}_1 \\ y_1 \\ y_2 \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 2 & 0 \end{bmatrix} \begin{bmatrix} x_1 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \end{bmatrix} \begin{bmatrix} u \end{bmatrix}$$

Ans.

Compensator

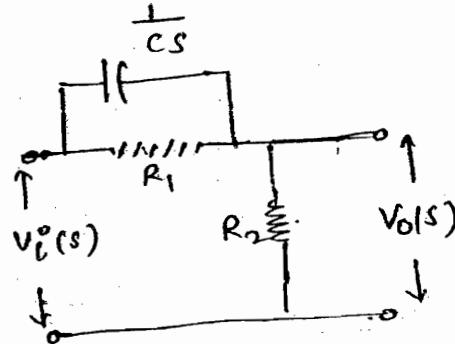
Phase lead compensator

$$\frac{i(s)}{v_i(s)} = \frac{R_2}{R_2 + R_1 \times \frac{1}{Cs}} = \frac{R_2}{R_2 + \frac{R_1}{R_1 Cs + 1}}$$

$$\frac{v_o(s)}{v_i(s)} = \frac{R_2 [R_1 Cs + 1]}{R_2 R_1 Cs + R_2 + R_1}$$

$$\frac{v_o(s)}{v_i(s)} = \frac{R_2 [R_1 Cs + 1]}{(R_2 + R_1) \left[\frac{R_2 R_1 Cs}{R_2 + R_1} + 1 \right]}$$

$$\frac{v_o(s)}{v_i(s)} = \frac{\alpha [Ts + 1]}{[\alpha St + 1]} = \frac{\alpha \left[\frac{s}{\omega_{cp}} + 1 \right]}{\left[\frac{s}{\omega_{cp}} + 1 \right]}$$



$$\therefore \alpha = \frac{R_2}{R_1 + R_2} < 1$$

$$T = R_1 C$$

$$\omega_{cz} = \frac{1}{T}$$

$$\omega_{cp} = \frac{1}{\alpha T}$$

$$\omega_{cp} > \omega_{cz}$$

$$\omega_{cp} = -\frac{1}{\alpha T}, \quad \omega_{cz} = \frac{1}{T}$$

\because zero closer to origin \Rightarrow 0

phase lead compensator is zero dominant

$$\frac{v_o(j\omega)}{v_i(j\omega)} = \frac{\alpha [1 + j\omega T]}{[1 + j\omega \alpha T]}, \quad \left| \frac{v_o(j\omega)}{v_i(j\omega)} \right| = \frac{\alpha \sqrt{1 + (\omega T)^2}}{\sqrt{1 + (\omega \alpha T)^2}}$$

$$\left| \frac{v_o(j\omega)}{v_i(j\omega)} \right| = \alpha \sqrt{1 + (\omega T)^2}$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right|_{dB} = 20 \log \alpha + 20 \log \sqrt{1+(WT)^2} - 20 \log \sqrt{1+(w\alpha T)^2}$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = + \tan^{-1}(WT) - \tan^{-1} \frac{w\alpha T}{1}$$

$$\therefore \left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = \alpha \frac{\sqrt{1+(WT)^2}}{\sqrt{1+(w\alpha T)^2}}$$

$$\text{At } w=0 \quad \frac{V_o}{V_i^o} = \alpha \Rightarrow V_o = \alpha V_i^o$$

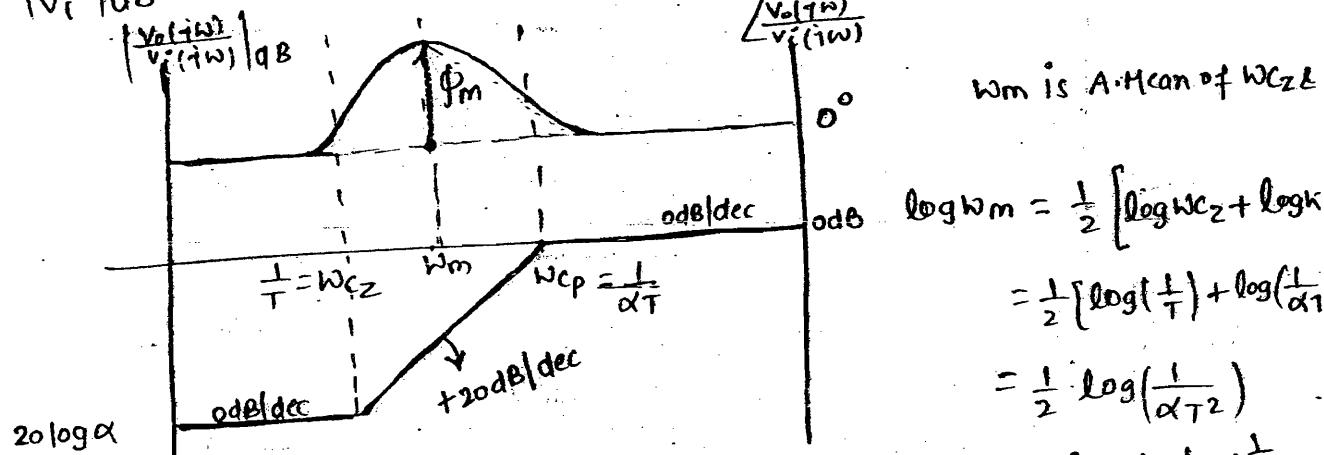
$$V_o = \alpha V_i^o < V_i^o \quad \{ \text{Attenuation} \}$$

At $w=\infty$ (H.F.R)

