Control Systems

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Contents

***Abstract*—This manual is an introduction to control systems based on GATE problems.Links to sample Python codes are available in the text.**

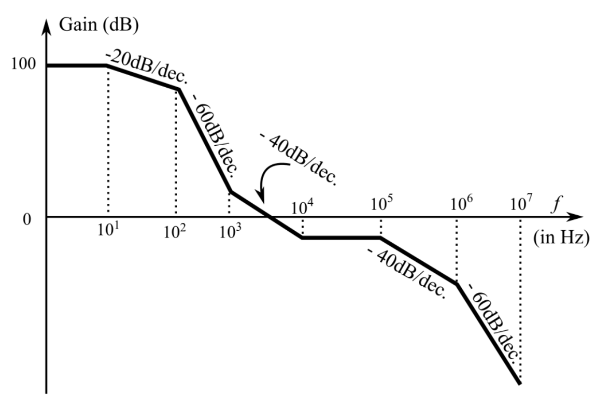
Download python codes using

```
svn co https://github.com/gadepall/school/trunk/
    control/codes
```

1 Routh Hurwitz Criterion

2 Bode Plot

2.1. For an LTI system, the Bode plot for its gain is as illustrated in the Fig. **??** The number of system poles N_p and number of system zeros N_z in the frequency range 1 Hz $\leq$ f $\leq 10^7$ Hz is



Solution:-

Let us consider a generalized transfer gain

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$H(s) = k\frac{(s-z_1)(s-z_2)...(s-z_{m-1})(s-z_m)}{(s-p_1)(s-p_2)....(s-p_{n-1})(s-p_n)}$

$$\text{Gain} = 20\log|H(s)| = 20\log|k| + 20\log|s-z_1| + 20\log|s-z_2| + \cdots + 20\log|s-z_m| - 20\log|s-p_1| - 20\log|s-p_2| - \cdots - 20\log|s-z_n| \quad (2.1.1)$$

Let us consider a $20\log|s-z_1|$

Let $s = j\omega$

$20\log|s-z_1| = 20\log\left|\sqrt{\omega^2+z_1^2}\right|$

Based on log scale plot approximations,to the left of z_1 $\omega << z_1$ and towards right $\omega >> z_1$

For $\omega < z_1$

$20\log|s-z_1| = 20\log\left|\sqrt{\omega^2+z_1^2}\right| = 20\log|z_1|$

$= constant$ i.e. Slope = 0

For $\omega > z_1$

$20\log|s-z_1| = 20\log\left|\sqrt{\omega^2+z_1^2}\right| = 20\log|\omega|$

i.e Slope = 20

When a zero is encountered the slope always increases by 20 dB/decade

Doing similar analysis for $-20\log|s-p_1|$

We conclude

When a pole is encountered the slope always decreases by 20 dB/decade

$Slope = \frac{d(20\log H(f))}{df}$

$$Slope = \begin{cases} 0 & 0 < f < 10^1 \\ -20 & 10 < f < 10^2 \\ -60 & 10^2 < f < 10^3 \\ -40 & 10^3 < f < 10^4 \\ 0 & 10^4 < f < 10^5 \\ -40 & 10^5 < f < 10^6 \\ -60 & 10^6 < f < 10^7 \end{cases}$$

$\Delta Slope =$ Change in slope at f

$$\Delta Slope = \begin{cases} -20 & f = 10^1 \\ -40 & f = 10^2 \\ +20 & f = 10^3 \\ +40 & f = 10^4 \\ -40 & f = 10^5 \\ -20 & f = 10^6 \end{cases}$$

$\boxed{\mathrm{N}_p = 6 \ N_z = 3}$

3 Compensators

4 Nyquist Plot