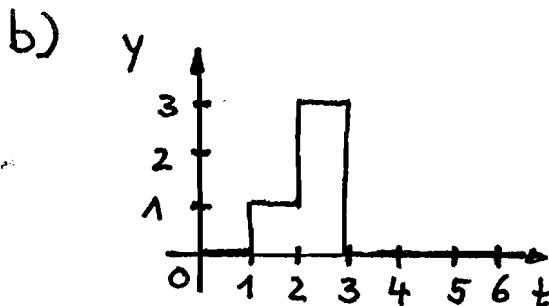


①

## Problem 1

- a) A reference value is a variable given from the environment to the controller, which gives the reference for the output as the value to be controlled.

The input variable is acting direct to the system and changes the output of the system. In open loop systems the input variable acts from the environment to the system, in closed loop systems the input is the output of the controller and the input of the system to be controlled.



- c) The poles denote those frequencies for which the transfer behavior probably get " $\infty$ " (resonance).

The zeros denote those frequencies, which cannot be transferred through the system.

c) For a double pole in the Bode diagram follows an amplitude change of  $-40 \text{ dB/dec.}$  and a phase change of  $-180^\circ$ .

d) PIDT<sub>1</sub> - system

ODE

$$T_1 \dot{y} + y = K \cdot \left( u + \frac{1}{T_I} \int u \, dt + T_D \dot{u} \right)$$

transfer function

$$G(s) = \frac{Y(s)}{U(s)} = \frac{K \cdot \left( 1 + \frac{1}{T_I s} + T_D s \right)}{T_1 s + 1}$$

e) Mathematical definition phase margin  $\bar{\Phi}_R$

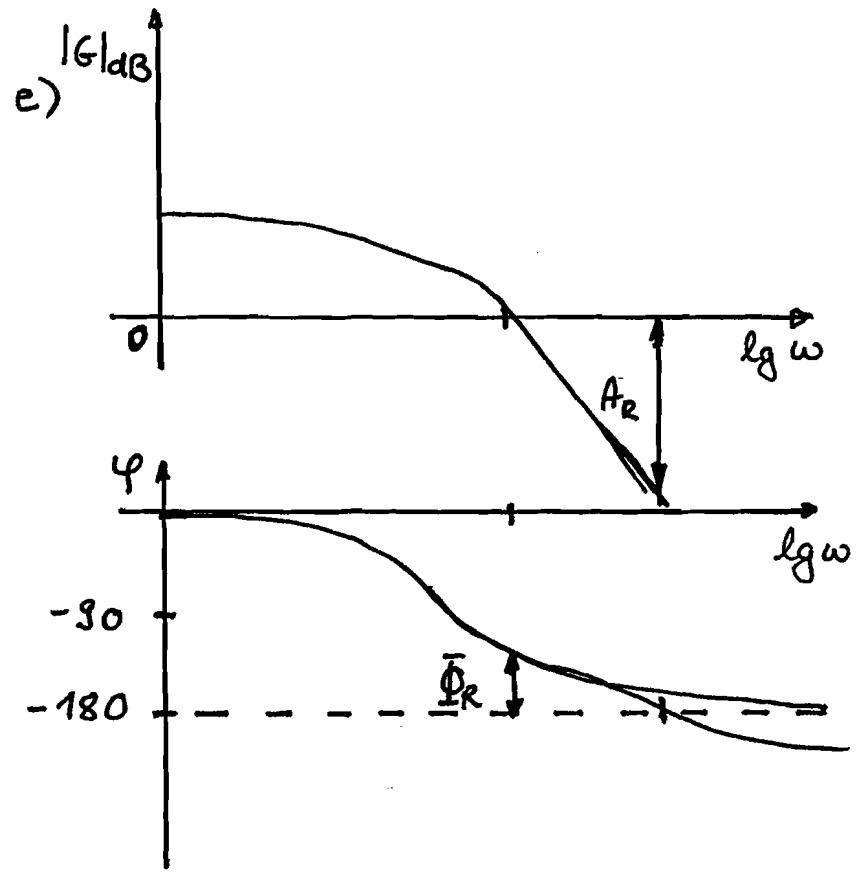
$$\bar{\Phi}_R = 180^\circ + \varphi_0(\omega_s)$$

Amplitude margin

$$A_R = \frac{1}{|G_0(j\omega_c)|}$$

The transfer function to be considered is the one of the open loop.

