Objective

a) Aim

• To verify the effect of input waveform, loop gain, and system type upon steady-state errors.

b) Apparatus

• MATLAB, Simulink, and the Control System Toolbox.

Theory

a) Description

- Steady-state error is defined as the difference between the input (command) and the output of a system in the limit as time goes to infinity (i.e. when the response has reached steady state). The steady-state error will depend on the type of input (step, ramp, etc.) as well as the system type (0,I, or II).
- Steady-state error can be calculated from the open- or closed-loop transfer function for unity feedback systems.

Steady state error can be calculated by:

$$e_{ss} = \lim_{s \to 0} sE(s) = \lim_{s \to 0} \frac{sR(s)}{1 + G(s)}$$

Input Signals

a) Step Input = 1/s

$$e_{SS} = \frac{1}{1 + \lim_{s \to 0} G(s)} = \frac{1}{1 + K_p}$$

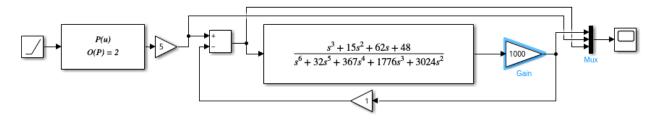
b) Ramp Input = $1/s^2$

$$e_{SS} = \frac{1}{1 + \lim_{s \to 0} sG(s)} = \frac{1}{1 + K_p}$$

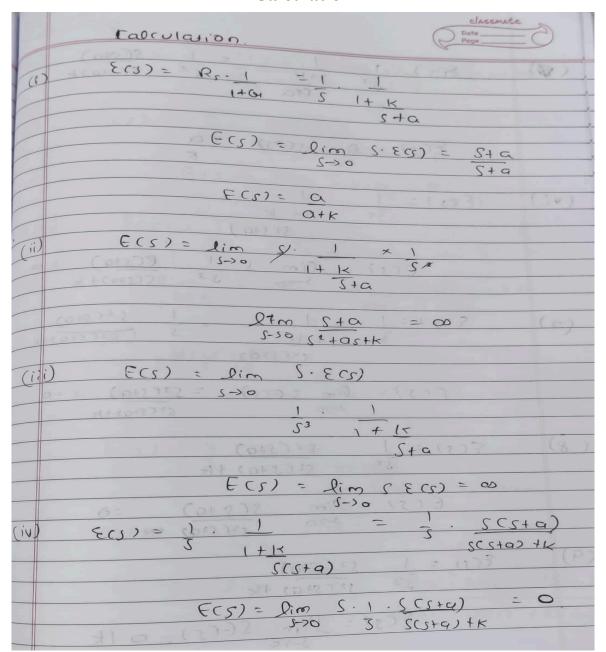
c) Parabolic Input = $1/s^3$

$$e_{ss} = \frac{1}{1 + \lim_{s \to 0} s^2 G(s)} = \frac{1}{1 + K_p}$$

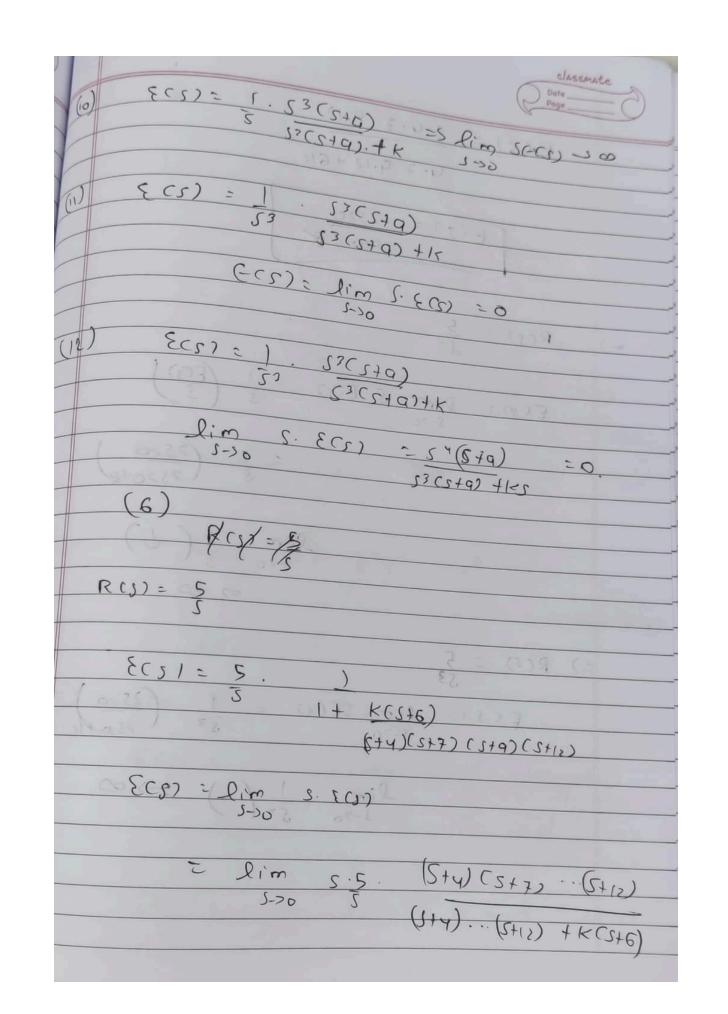
System Design

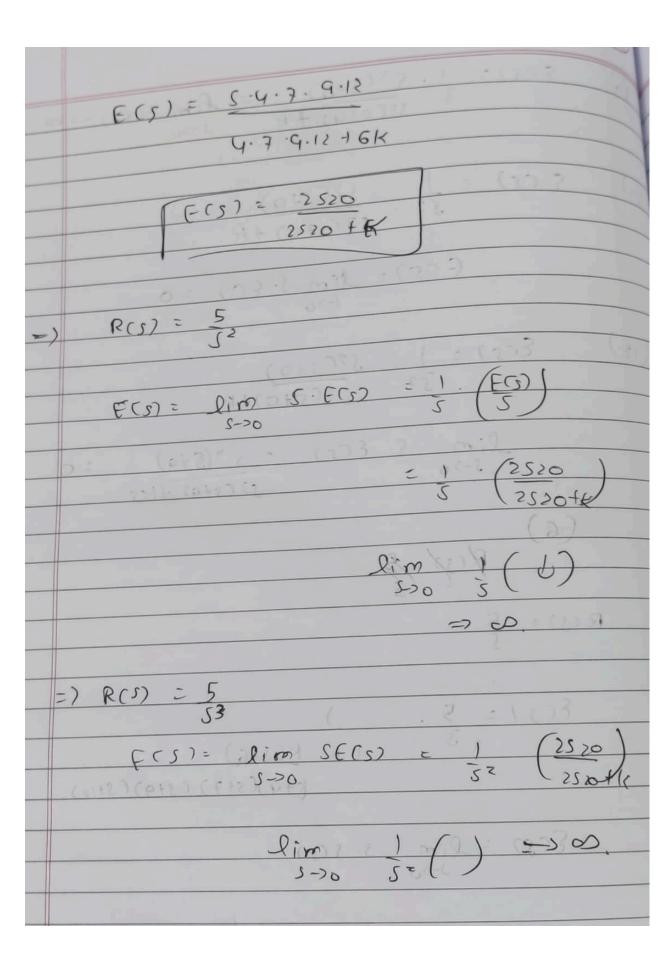


Calculation



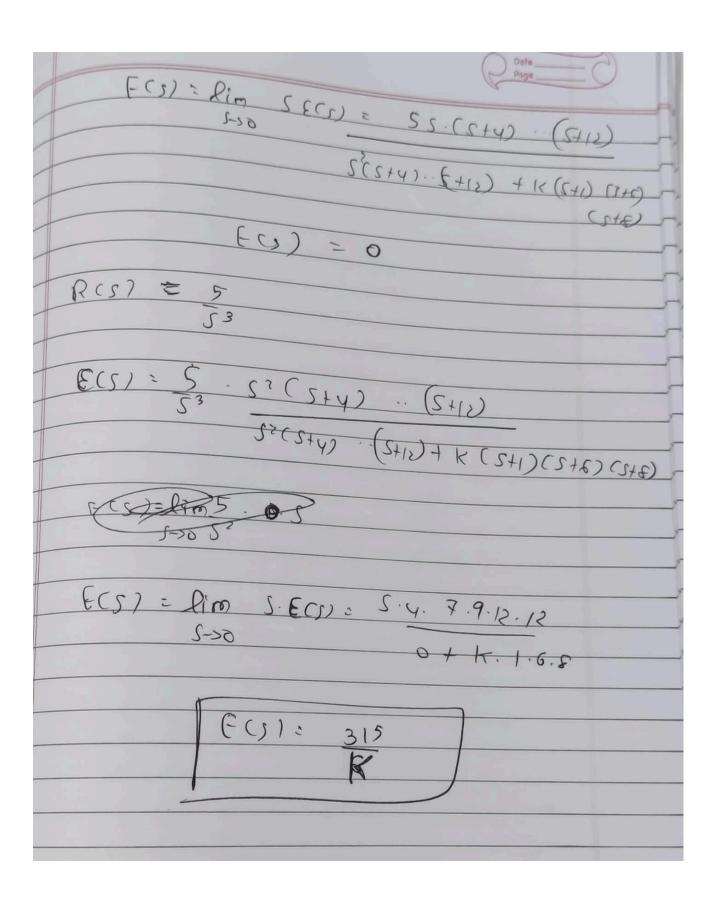
100	Page Page
(4)	$S(c) = 1 \cdot 1 = 1 \cdot S(S(a))$
marine (D)	$\frac{\mathcal{E}(s)=1}{s^2}\frac{1}{1+k}=\frac{1}{s^2}\frac{\mathcal{S}(s+a)}{\mathcal{S}(s+a)+k}$
Market and	54a 10-1
2000	20+2
- M	
	E(3) = lim SEES) = 9
M-2-	J->0 K
W	
(Vi)	EC) 1 : 101 : (7) 3
v	53 -1-(1+ K
	S(S+q)
-	CCC) 1 Pin (Colo)
