

# ASSIGNMENT

$$1.1 \text{ A.1) } G_1(s) = \frac{10}{s+10}$$

(1)

$$\text{Pole: } s = -10$$

$$G_1(0) = \frac{10}{0+10} = 1$$

$$(2) \quad G(s) = \frac{1}{1 + \left(\frac{s}{\omega_0}\right)} \quad (\omega_0 = 10)$$

$$\text{Put } s = j\omega$$

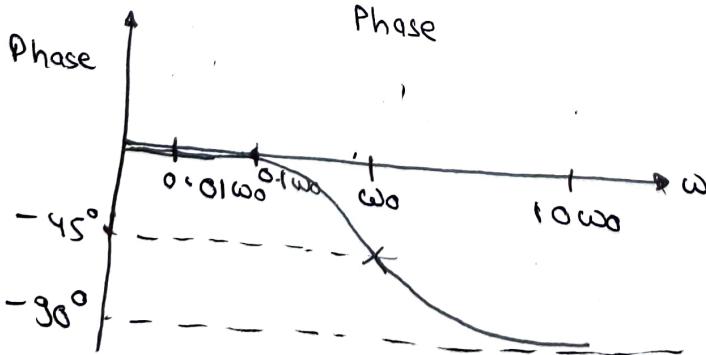
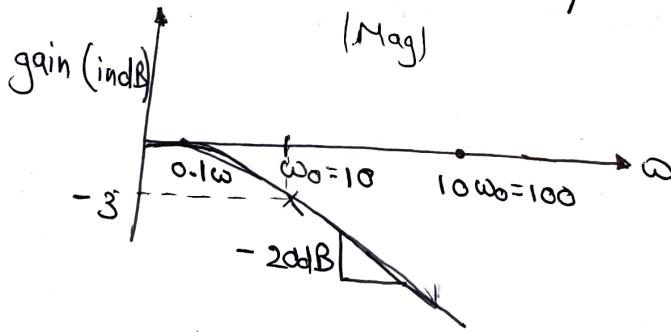
$\Rightarrow$

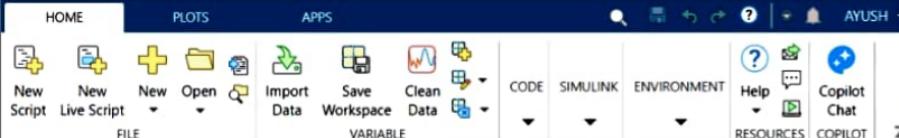
$$G(j\omega) = \frac{1}{j\omega + \left(\frac{\omega}{\omega_0}\right)} = \frac{1 - j\omega/\omega_0}{1 + (\omega/\omega_0)^2}$$

$$|G(j\omega)| = \left(1 + \frac{\omega^2}{\omega_0^2}\right)^{-1/2} \quad \arg(G(j\omega)) = \tan^{-1}\left(-\frac{\omega}{\omega_0}\right)$$

$$\text{gain} \Rightarrow 20 \log_{10} \left(1 + \frac{\omega^2}{\omega_0^2}\right)^{-1/2}$$