Problem 1



Problem 2

1

a) PT<sub>2</sub> transfer behavior

$$T_2 \ddot{y} + T_1 \dot{y} + y = K \cdot u$$

$$\mathcal{L}\{\delta(t)\} = 1$$

$$F(s) = G(s) \cdot \mathcal{L}\{\delta(t)\}$$

$$= G(s) \cdot 1$$

stationary final value

$$\lim_{t \rightarrow \infty} f(t) = \lim_{s \rightarrow 0} s \cdot G(s)$$

$$= \underline{\underline{0}}$$

b) Damping of a pair of eigenvalues

$$d = \cos \left( \arctan \frac{\text{Im}\{\lambda_i\}}{\text{Re}\{\lambda_i\}} \right)$$

$$\lambda_1 = -2 \pm 2j$$

$$\lambda_2 = -4 \pm 2j$$

$$d_{11} = \cos \left( \arctan \left( \frac{2}{-2} \right) \right)$$

$$= \frac{\sqrt{2}}{2}$$

$$d_{21} = \cos \left( \arctan \left( \frac{2}{-4} \right) \right)$$

$$= 0.894$$

$$d_{12} = \cos \left( \arctan \left( \frac{-2}{-2} \right) \right)$$

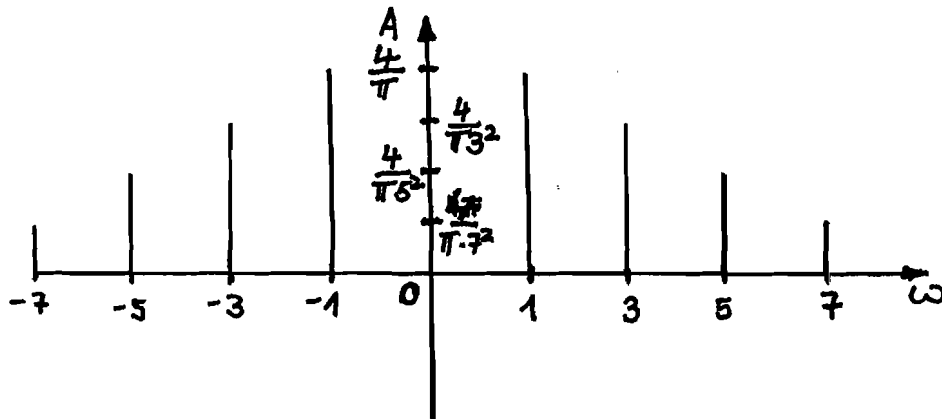
$$= \frac{\sqrt{2}}{2}$$

$$d_{22} = \cos \left( \arctan \left( \frac{-2}{-4} \right) \right)$$

$$= 0.894$$

The least damping is  $d_{11}/d_{12} = \frac{\sqrt{2}}{2}$ .

c)



d) 
$$f_a(s) = \frac{1}{T_1 T_2 s^3 + (T_1 + T_2) s^2 + s}$$

PT<sub>2</sub> - transfer function

$$G(s) = \frac{1}{T_1 T_2 s^2 + (T_1 + T_2) s + 1}$$

$$G(s) = \frac{Y(s)}{U(s)} \Rightarrow Y(s) = G(s) \cdot U(s)$$

$$\Rightarrow \frac{1}{T_1 T_2 s^3 + (T_1 + T_2) s^2 + s} = \frac{1}{T_1 T_2 s^2 + (T_1 + T_2) s + 1} \cdot \frac{1}{s}$$