~	E(S) = lim S. 1 . R(S+q) = 00 S->0 53 S(S+0)+k
-	2(4+e)+ K
(7)	(042) 52 1 (140. 1 = 1,03
(* /	2 55 C2+03 5 5 C2+03 5
	5°(S+Q)
	(203.2 mil = (203 - (1))
	[[]] Di ([])
	7-50 25 (2+0) +K
	71 7 57
(8)	€C57 == 1 .
	52 S2CS+a) +15
101	$\frac{E(S) = \lim_{z \to 0} \frac{S(S+a)}{S(S+a)} = 0$
	J (3+4) FIR
(9)	EC 1 02.62
	E(1) = 1. 52(57a)
	13 (21 - 11
	E(s) = Dim S(-(s) = 0 1k
	((S)= lim S(-(s)- alt
	5-)0
(1) 41	





$\frac{2}{S}$ $\frac{2}{S}$ $\frac{2}{S}$ $\frac{2}{S}$
ECS7: 5. 1
= 5. S(Sty)(S1226 = 5. S(Sty)(S1226
S (2+45) (2+55) (2+15)
$F(s) = \lim_{n \to \infty} S(s)$
3-50
S(S+4) (S+15) + KCS+E) CS+E) S(S+4) (S+15) + KCS+E) CS+E)
(a) (P+2)(P+2)(P+3)()
) R(S) = (5)
$\frac{S(S+4)(S+4)(S+4)(S+6)}{S(S+4)(S+6)}$
+ K(2+e)(2+t) + K(2+e)(2+t)
ECS) = lim S.FCS) = 5.4-7.9.12.12 15-30 K.60.5

