Control Systems

G V V Sharma*

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

*The author is with the Department of Electrical Engineering, Indian Institute of Technology, Hyderabad 502285 India e-mail: gadepall@iith.ac.in.

1 Mason's Gain Formula

2 Bode Plot

2.1 Introduction

2.2 Example

3 Second order System

3.1 Damping

3.2 Example

3.3 Example 2

3.1. A second-order real system has the following properties:
a) the damping ratio $\zeta = 0.5$ and undamped natural frequency $\omega_n = 10 rad/s$
b) the steady state value of the output, to a unit step input, is 1.02.
The transfer function of the system is
(A) $\frac{1.02}{s^2+5s+100}$ (B) $\frac{102}{s^2+10s+100}$
(C) $\frac{100}{s^2+10s+100}$ (D) $\frac{102}{s^2+5s+100}$
Solution: Characteristic equation of second order system is as follows

$$s^2 + 2\zeta\omega_n s + \omega_n^2 = 0 \tag{3.1.1}$$

Given

$$\zeta = 0.5 \tag{3.1.2}$$
$$\omega_n = 10 rad/s \tag{3.1.3}$$

The damping coefficient is between 0 and 1. Thus, the system is Underdamped.
and the Characteristic equation becomes

$$s^2 + 10s + 100 = 0 \tag{3.1.4}$$

Denominator of the Transfer Function is characteristic equation. Considering this, we can eliminate A and D options.

We know that output of the system in s domain is

$$ \tag{3.1.5} $$

$$C(s) = T(s)R(s) \tag{3.1.6}$$

$$R(s) = \frac{1}{s} \tag{3.1.7}$$

as it is unit step input.

Steady state output is given by

$$C(\infty) = \lim_{s \to 0} sC(s) \tag{3.1.8}$$

Given, steady state output is 1.02 and is the same for only option B

Therefore, transfer function of the system is

$$\frac{102}{s^2 + 10s + 100} \tag{3.1.9}$$

The step response of the transfer function

$$C(t) = \mathscr{L}^{-1}\left\{\frac{102}{s(s^2 + 10s + 100)}\right\} \tag{3.1.10}$$

Dividing into partial fractions

C(t)=$L^{-1}\left\{\frac{51}{50s}\right\} - \mathscr{L}^{-1}\left\{\frac{-51s-510}{50(s^2+10s+100)}\right\}$

C(t)=$\left(\frac{-51}{50}\right)L^{-1}\left\{\frac{s+5}{(s+5)^2+75}\right\}+\left(\frac{-51}{10}\right)\mathscr{L}^{-1}\left\{\frac{1}{(s+5)^2+75}\right\}+\mathscr{L}^{-1}\left\{\frac{51}{50s}\right\}$

Applying Inverse Laplace Transform, we get

$L^{-1}\left\{\frac{s+5}{(s+5)^2+75}\right\} = \exp^{-5t} cos(5\sqrt{3}t)$
$L^{-1}\left\{\frac{1}{(s+5)^2+75}\right\} = \frac{1}{5\sqrt{3}} \exp^{-5t} cos(5\sqrt{3}t)$

Therefore,

$$C(t) = -\frac{51}{50}\exp^{-5t} cos(5\sqrt{3}t) - \frac{17\sqrt{3}}{50}\exp^{-5t} sin(5\sqrt{3}t) + \frac{51}{50}u(t) \tag{3.1.11}$$

The following code is used to get the step response plot

```
stepresponseplot.py
```

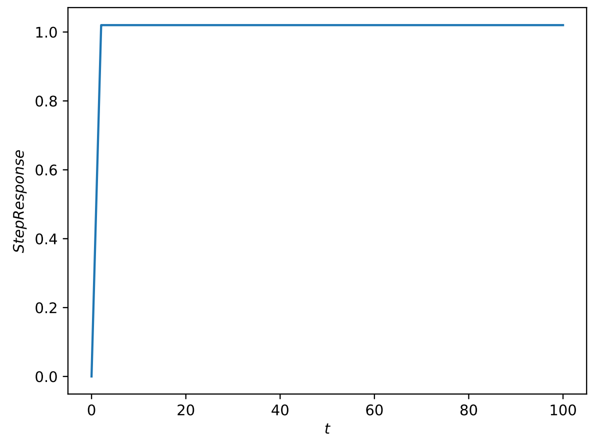

Fig. 3.1

4 Routh Hurwitz Criterion

4.1 Routh Array

4.2 Marginal Stability

4.3 Stability

5 State-Space Model

5.1 Controllability and Observabiity

5.2 Second Order System

6 Nyquist Plot

7 Compensators

8 Phase Margin

9 Gain Margin