22-S1-Q2

Q: 
$$T=1$$

(a) show pulse transfer function

Solution let Digital controller transfer function

 $E(Z) = R(Z) - C(Z)$ 
 $C(Z) = C(Z) = \frac{C(Z)}{E(Z)}$ 
 $C(Z) = R(Z) - C(Z)$ 
 $C(Z) = R(Z) - C(Z)$ 

So the system has a pulse transfer function (b) apply 2 transform of the equation  $M(Z) - z^{-1}M(Z) = 2.2E(Z) - 1.4 z^{-1}E(Z) + 0.2 Z^{-2}E(Z)$ 

$$M(z) = \frac{2 \cdot 2 - 1.4z^{-1} + 0.2z^{-2}}{1 - z^{-1}}$$

PID controller 
$$G(z) = k_p + \frac{k_z}{1-z^{-1}} + k_D(+z^{-1})$$
 $\frac{M(z)}{E(z)} = \frac{A(1-z^{-1})^2 + B(1-z^{-1}) + C}{1-z^{-1}}$ 
 $A(1-2z^{-1}+z^{-2}) + B - Bz^{-1} + C$ 
 $= Az^{-2} + (-2A-B)z^{-1} + (A+B+C)$ 
 $\zeta A = 0.2$ 
 $\begin{cases} A = 0.2 \\ -2A-B = -1.4 \\ A+B+C = 2.2 \end{cases}$ 
 $\begin{cases} B = [.4-2x0.2 = ] \\ C = 2.2-1.2 = ] \end{cases}$ 
 $C = 2.2-1.2 = [$ 
 $M(z) = 0.2(1-z^{-1})^2 + (1-z^{-1}) + [$ 
 $= 0.2(1-z^{-1}) + [ + \frac{1}{1-z^{-1}} + 0.2(1-z^{-1}) ]$ 

compare than dard PID controller

 $G(z) = k_p + \frac{k_z}{1-z^{-1}} + k_D(1-z^{-1})$ 
 $k_p = 1$ 
 $k_z = 1$ 
 $k_z = 1$ 
 $k_z = 0.2$ 

So it is a P2D controller

$$= \frac{-0.2}{1-0.13532^{-1}} + \frac{0.6}{1-2^{-1}} + 0.27n2$$

from(b) 
$$G_{b(8)} = \frac{M(2)}{E(3)} = 1 + \frac{1}{(-2^{-1})}$$

$$= \left[1 + \frac{1}{(-z^{-1})} + 0.2(1 - z^{-1})\right] \frac{0.8647 z^{-1}}{(-0.1353z^{-1})}$$

$$= \left[2 - z^{-1} + 0.2(1 - z^{-1})^{2}\right] 0.8647 z^{-1}$$

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$$= \left[2 z^{2} - z + 0.2(z^{2} - 2z + 1)\right] 0.8647$$

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$$= \left[2 z^{2} - z + 0.2z^{2} - 0.4z + 0.2\right) 0.8647$$

$$= \left[2 \cdot 2z^{2} - 1.4z + 0.2\right) 0.8647$$

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$$= \left[4 \cdot 2z^{2} - 1.4z + 0.2\right] 0.8647$$

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$$= \left[4 \cdot 2z + 0.2z^{2} - 2z$$

## [.9023(8-0.4199)(8-0.2165)

$$= \frac{1.90232^2 - 1.21062 + 0.172935}{2^3 + 0.76702^2 - 1.07532 + 0.172935}$$