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = \frac{\alpha \sqrt{(WT)^2}}{\sqrt{(w\alpha T)^2}} = \frac{w\alpha T}{w\alpha T} = 1 \Rightarrow V_o = V_i^o$$

$$\left| \frac{V_o}{V_i^o} \right|_{dB} = 20 \log \alpha \quad (\text{-ve}) \quad \{ \because \alpha < 1 \}$$

$$\left| \frac{V_o}{V_i} \right|_{dB} = 20 \log 1 = 0 \text{ dB}$$



$$\begin{aligned} \log \omega_m &= \frac{1}{2} [\log \omega_{CP} + \log k] \\ &= \frac{1}{2} [\log(\frac{1}{\alpha T}) + \log(\frac{1}{\alpha T})] \\ &= \frac{1}{2} \log(\frac{1}{\alpha T^2}) \\ &= \log(\frac{1}{\alpha T^2})^{\frac{1}{2}} \end{aligned}$$

$$\text{Now } \phi_m = \left[\tan^{-1}(\omega_m T) - \tan^{-1}(w_m \alpha T) \right] = \log \frac{1}{\sqrt{\alpha T}}$$

$$\phi_m = \tan^{-1}(\frac{1}{\sqrt{\alpha}}) - \tan^{-1}(\sqrt{\alpha}) = \tan^{-1} \frac{(1-\alpha)}{2\sqrt{\alpha}}$$

$$\tan \phi_m = \frac{(1-\alpha)}{2\sqrt{\alpha}} = \frac{P}{B} \Rightarrow P = (1-\alpha), B = 2\sqrt{\alpha}$$

$$\sin \phi_m = \frac{(1-\alpha)}{(1+\alpha)}, \cos \phi_m = \frac{2\sqrt{\alpha}}{(1+\alpha)} \quad r = \sqrt{P^2 + B^2} = \sqrt{(1-\alpha)^2 + 4\alpha}$$

$$w_m = \frac{1}{\sqrt{\alpha T}}, w_m T = \frac{1}{\sqrt{\alpha}}$$

* Phase lead compensator is zero dominant because zero is closer to the origin

* Phase lead compensator act as High pass Filter

* P.L. compensator shift Gain Cross-over freq? to Higher

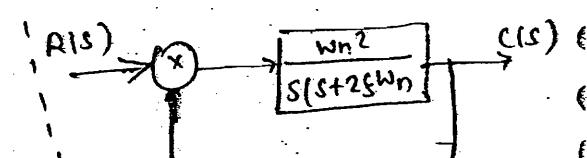
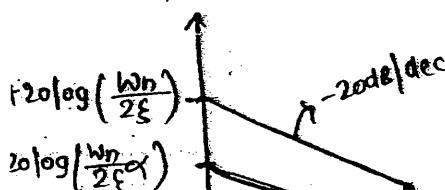
bandwidth of S/T will ↑ → age overshoot will also ↑
 settling time will ↓

P.L.C. will not affect steady state error.

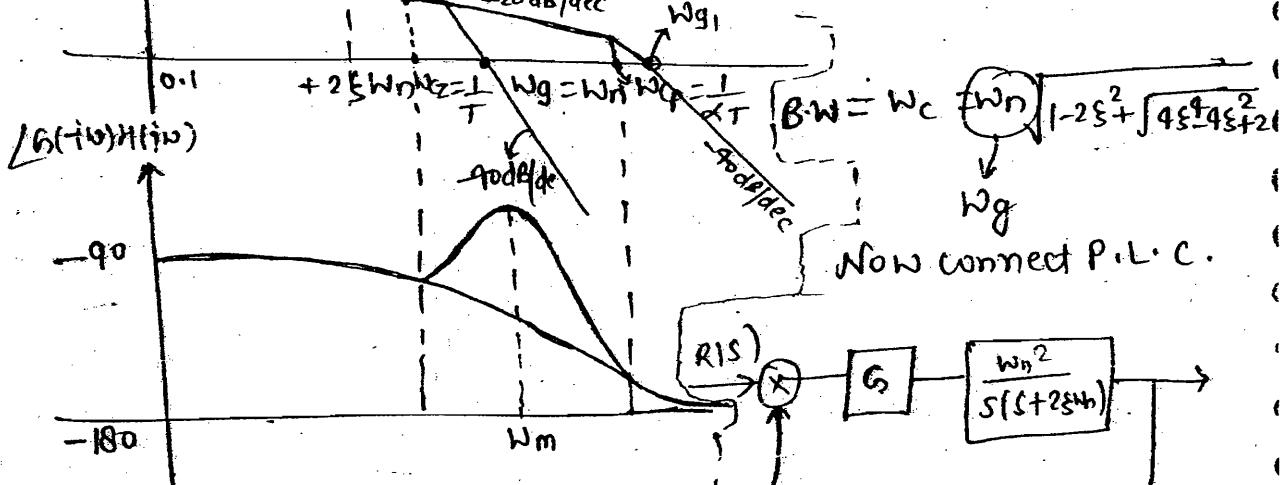
As P.L.C. comp. is zero dominant so it increase the bandwidth of system.

Consider $(G(s)H(s)) = \frac{w_n^2}{s(s+2\zeta w_n)}$ $\Rightarrow G(s)H(s) = \frac{\frac{w_n^2}{2\zeta}}{s\left[\frac{s}{2\zeta w_n} + 1\right]}$

$$\left| G(j\omega)H(j\omega) \right|_{dB}$$



$$\frac{C(s)}{R(s)} = \frac{w_n^2}{s^2 + 2\zeta w_n s + w_n^2}$$



In case of second order system
 P.L.C. increase the phase margin
 of the system but it will not
 affect the gain margin.

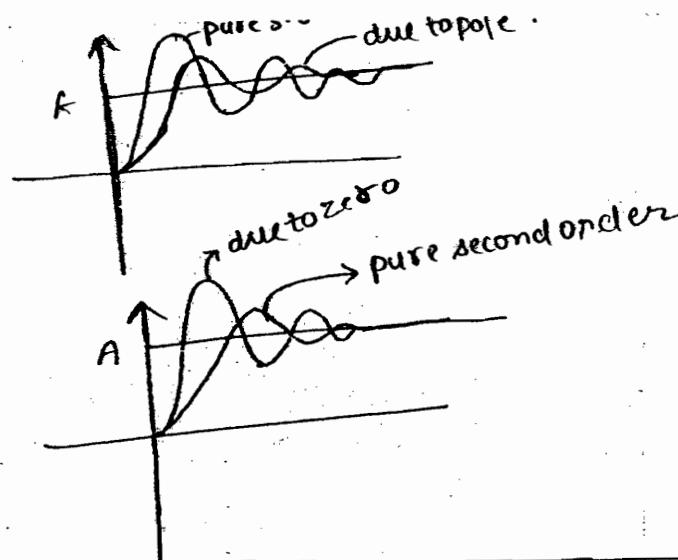
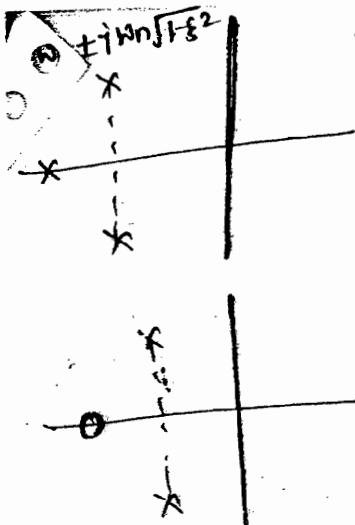
Thus whenever faster response is
 required we will use phase lead compensator.