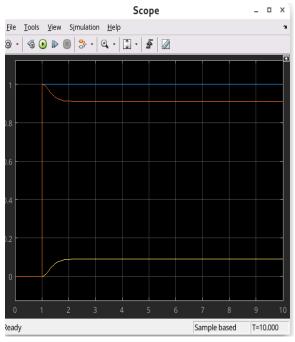
	7 = 315	
	E(s) = 315	
	3	
	$P(S) = \frac{5}{S^3}$	
	53	
	TEGO)	
	E(1)-lim = 1 [E(5)]	
	TANK TERM MANUAL AND	
	ECS): lim 1 (315) 500 5 (K)	
	50 S C R	1
	$(-(s) \rightarrow \infty)$	1
(8)		
(0)	RC57 = 5	1
	5	1
		+
	{(S) = 5. 57(S+4)(S+7)(S+9)(S+12)	+
(2003 B)	S2(S+4)(S+7)(S+9)(S+18)+	1
	k (2+1)(3+6) (5+8)	1
	E())= lim 5.E(s) = 0	-
	05-7	
Car	1)(0+2)(\$12)(p+2)? ? = (p)3	
	R(s) = 5	
(= 3	J (2+12) (32) (4+2) (
(2x)	2(24)	
	ECS 1-2 5 8 (S+4) (S+12) 52 (S+4) (S+12) + K(S+1)(
4141	57 - (35 6)	_
	(St (St4) - (St1) + K(St1)(S+6)
_ 517		5+8)
with		No. of Parties



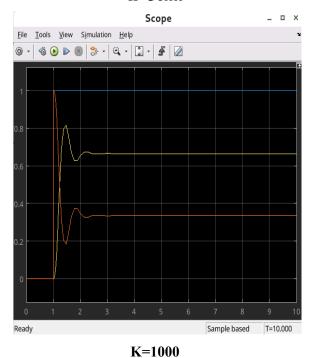
Graphs

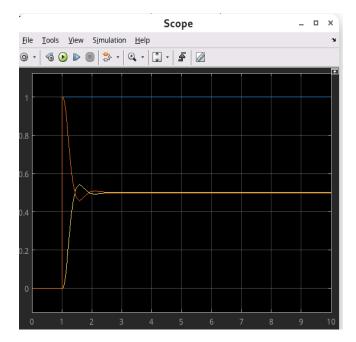
a) Question-6

Step Input

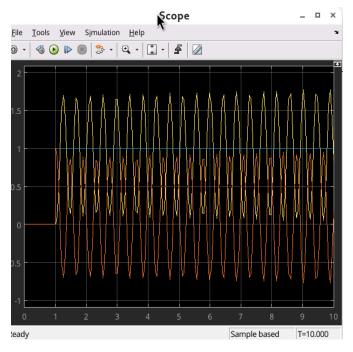








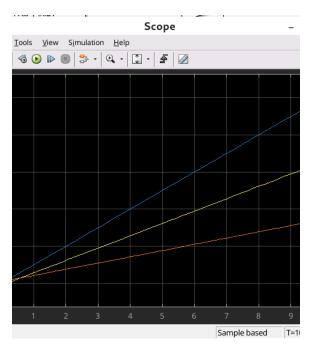
k=500



k=5000

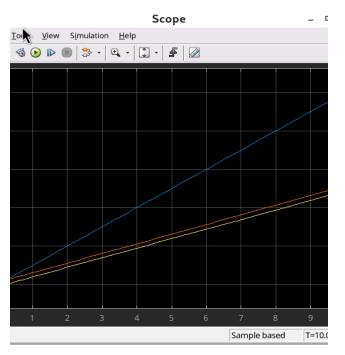
a) Question-6

k=50[OBJ]