$$\phi = \text{Phase} = \tan^{-1}\left(-\frac{\omega}{\omega_0}\right)$$



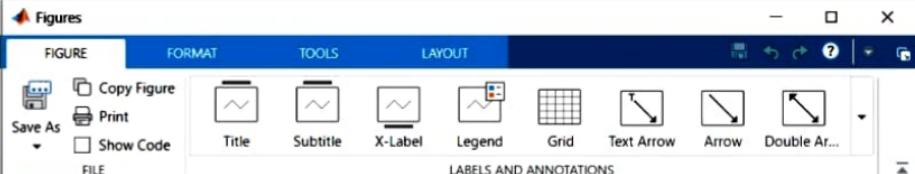


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## Command Window

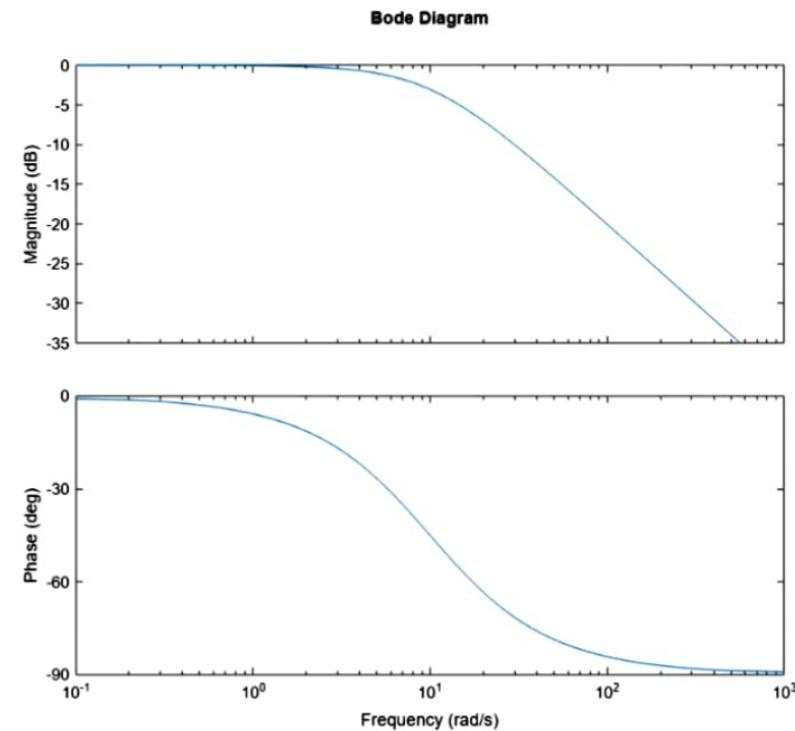
```
G1 =  
10  
-----  
s + 10  
  
Continuous-time transfer function.  
Model Properties  
  
Numerator: {[0 10]}  
Denominator: {[1 10]}  
Variable: 's'  
IODelay: 0  
InputDelay: 0  
OutputDelay: 0  
InputName: '{}'  
InputUnit: '{}'  
InputGroup: [1x1 struct]  
OutputName: '{}'  
OutputUnit: '{}'  
OutputGroup: [1x1 struct]  
Notes: [0x1 string]  
UserData: []  
Name: ''  
Ts: 0  
TimeUnit: 'seconds'  
SamplingGrid: [1x1 struct]  
  
>> bode(G1)
```

>>



LABELS AND ANNOTATIONS

Figure 1 x



$$(1.2) \quad G_2(s) = \frac{s-2}{s+10}$$

zero:  $s=2$  pole:  $s=-10$   $G_2(0) = -0.2$

$$G_2(s) = \frac{s-2}{s+10}$$

$\Rightarrow$  By logarithmic property

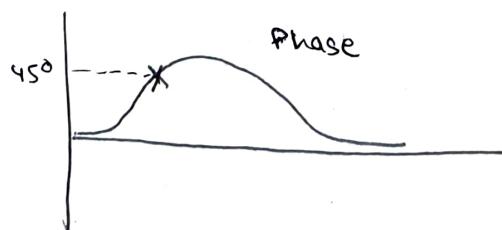
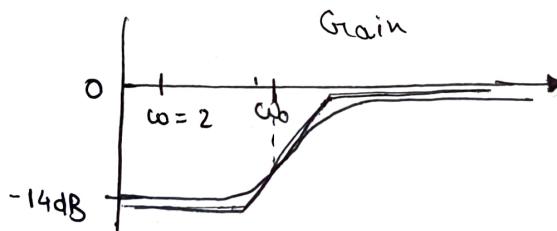
$$\text{Gain} = \text{gain}(s-2) - \text{gain}(s+10)$$