$$G(s)H(s) = \frac{w_n^2}{s(s+2\zeta w_n)} \cdot \alpha \left[\frac{s}{w_c} + 1 \right] \left[\frac{s}{w_{cp}} + 1 \right]$$

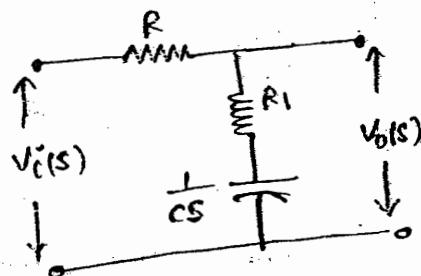
$$= \frac{\left(\frac{w_n}{2\zeta} \alpha \right) \left(\frac{s}{w_c} + 1 \right)}{s \left[\frac{s}{2\zeta w_n} + 1 \right] \left[\frac{s}{w_{cp}} + 1 \right]}$$

\therefore B.W depends on $w_n = w_g \Rightarrow$ when we use P.L.C.

$w_g \uparrow$ hence $B.W \uparrow$



Phase-Lag Compensator



$$\frac{V_o(s)}{V_i(s)} = \frac{R_1 + \frac{1}{Cs}}{R_2 + R_1 + \frac{1}{Cs}} = \frac{(R_1 C_1 s + 1)}{\left(\frac{R_1 + R_2}{R_1}\right) R_1 C_1 s + 1}$$

$$\therefore \beta = \frac{R_1 + R_2}{R_1} > 1$$

$$\beta > 1$$

$$T = R_1 C_1$$

$$\frac{V_o(s)}{V_i(s)} = \frac{(Ts + 1)}{(BTS + 1)} = \frac{1/T \left[\frac{s}{\omega_{cz}} + 1 \right]}{\left[\frac{s}{\omega_{cp}} + 1 \right]}$$

$$\omega_{cz} = \frac{1}{T} \quad \omega_{cp} = \frac{1}{BT} \quad \omega_{cp} > \omega$$

$$\frac{V_o(i\omega)}{V_i(i\omega)} = \frac{1 + i\omega T}{1 + i\omega BT}$$

$$\omega_{cz} = -\frac{1}{T} \quad \omega_{cp} = -\frac{1}{BT}$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = \frac{\sqrt{1 + (\omega T)^2}}{\sqrt{1 + (\omega BT)^2}}$$

* p.Lag compensator is pole dominant.

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = +\tan^{-1}(\omega T) + \tan^{-1}(\omega BT) \quad \because \phi_1 < \phi_2 \Rightarrow \text{result } (-ve) \text{ so } \frac{\phi_1}{\phi_2}$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right|_{dB} = 20 \log 1 + 20 \log \sqrt{1 + (\omega T)^2} - 20 \log \sqrt{1 + (\omega BT)^2}$$

At L.F.R. $\Rightarrow \omega = 0$

$$\frac{V_o}{V_i} = 1 \Rightarrow V_o = V_i$$

$$\left| \frac{V_o}{V_i} \right|_{dB} = 20 \log 1 = 0 \text{ dB}$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right| = \frac{\sqrt{1 + (\omega T)^2}}{\sqrt{1 + (\omega BT)^2}}$$

$R \Rightarrow \omega = \infty$

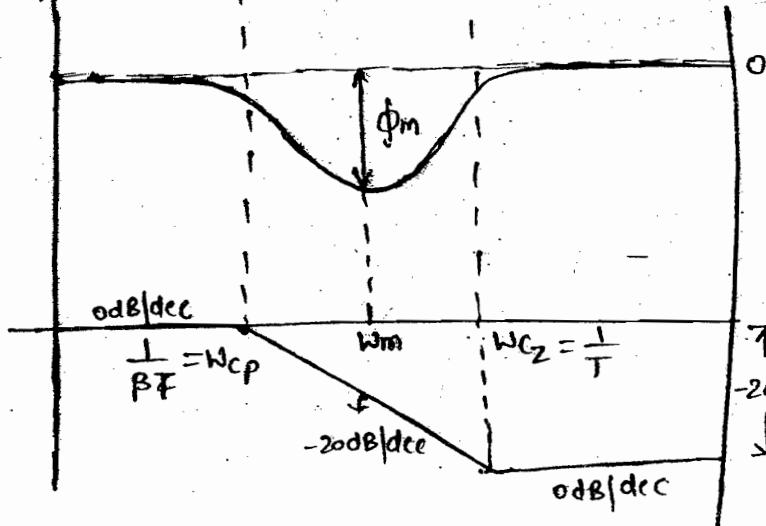
$$= \frac{\sqrt{(WT)^2}}{\sqrt{(\omega\beta T)^2}} = \frac{1}{\beta} \Rightarrow V_o = \frac{1}{\beta} V_i^o$$

Attenuation
O/P β times decrease..

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right|_{dB} = -20 \log \beta$$

$$\left| \frac{V_o(i\omega)}{V_i(i\omega)} \right|_{dB}$$

$$\angle \frac{V_o(i\omega)}{V_i(i\omega)}$$



$-20 \log(\beta)$ for attenuation
filter at H.F.R. \Rightarrow LPF

$$\log \omega_m = \frac{1}{2} \left[\log \frac{1}{T} + \log \frac{1}{\beta T} \right] = \frac{1}{2} \log \frac{1}{\beta T^2} = \log \left(\frac{1}{\beta T^2} \right)^{\frac{1}{2}}$$

$$\log \omega_m = \log \frac{1}{T\sqrt{\beta}} \Rightarrow \omega_m = \frac{1}{T\sqrt{\beta}}, \omega_m T = \frac{1}{\sqrt{\beta}}$$

$$\phi_m = \angle \frac{V_o(i\omega_m)}{V_i(i\omega_m)} = +\tan^{-1}(\omega_m T) - \tan^{-1}(\omega_m T \beta)$$

$$\phi_m = \tan^{-1}\left(\frac{1}{\sqrt{\beta}}\right) - \tan^{-1}(\sqrt{\beta}) = \tan^{-1}\frac{1-\beta}{2\sqrt{\beta}}$$

$$\tan \phi_m = \frac{1-\beta}{2\sqrt{\beta}}, \sin \phi_m = \frac{1-\beta}{1+\beta}, \cos \phi_m = \frac{2\sqrt{\beta}}{1+\beta}$$