$$U(s) = \frac{1}{s} \Rightarrow \underline{\underline{u(t) = 1(t)}}$$

e) PDT<sub>1</sub> - behavior

P-behavior

$$T_1 s y + y = k_1 (u + T_D s u) \quad y = k_2 \cdot u$$

$$G_1(s) = \frac{k_1 \cdot (1 + T_D s)}{1 + T_1 s}$$

e) Reference transfer function

$$G_w(s) = \frac{z_R z_s}{N_R N_s + z_R z_s} = \frac{G_o}{1 + G_o}$$

$$= \frac{K_2 K_1 (1 + T_D s)}{(T_1 s + 1) + K_2 K_1 (1 + T_D s)}$$

Disturbance transfer function

$$G_d(s) = \frac{N_R z_s}{N_R N_s + z_R z_s} = \frac{G_s}{1 + G_o}$$

$$= \frac{K_2 \cdot (T_1 s + 1)}{T_1 s + 1 + K_2 K_1 (1 + T_D s)}$$

Characteristic equation

$$T_1 s + 1 + K_1 K_2 + K_2 K_1 T_D s > 0$$

$$\Leftrightarrow s \cdot (T_1 + K_2 K_1 T_D) + 1 + K_1 K_2 > 0$$

$$\rightarrow T_1 + K_1 K_2 T_D > 0 \quad \wedge \quad 1 + K_1 K_2 > 0$$

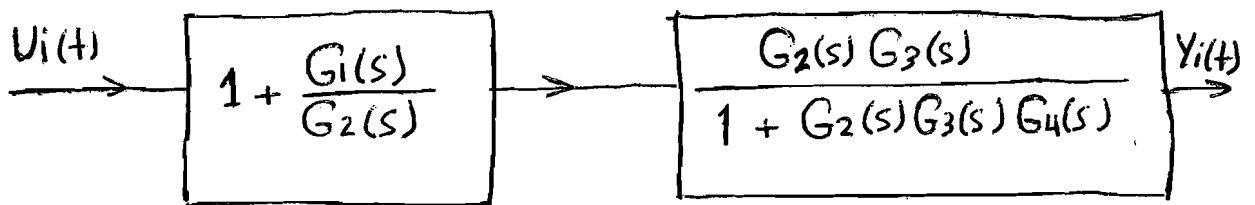
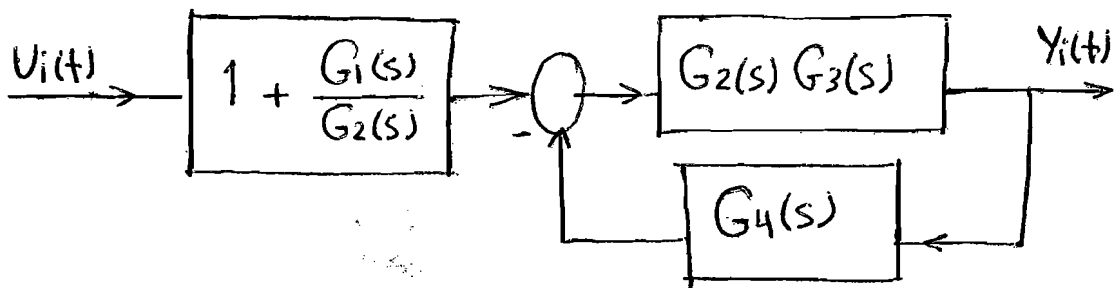
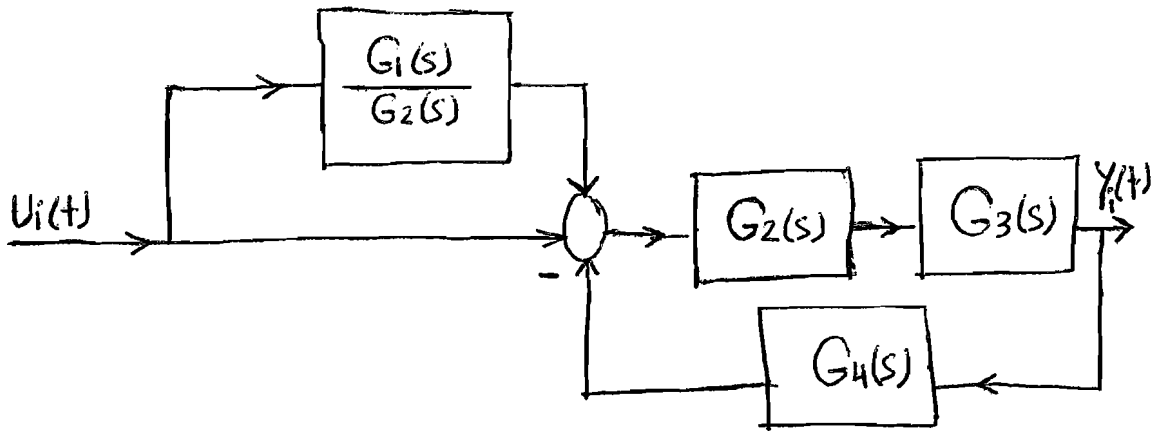
$$\Rightarrow K_2 > -\frac{T_1}{K_1 T_D} \quad \wedge \quad \underline{\underline{K_1 K_2 > -1}}$$