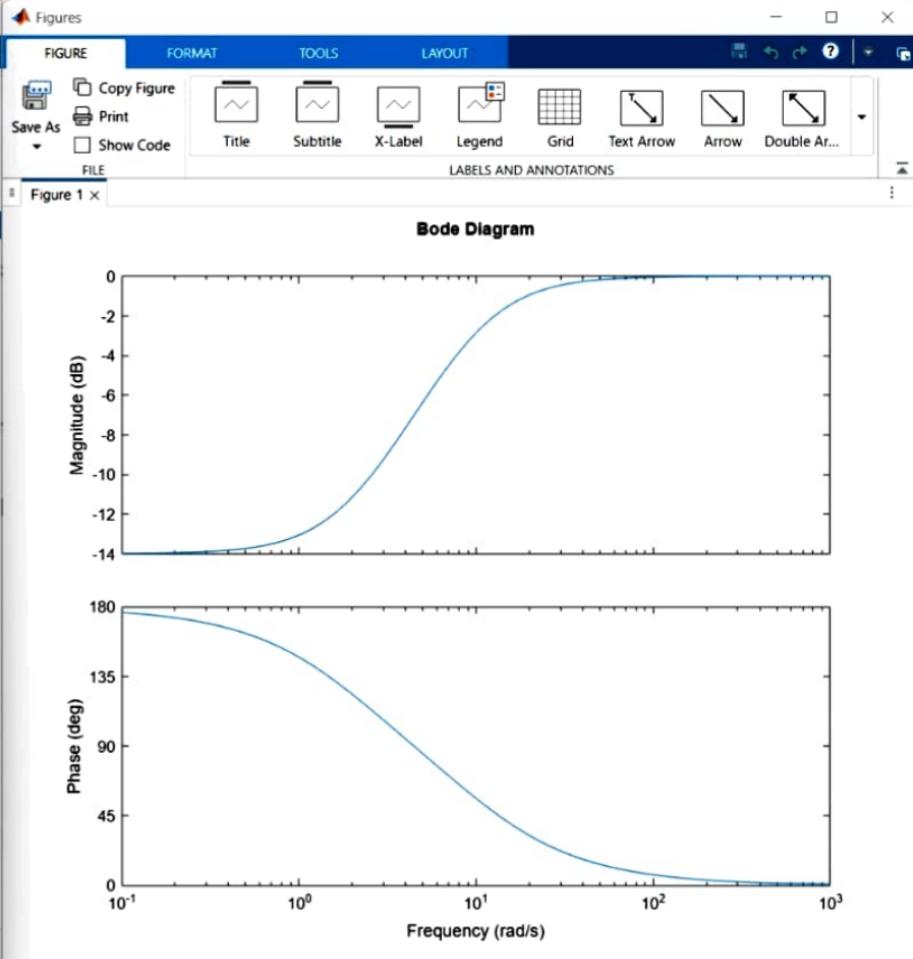
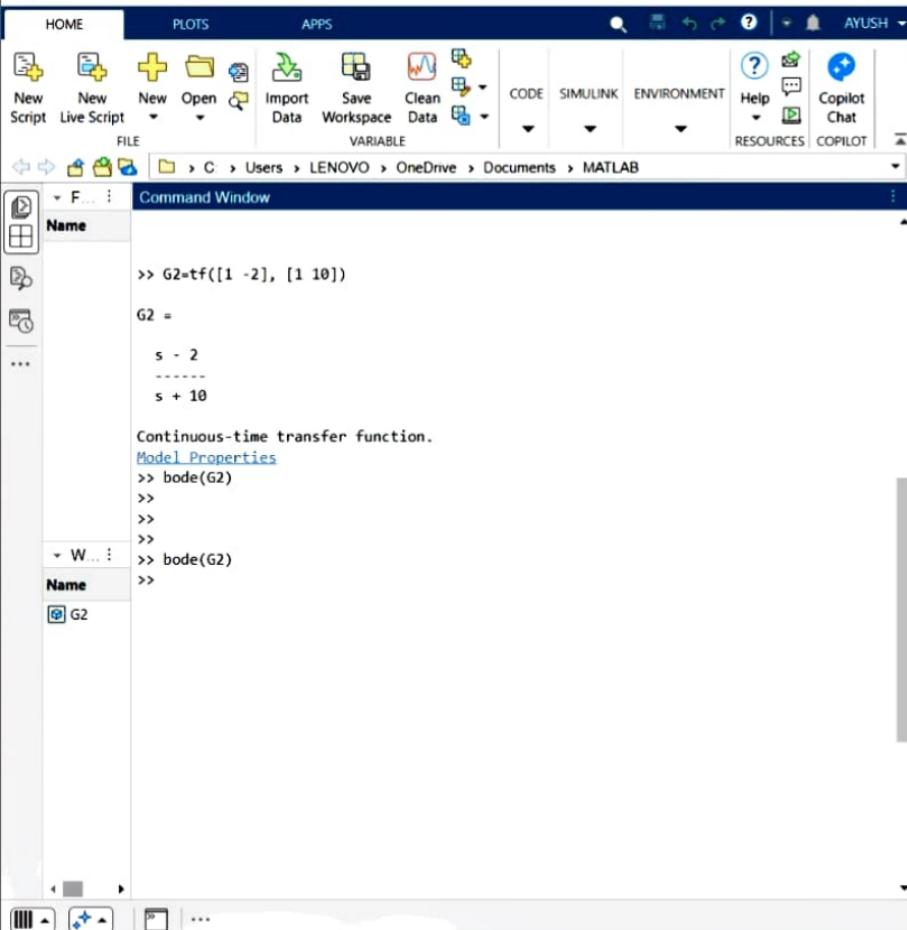
$$\text{gain}(s-2) = 2\left(\frac{s}{2} + 1\right) = \frac{2}{\frac{1}{\frac{s}{2} + 1}} = \frac{-2}{1 + \left(\frac{s}{-2}\right)} = \text{gain}(-2)$$