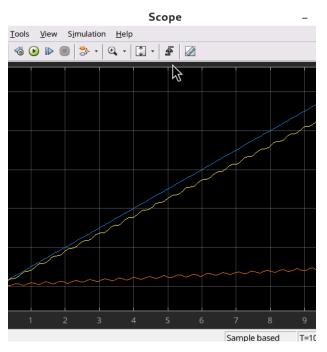


K=1000

Ramp Input



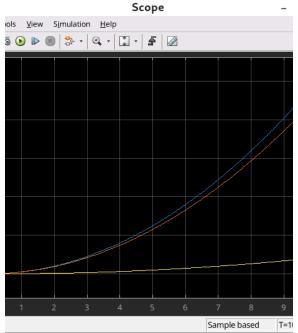
k=500



k=5000

a) Question-6

Polynomial Input



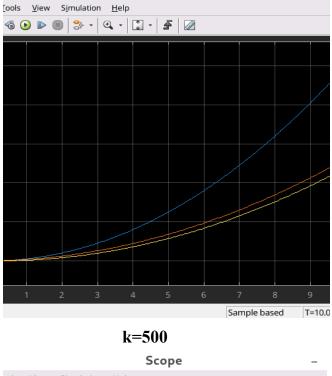
k=50

<u>V</u>iew S<u>i</u>mulation <u>H</u>elp

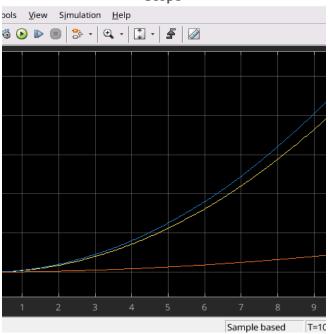


K=1000

Sample based



Scope

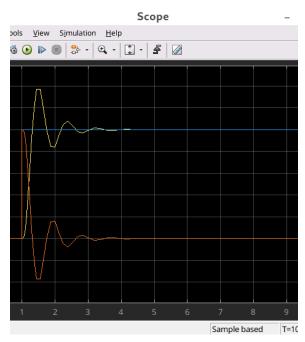


k=5000

b) Question-7

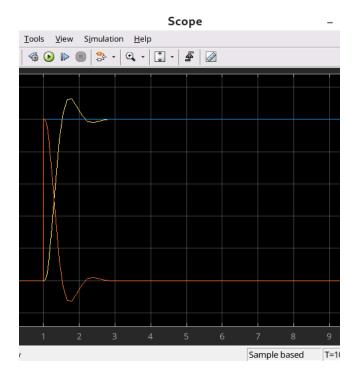
Scope Cools View Simulation Help Cools View Simulation Help

k=50[OBJ]

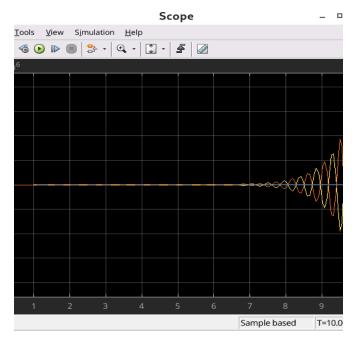


K=1000

Step Input



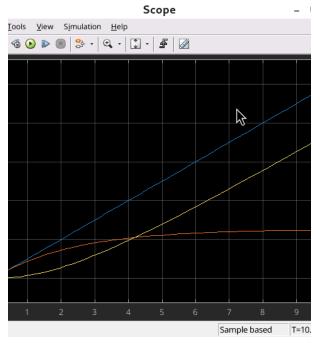
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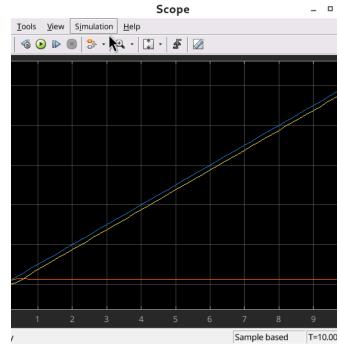