$$\Rightarrow \underline{\underline{K_1 K_2 > -\frac{T_1}{T_D}}}$$

# Problem 3:

a) Transfer function of The marked inner system

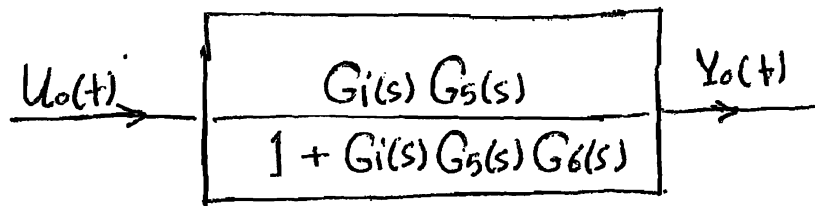
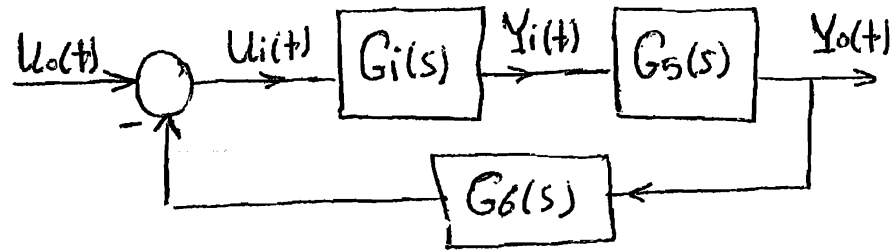
$$G_i(s) = Y_i(s)/U_i(s) :$$



$$G_i(s) = \frac{G_2(s)G_3(s) + \frac{G_1(s)G_2(s)G_3(s)}{G_2(s)}}{1 + G_2(s)G_3(s)G_4(s)}$$

$$G_i(s) = \frac{G_3(s)(G_2(s) + G_1(s))}{1 + G_2(s)G_3(s)G_4(s)} = \frac{Y_i(s)}{U_i(s)}$$

b) Transfer function of the whole system  $G_0(s) = \frac{Y_0(s)}{U_0(s)}$ :



$$G_0(s) = \frac{\left( \frac{G_3(s)(G_2(s) + G_1(s))}{1 + G_2(s)G_3(s)G_4(s)} \right) G_5(s)}{1 + \left( \frac{G_3(s)(G_2(s) + G_1(s))}{1 + G_2(s)G_3(s)G_4(s)} \right) G_5(s)G_6(s)} = \frac{Y_0(s)}{U_0(s)}$$

c) The state space model of the system

$$A = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ 0 & -6 & -5 \end{bmatrix}, \quad B = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

$$C = [1 \quad 6 \quad 2], \quad d = 0$$

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ 0 & -6 & -5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} u$$

$$Y = [1 \quad 6 \quad 2] \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + [0] u$$



d) The transfer function of the system:

$$2 \ddot{y}(t) - 4\dot{u}(t) - 12 \int \dot{u}(t) dt = -10\dot{y}(t) - 12y(t) + 2 \int u(t) dt + 12u(t)$$

$\frac{d}{dt} \rightarrow$

$$2 \dddot{y}(t) - 4\ddot{u}(t) - 12 \dot{u}(t) dt = -10\ddot{y}(t) - 12\dot{y}(t) + 2 \dot{u}(t) + 12\dot{u}(t)$$