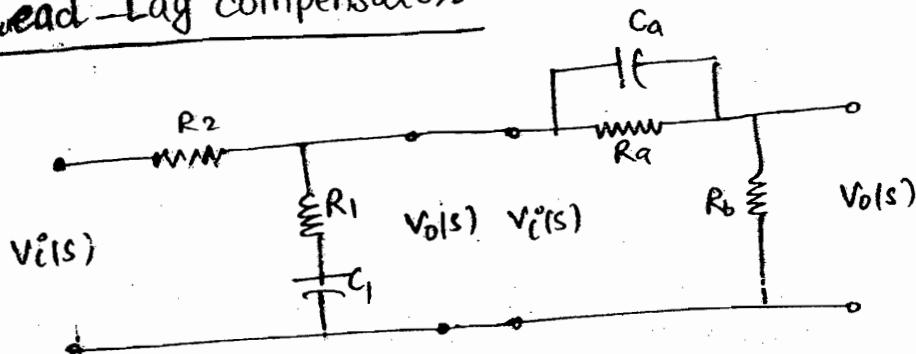
phase lag compensator is pole dominant

phase lag compensator act as low pass filter

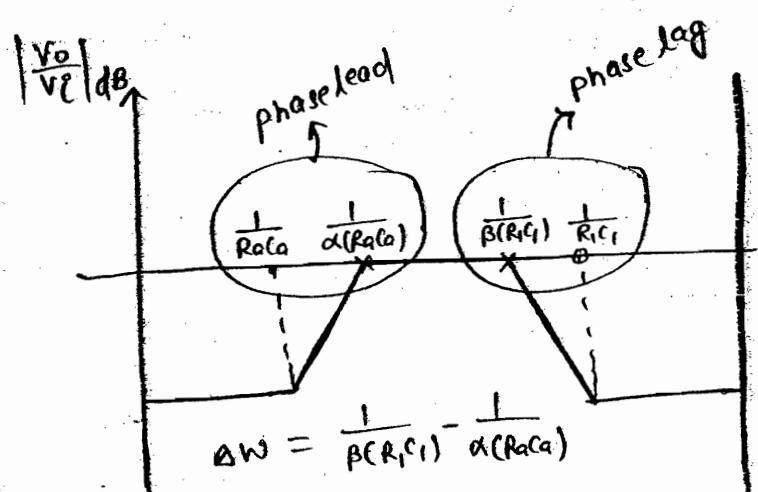
phase lag compensator shift gain crossover freqn to lower value so B.W of system will decrease

P.Lag. C. decrease steady state error. Thus if we want to improve steady state error in that case we will use phase-lag compensator.

Lead-Lag Compensator



$$\begin{aligned} \text{Left side: } & -\frac{1}{R_1 C_1} \quad \beta(R_1 C_1) \\ \text{Right side: } & -\frac{1}{\alpha(R_a C_a)} \quad \frac{1}{R_a C_a} \end{aligned}$$



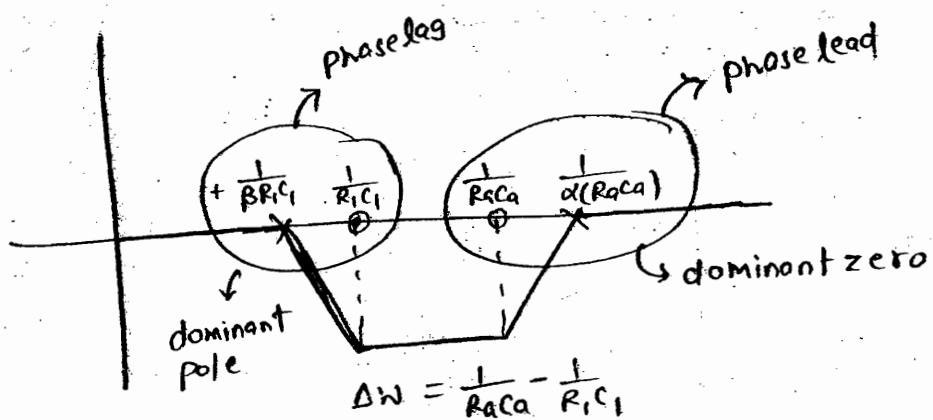
$$\begin{aligned} \text{Left side: } & -\frac{1}{R_1 C_1} \quad \beta(R_1 C_1) \\ \text{Right side: } & -\frac{1}{\alpha(R_a C_a)} \quad \frac{1}{R_a C_a} \end{aligned}$$

