PS 5

# Will Graham

# PD Controller

## Simulink Model:

*Note: Kp = 8.4049, Kd = 0.2699 (values from last homework solutions if we didn’t round*

### Low Frequency



### High Frequency



# PD Control with Feedback Compensation (Gravity, Friction, Centripetal)

## Simulink Model

*Note: Kp = 8.4049, Kd = 0.2699 (values from last homework solutions if we didn’t round*



## Embedded MATLAB Code (1 block)

### Low Frequency

 

### High Frequency

 

# PD Feedforward Control

## Simulink Model

*Note: Kp = 8.4049, Kd = 0.2699 (values from last homework solutions if we didn’t round*