$$\begin{aligned} \text{gain}(s+10) &= \frac{10}{1 + \left(\frac{s}{10}\right)} \\ &= \text{gain of } 10 - \text{gain of } \left(\frac{1}{1 + \frac{s}{10}}\right) \end{aligned}$$

$$\begin{aligned} \text{gain}(-2) &= 6 \text{ dB} \\ \text{gain}(+10) &= 20 \text{ dB} \end{aligned} \quad \} \text{CONSTANT}$$

Adding the gain plots  $\# 4$  we get





(1.3)

$$G_3(s) = \frac{100}{s^2 + 10s + 100}$$

(1)

Pole:  $s = 5 \pm 5\sqrt{3}j$

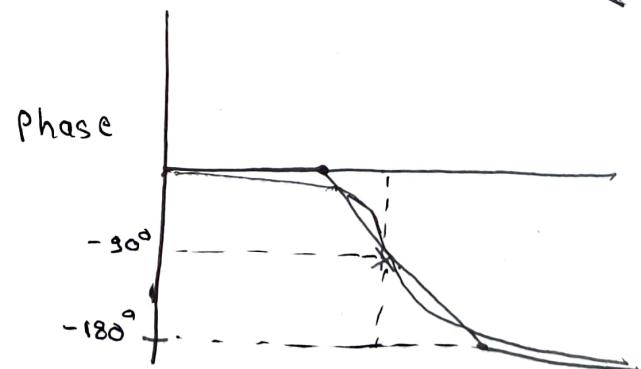
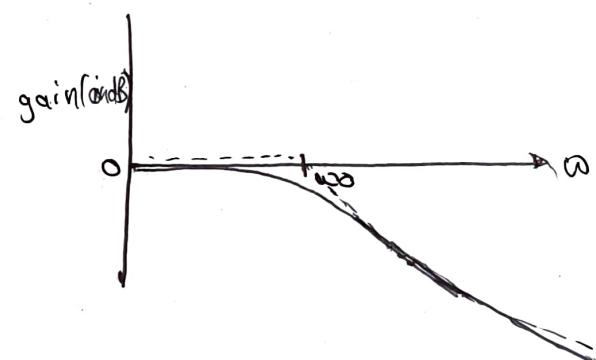
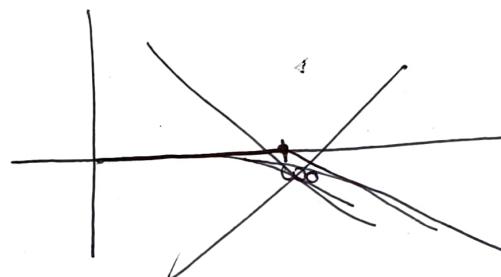
$j = \sqrt{-1}$