To achieve this cond^r

$$\frac{1}{R_a C_a} < \frac{1}{R_1 C_1}$$

$$R_1 C_1 < R_a C_a$$

→ This is Band pass filter

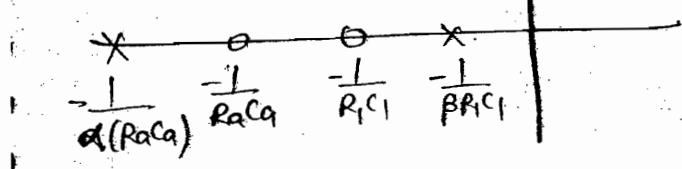


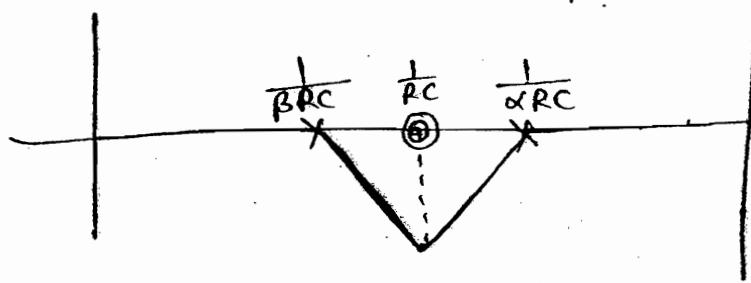
To achieve this requirement

$$\frac{1}{R_a C_a} > \frac{1}{R_1 C_1}$$

$$R_1 C_1 > R_a C_a$$

This is Band elimination filter



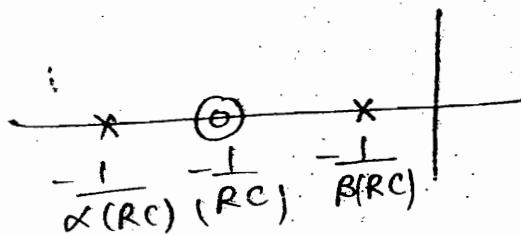


$$R_1 C_1 = R_2 C_2 = RC$$

$$\omega = \frac{1}{RC} \text{ for heavy}$$

attenuation $\rightarrow 20\text{dB}$

\rightarrow Notch Filter

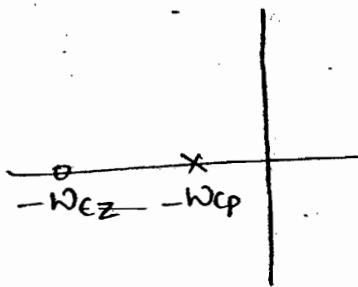


minimum phase and non-minimum phase system

minimum phase system

$$T(s) = G(s) \cdot H(s) = \frac{K \left[\frac{s}{\omega_{cz}} + 1 \right]}{\left[\frac{s}{\omega_{cp}} + 1 \right]}$$

$$\omega_{cp} < \omega_{cz} \Rightarrow \frac{\omega_{cp}}{\omega_{cz}} < 1$$



$$G(i\omega) H(i\omega) = K \left[1 + \frac{i\omega}{\omega_{cz}} \right] / \left[1 + \frac{i\omega}{\omega_{cp}} \right]$$

$$|G(i\omega) H(i\omega)| = K \frac{\sqrt{1 + \left(\frac{\omega}{\omega_{cz}}\right)^2}}{\sqrt{1 + \left(\frac{\omega}{\omega_{cp}}\right)^2}}$$

$$|G(i\omega) H(i\omega)|_{\text{dB}} = 20 \log K + 20 \log \sqrt{1 + \left(\frac{\omega}{\omega_{cz}}\right)^2} - 20 \log \sqrt{1 + \left(\frac{\omega}{\omega_{cp}}\right)^2}$$

$$\angle(G(i\omega) H(i\omega)) = \tan^{-1} \frac{\omega}{\omega_{cz}} - \tan^{-1} \frac{\omega}{\omega_{cp}}$$

AO

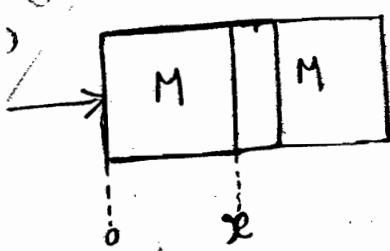
Mathematical Modelling

In case of Mechanical system there is a fixed node known as Ground node and (or) datum node and second node is known as variable node on application of force variable node will move in that direction to achieve equilibrium cond'n. Mechanical system containing mass, spring and damper and force is applied on the mass in this case each mass will have its own variable node and force, spring and damper will use the variable node of this masses.

Mechanical system containing Mass, spring, damper and force is not applied on the mass in this case each mass will have its own variable node, force will also have its own variable node while spring and damper will use the variable node of either force or mass.

- Mechanical system containing spring and damper in series in this case both spring and damper will have its own variable node
- Mass is a second order system, damper is first order system while spring is zero order S/T Mass and damper are responsible for transient behaviour of the S/T while spring is responsible for steady state behaviour.
- * If any mechanical S/T contain N no of mass then overall order of that S/T will be '2N'

Mass



$$F_M = \text{Mass} \times \text{Acceleration}$$

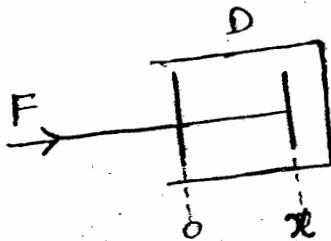
$$F_M = M \left(\frac{d^2x}{dt^2} \right)$$

$\rightarrow \text{if } x = \text{const}$

$$F_M = M \cdot \frac{d}{dt} (v)$$

$\rightarrow \text{if } v \text{ constant}$
Then $F_M = 0$

(2) Damper



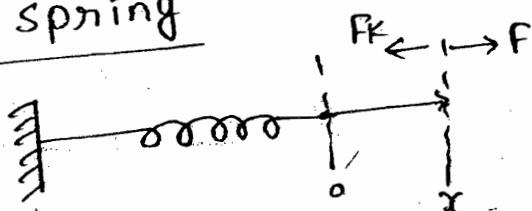
$\rightarrow \text{if } x = \text{const}$
Then $F_D = 0$

$$F_D = D \left(\frac{dx}{dt} \right)$$

friction coefficient

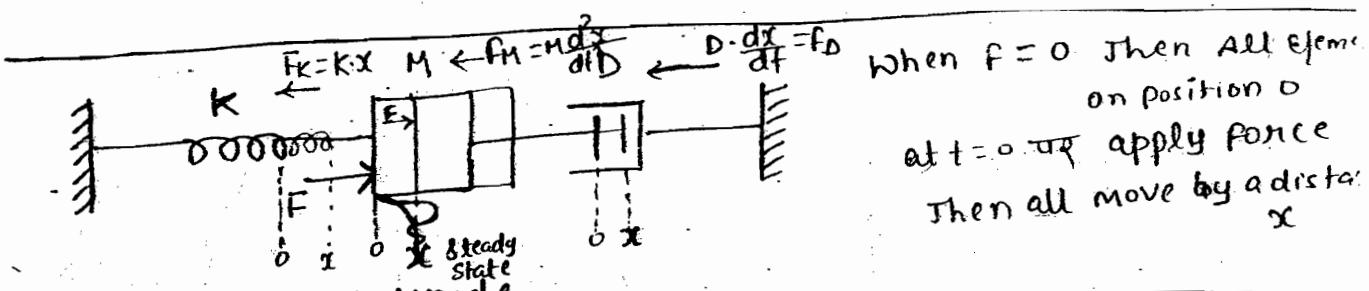
* steady state condition means x becomes constant and $F_M = 0$ & $F_D = 0$
 \Rightarrow After removing force $x = \text{cons}$