k=5000

b) Question-7

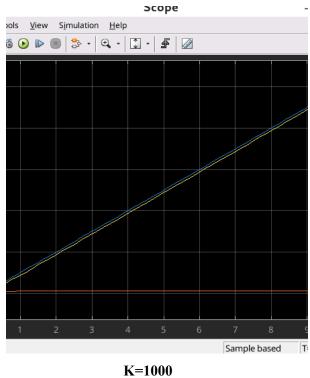
Ramp Input

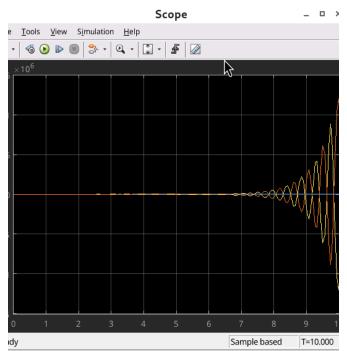




k=50[0BJ]

k=500

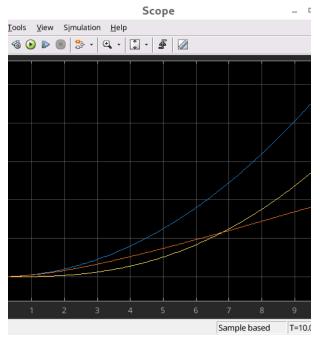


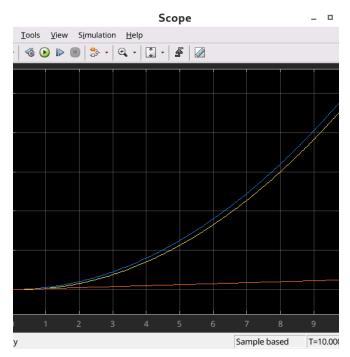


k=5000

b) Question-7

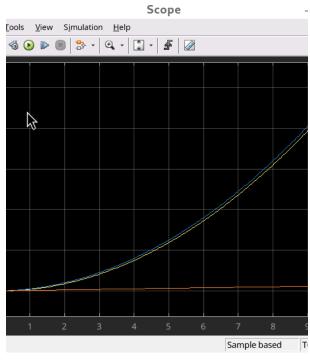
Ploynomial Input

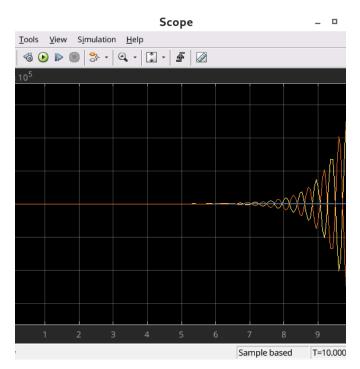




k=50[OBJ]

k=500



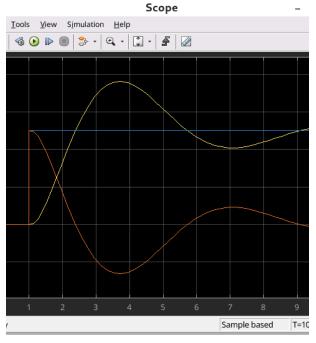


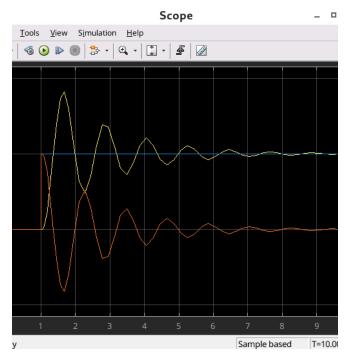
K=1000

K=5000

c) Question-8

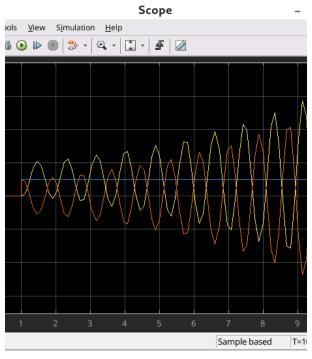
Step Input

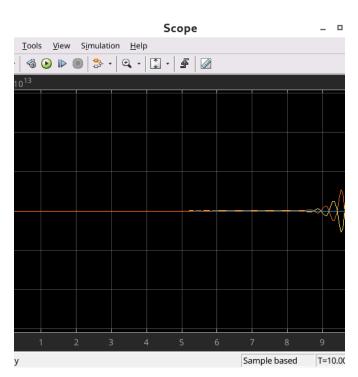




k=50[OBJ]