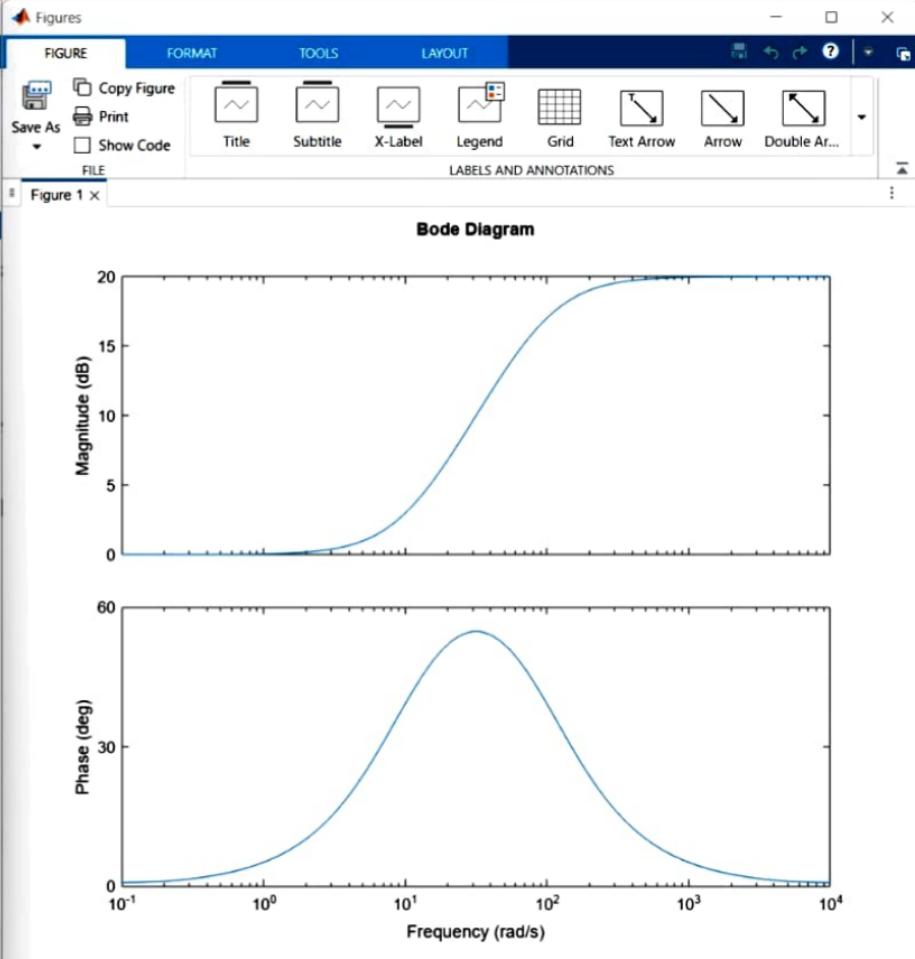
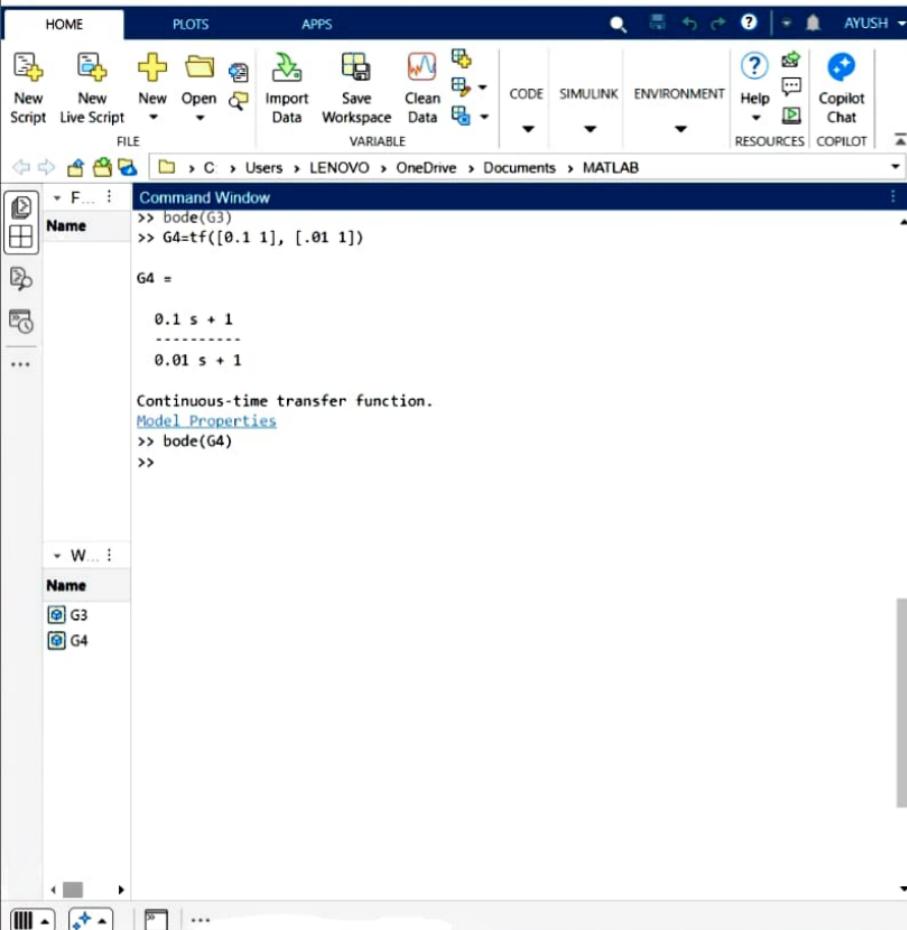
(2) BODE PLOT