③ spring

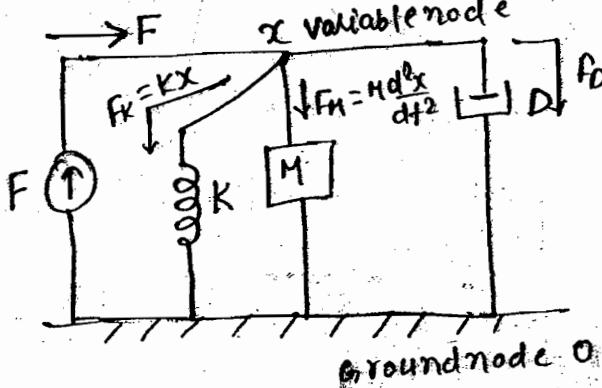


$$F_K = K \cdot x$$

\rightarrow even x constant then
 $F_K \neq 0$



When $F = 0$ Then all elements on position 0
at $t = 0$ we apply force
Then all move by a distance x



F , M , K and D goes away
from ground node to a distance
of x . When apply force.

$$F = F_M + F_D + F_K \Rightarrow F = M \frac{d^2x}{dt^2} + D \frac{dx}{dt} + Kx$$

Apply Laplace transform

$$F(s) = M s^2 X(s) + D s X(s) + K X(s)$$

$$\therefore X(s) = \frac{F(s)}{(M s^2 + D s + K)}$$

transfer function $\frac{X(s)}{F(s)} = \frac{1}{Ms^2 + Ds + K}$

$$\frac{X(s)}{F(s)} = \frac{\left(\frac{1}{M}\right)}{s^2 + \left(\frac{D}{M}\right)s + \frac{K}{M}} \Rightarrow \text{2nd order system.}$$

$$s^2 + \left(\frac{D}{M}\right)s + \frac{K}{M} = s^2 + 2\zeta\omega_n s + \omega_n^2 = 0$$

on comparing $\omega_n = \sqrt{\frac{K}{M}}, 2\zeta\omega_n = \frac{D}{M} \Rightarrow \zeta = \frac{D}{2\sqrt{KM}}$

$$\zeta = \frac{D}{2\sqrt{KM}}$$

case 1 underdamped condition.

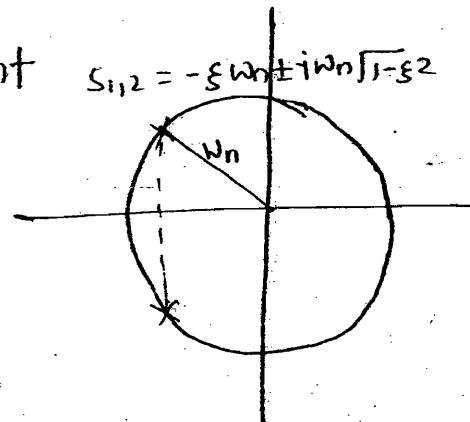
For underdamped cond' $0 < \zeta < 1$

: ω_n should be constant

for this K, M should be = constant $s_{1,2} = -\zeta\omega_n \pm j\omega_n\sqrt{1-\zeta^2}$

so different ζ we can vary D

$$\zeta = \frac{D}{2\sqrt{KM}} < 1 \Rightarrow D < 2\sqrt{KM}$$



$$s_{1,2} = -\zeta\omega_n \pm j\omega_n\sqrt{1-\zeta^2}$$

$$s_{1,2} = -\frac{D}{2M} \pm j\sqrt{\frac{K}{M}}\sqrt{1-\frac{D^2}{4KM}}$$

time constant

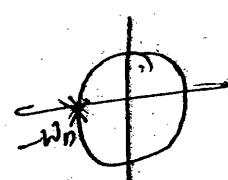
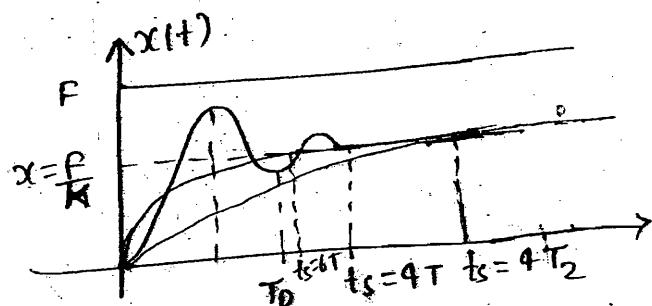
$$T = \frac{1}{\zeta\omega_n} = \frac{2M}{D} \quad \text{for } 2\% \text{ error band} \quad t_s = 4T = \frac{8M}{D}$$

$$T_D = \frac{2\pi}{\omega_d} = \frac{2\pi}{\sqrt{\frac{K}{M}}\sqrt{1-\frac{D^2}{4KM}}}$$

case 2 critically damped

$$\zeta = 1$$

$$\frac{D}{2\sqrt{KM}} = 1 \Rightarrow D = 2\sqrt{KM}$$



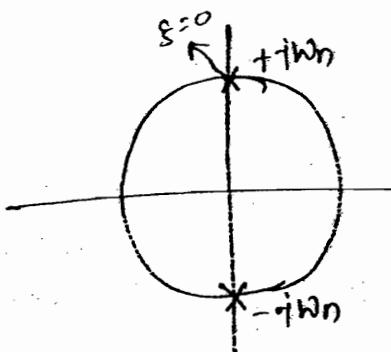
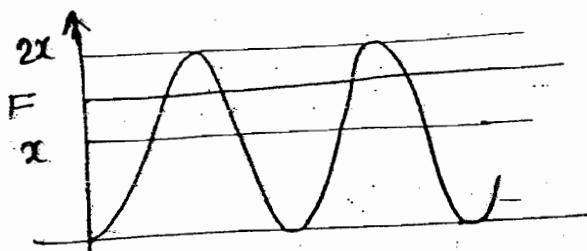
$$\zeta_{1,2} = -\omega_n = -\sqrt{\frac{K}{M}} \Rightarrow T = \frac{1}{\omega_n} = \sqrt{\frac{M}{K}}, t_s = 6T = 6\sqrt{\frac{M}{K}}$$

case-III undamped condn

$$\zeta = 0$$

$$D = 0 \Rightarrow \zeta_{1,2} = \pm i\omega_n = \pm i\sqrt{\frac{K}{M}}$$

$$T = \infty, t_s = \infty$$



Marginally stable
never settle this

Case IV overdamped Cond.