k=500



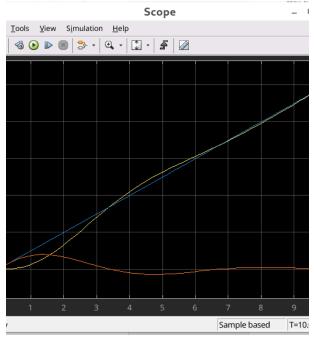


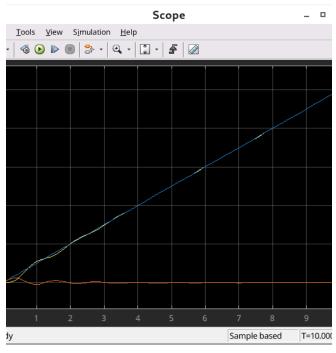
K=1000

K=5000

c) Question-8

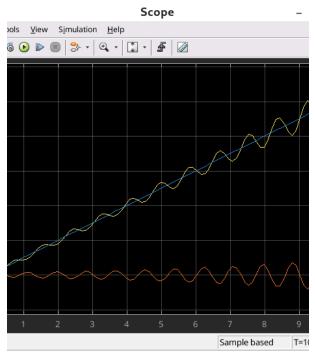
Ramp Input

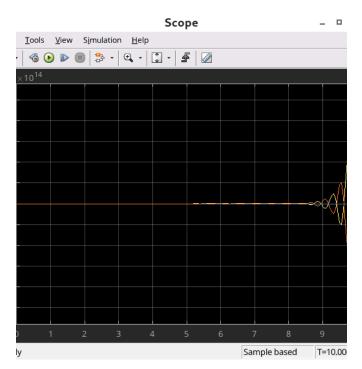




k=50[OBJ]

k=500





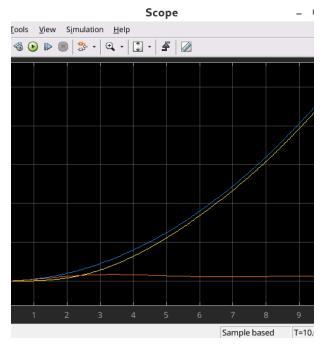
K=1000

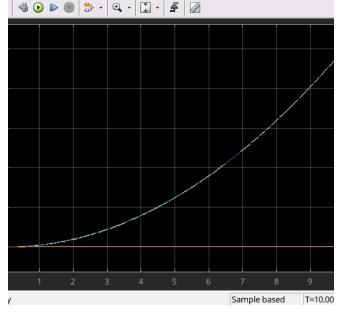
K=5000

c) Question-8

Polynomial Input

<u>T</u>ools <u>V</u>iew S<u>i</u>mulation <u>H</u>elp

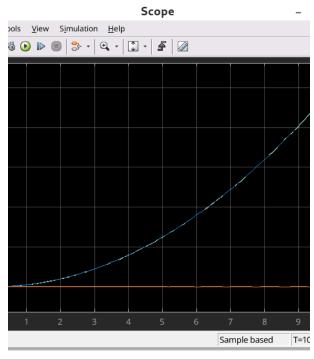


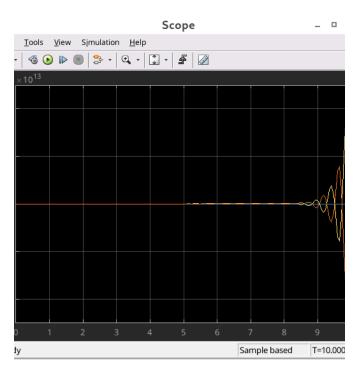


Scope

k=50[OBJ]

k=500





K=1000

K=5000