$$G_1(s) = \frac{\omega_0^2}{s^2 + 2z\omega_0 s + \omega_0^2}$$

$$\omega_0 = 10, 2z\omega_0 = 10 \Rightarrow z = \frac{1}{2}$$

When  $z = 0.5$ , for  $\omega = \omega_0$  gain = 0





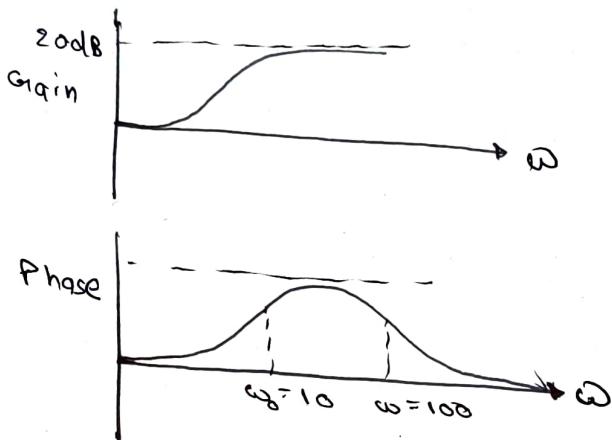
$$(1.4) \quad G_4(s) = \frac{0.1s + 1}{0.01s + 1}$$

(1) zero at  $s = -10$

Pole at  $s = -100$

(2)

$$\text{Gain} \Rightarrow \text{gain}\left(1 + \frac{s}{10}\right) = \text{gain}\left(1 + \frac{s}{100}\right)$$



(4) zero is at  $\omega = 10$

Pole at  $\omega = 100$

$\therefore$  Between zero and pole  $G_4(s)$  tends to add positive phase as seen from the plots.