$$\zeta > 1 \Rightarrow \frac{D}{2\sqrt{KM}} > 1$$

$$D > 2\sqrt{KM}$$

$$\zeta_{1,2} = -\zeta\omega_n \pm \omega_n \sqrt{\zeta^2 - 1}$$

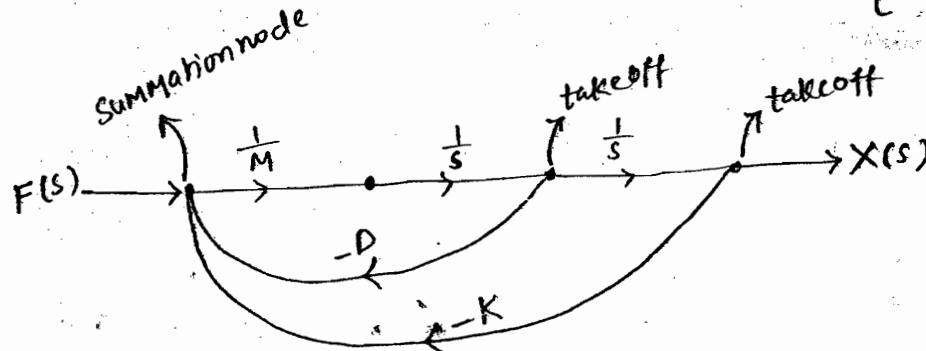
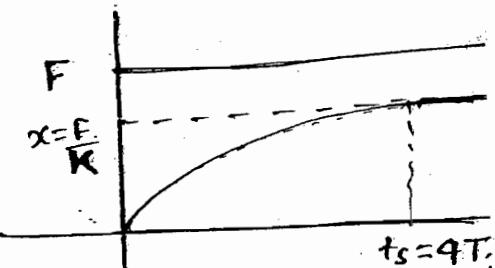
$$\zeta_{1,2} = -\frac{D}{2M} \pm \sqrt{\frac{K}{M} \cdot \sqrt{\frac{D^2}{4KM} - 1}}$$

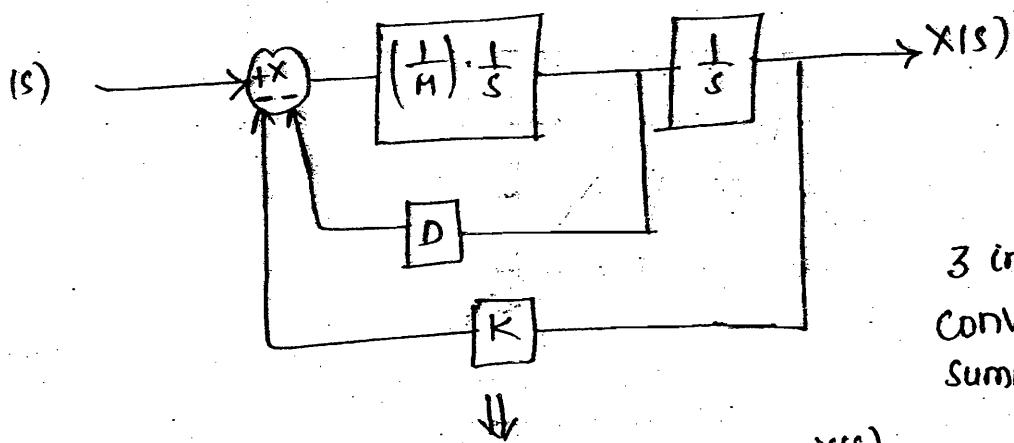
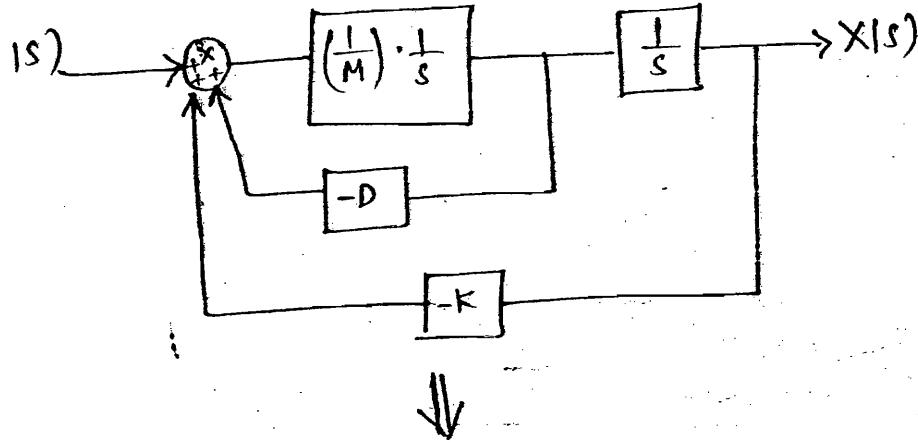
$$\text{time constant } T_2 = \frac{1}{\zeta\omega_n - \omega_n \sqrt{\zeta^2 - 1}}$$

$$T_2 = \frac{1}{\frac{D}{2M} - \sqrt{\frac{K}{M} \cdot \sqrt{\frac{D^2}{4KM} - 1}}}, t_s = 4T_2$$

