Case 1: Block Diagram R(s)  $G_{\alpha} \rightarrow G_{\rho} \rightarrow \times (s)$ K Oals) - O. I S(SH)  $K \rightarrow G_{\alpha}G_{p} = \underbrace{O.2}_{S(SH)} \times (S)$  $\rightarrow G_{\alpha}G_{\rho}K: \underbrace{O.2K}_{S(s+1)} \longrightarrow X(s)$ OLTF =  $\frac{X}{E} = \frac{o_2 K}{s(s+a)}$  CLTF =  $\frac{C}{R} = \frac{K(2)(\frac{o_1}{s(s+1)})}{1 + K(2)(\frac{o_1}{s(s+1)})}$ Specifications: 1.) and order system 2. Junderdamped because it moves quickly to the desired output, so when a lone change is needed the respone is immediate with some overshoot. (Furthermore, underdamped systems have less bandwidth and are more practical  $\frac{\left(\frac{O.2}{S(SH)}\right)}{\left(\frac{S(SH)}{S(SH)}\right)} = \frac{O.3K}{S(SH)+O.3K} = \frac{O.2K}{S^2+S+O.2K}$   $\frac{3K}{S(SH)}$ 2W/3= 1 W/3= 1/2 1=1/2W/

control Incony CAT

R(s) 
$$K + G_{A} \rightarrow G_{P}$$

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N=  $K + G_{A} \rightarrow G_{P}$ 

R(s)  $K + G_{A} \rightarrow G_{P}$ 

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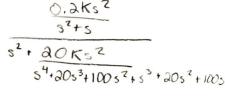
N=  $K + G_{A} \rightarrow G_{P}$ 

R(s)  $K + G_{A} \rightarrow G_{$ 

CAY

$$\frac{K(2)(\frac{s^2 0.1}{s(s+1)})}{s^2 + K(2)(\frac{s^2(0.1)}{s(s+1)})(\frac{100}{s^2 + 20s + 100})}$$

$$\frac{0.2 K s^2}{s^2 + s} = \frac{1}{s^2}$$



$$\frac{(5^{7}+3)(5^{4}+3)(5^{3}+1205^{2}+1005)}{(5^{2}+5)(5^{4}+3)(5^{4}+3)(5^{3}+1205^{2}+1205^{3}+1205^{2}+1205^{3}+1205^$$

54+2053+10052+53+2052+1005+20K

 $\frac{0.4(5^{2}+3051100)}{(5^{2}+5)(5^{2}+305100)+20} = \frac{0.45^{2}+85+40}{5^{4}+305^{3}+1005^{2}+30+5^{3}+305^{4}+100}$ 

= 0.452+85+40 54,2153+12052+1005+20