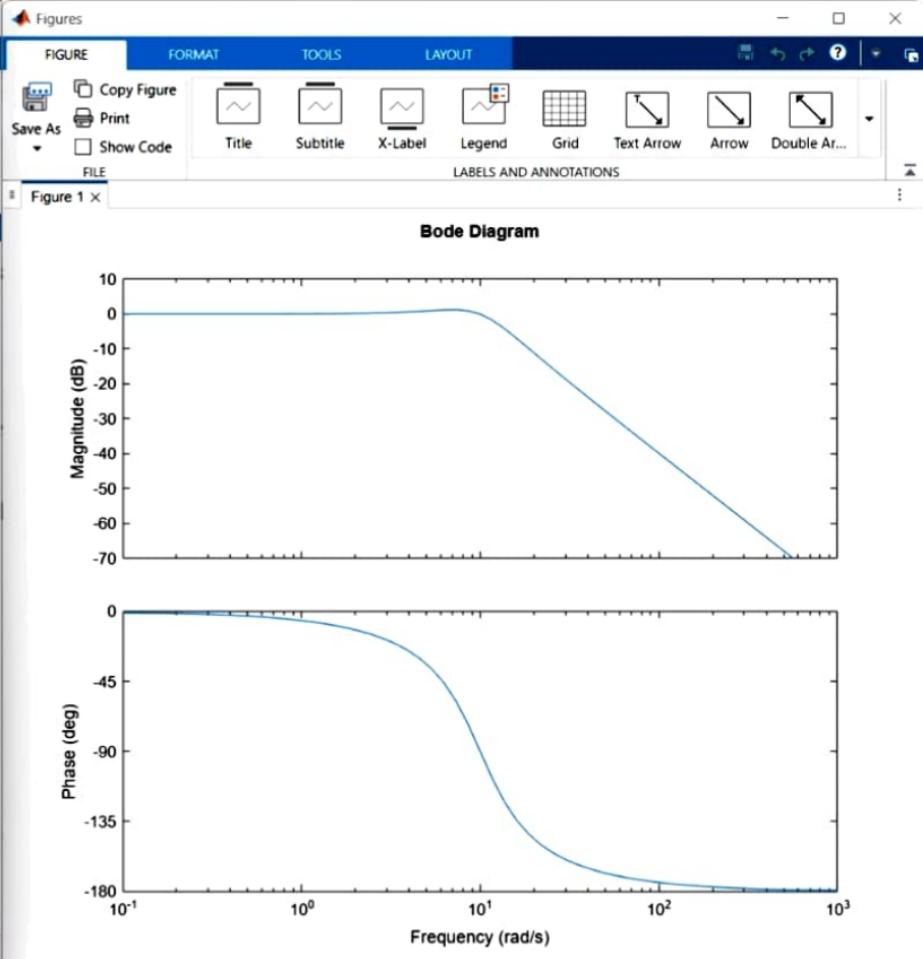
HOME PLOTS APPS

FILE VARIABLE

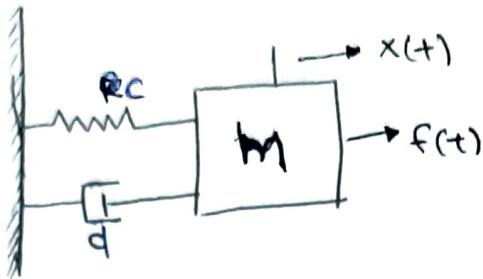
New Script New Live Script New Open Import Data Save Workspace Clean Data CODE SIMULINK ENVIRONMENT

RESOURCES COPilot Chat

```
>> G2=tf([1 -2], [1 10])
G2 =
  s - 2
  -----
  s + 10
Continuous-time transfer function.
Model Properties
>> bode(G2)
>>
>>
>> bode(G2)
>> G3=tf([100], [1 10 100])
G3 =
  100
  -----
  s^2 + 10 s + 100
Continuous-time transfer function.
Model Properties
>> bode(G3)
>> |
```



B.1)



The force to spring is directly proportional to  $m(t)$  while force of Damper is proportional to velocity of Mass  $m$ .

$$\Rightarrow f(t) - c\dot{m}(t) - \frac{d\dot{m}(t)}{dt} = m \frac{d^2m}{dt^2}$$

$$F(s) = cX(s) + ds(X(s)) + ms^2X(s)$$

$$F(s) = X(s)[c + ds + ms^2]$$

$$G(s) = \frac{X(s)}{F(s)}$$

$$G(s) = \frac{1}{[c + ds + ms^2]}$$

B.2)

$$G(s) = \frac{1}{[16 + 4s + s^2]}$$

$$\Rightarrow \text{Pole: } s = -2 \pm 2\sqrt{3}i$$