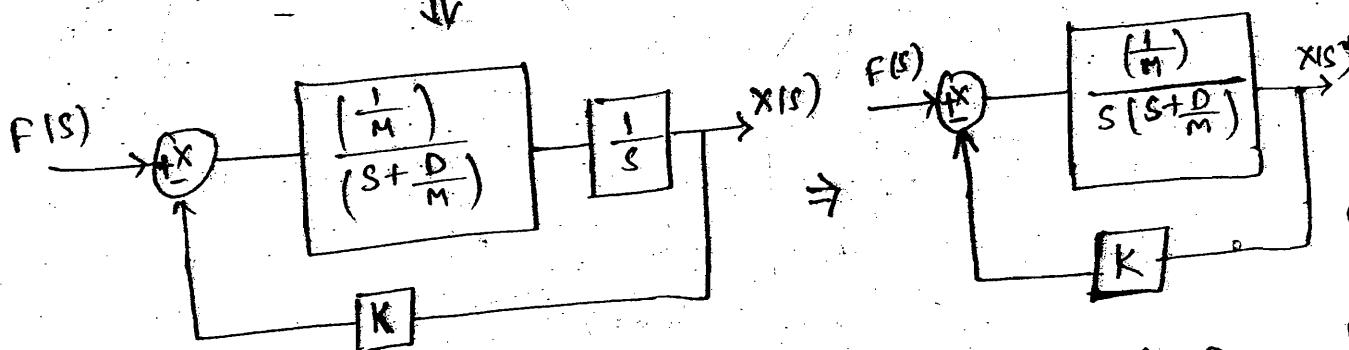
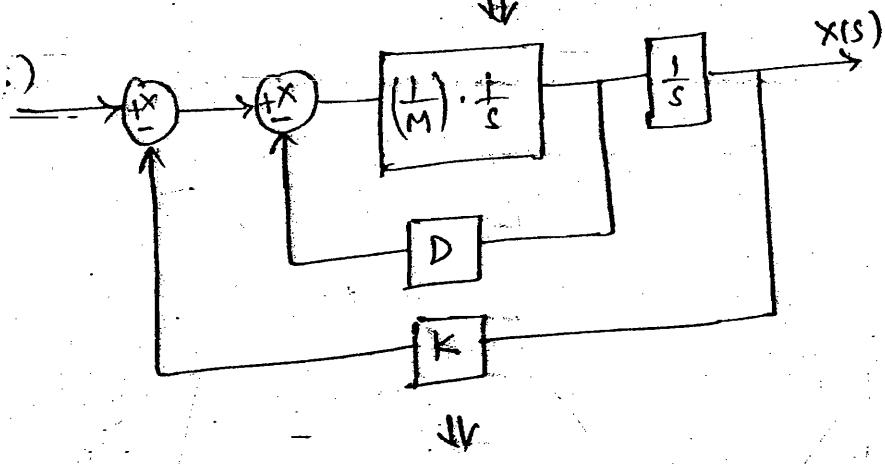
Now

$$\frac{T(s)}{F(s)} = \frac{\left(\frac{1}{M}\right)}{s^2 + \left(\frac{D}{m}\right)s + \left(\frac{K}{m}\right)} = \frac{\left(\frac{1}{M}\right) \frac{1}{s^2}}{1 - \left[-\left(\frac{D}{m}\right) - \left(\frac{K}{m}\right)\right] \frac{1}{s^2}}$$





3 input summation
convert into 2 input
summ' side by side



* It is closed loop
non unity feedback s/t
to make unity feedback s/t
Then we have to put $K=1$ (spring constant)
because opp settle at F not at E

$$\frac{X(s)}{F(s)} = \frac{\frac{1}{M}}{s^2 + (\frac{D}{M})s + \frac{K}{M}}$$

Force Voltage and Force Current Analogy

Force voltage analogy

$$V = L \frac{dI}{dt} + IR + \frac{1}{C} \int I \cdot dt$$

$$V = M \frac{d^2Q}{dt^2} + R \frac{dQ}{dt} + \frac{1}{C} Q$$

$$\left\{ \because I = \frac{dQ}{dt} \right\}$$

on comparing with Force eqn

$$F \leftrightarrow V, M \leftrightarrow L, D \leftrightarrow R, K \leftrightarrow \frac{1}{C}, x \leftrightarrow Q, \dot{x} \leftrightarrow \frac{dQ}{dt}$$

Mechanical in series \Rightarrow electrical H/W will be in parallel

Force current analogy

$$I = C \frac{dU}{dt} + \frac{U}{R} + \frac{1}{L} \int U \cdot dt$$

$$\therefore U = \frac{dP}{dt} \quad \text{go}$$

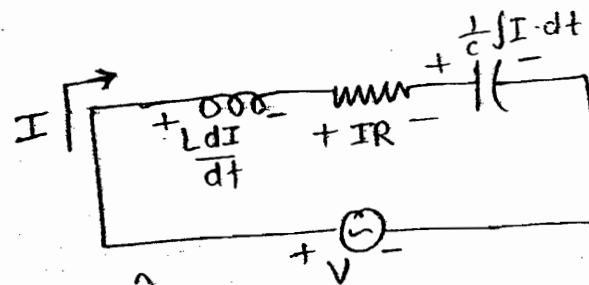
$$I = C \frac{d^2\psi}{dt^2} + \frac{1}{R} \frac{d\psi}{dt} + \frac{\psi}{L}$$

on comparing with force eqn

$$F \leftrightarrow I, M \leftrightarrow C, D \leftrightarrow \frac{1}{R}, K \leftrightarrow \frac{1}{L}, x \leftrightarrow \psi, \dot{x} \leftrightarrow \frac{d\psi}{dt}$$

* In Force-Voltage analogy if mechanical system is connected in parallel then its analogous electrical S/H will be connected in series and vice-versa.

* In force-current analogy if mechanical system is connected in parallel then its analogous electrical S/H will also be connected in parallel and if mech. S/H is connected in series and its analogous electrical S/H will also be connected in series.

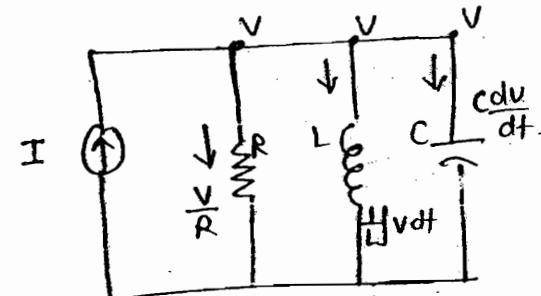


(Velocity,
↑)

$F \leftrightarrow V, M \leftrightarrow L, D \leftrightarrow R, K \leftrightarrow \frac{1}{C}, x \leftrightarrow Q, \dot{x} \leftrightarrow \frac{dQ}{dt}$

Mechanical in series \Rightarrow electrical H/W will be in parallel

Force current analogy



$$I = C \frac{d^2\psi}{dt^2} + \frac{1}{R} \frac{d\psi}{dt} + \frac{\psi}{L}$$

on comparing with force eqn

$$F \leftrightarrow I, M \leftrightarrow C, D \leftrightarrow \frac{1}{R}, K \leftrightarrow \frac{1}{L}, x \leftrightarrow \psi, \dot{x} \leftrightarrow \frac{d\psi}{dt}$$

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