$\Rightarrow$

$$\ddot{y}(t) + 5\dot{y}(t) + 6y(t) = 2\ddot{u}(t) + 6\dot{u}(t) + u(t)$$

$$\mathcal{L}[\ddot{y}(t) + 5\dot{y}(t) + 6y(t)] = \mathcal{L}[2\ddot{u}(t) + 6\dot{u}(t) + u(t)]$$

$$[s^3 + 5s^2 + 6s] Y(s) = [2s^2 + 6s + 1] U(s)$$

$$G(s) = \frac{Y(s)}{U(s)} = \frac{2s^2 + 6s + 1}{s^3 + 5s^2 + 6s}$$

e)  $G(s) = \frac{2s^2 + 6s + 1}{s^3 + 5s^2 + 6s}$

Characteristic equation:

$$s^3 + 5s^2 + 6s = 0 \Rightarrow s(s^2 + 5s + 6) = 0$$

$$s_1 = 0, s_2 = -2, s_3 = -3$$

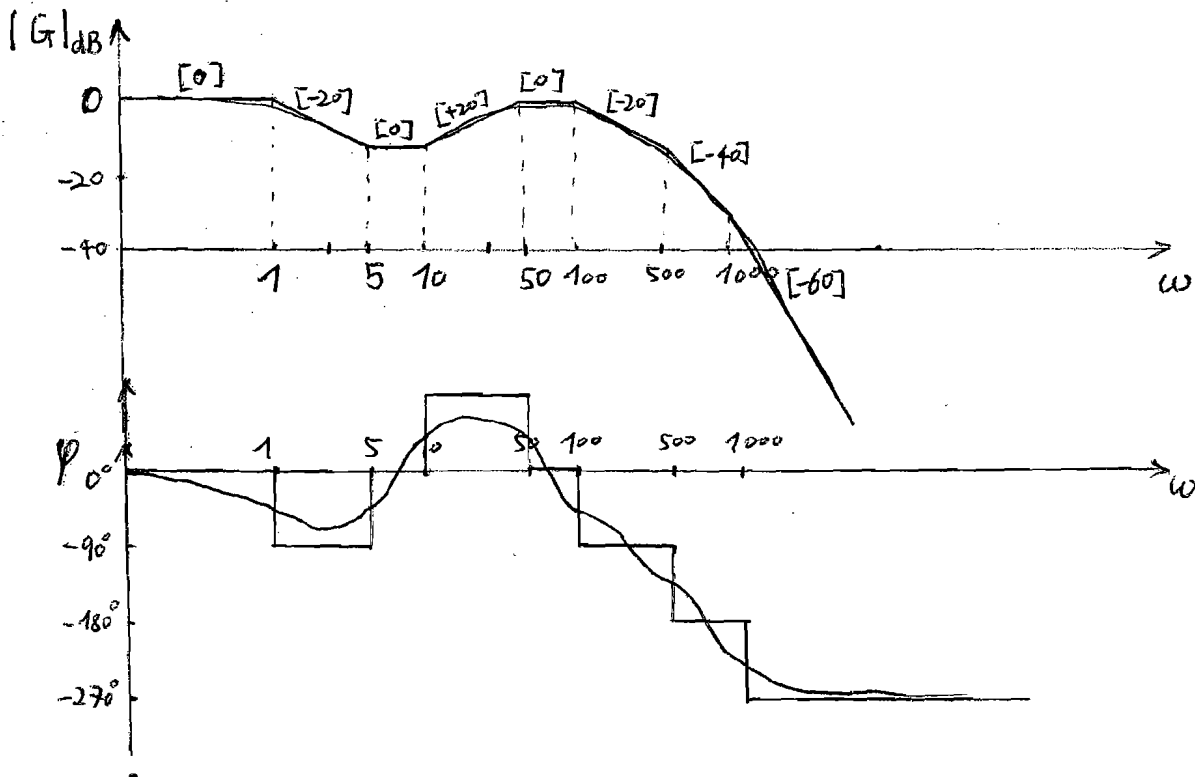
$\Rightarrow$  The system is boundary stable.

# Problem 5

a)  $G_{R1} = 1$  ;  $G_{R2} = K(1 + T_D s) = 800(1 + \frac{1}{800}s) = s + 800$

with  $G_{R1}$

$$\begin{aligned}
 G_{of}(s) &= G_s(s) G_{R1}(s) \\
 &= \frac{5 \times 10^7 (s+5)(s+10)}{(s+1)(s+50)(s+100)(s+500)(s+1000)} \\
 &= \frac{(\frac{s}{5} + 1)(\frac{s}{10} + 1)}{(s+1)(\frac{s}{50} + 1)(\frac{s}{100} + 1)(\frac{s}{500} + 1)(\frac{s}{1000} + 1)} \quad (*1)
 \end{aligned}$$

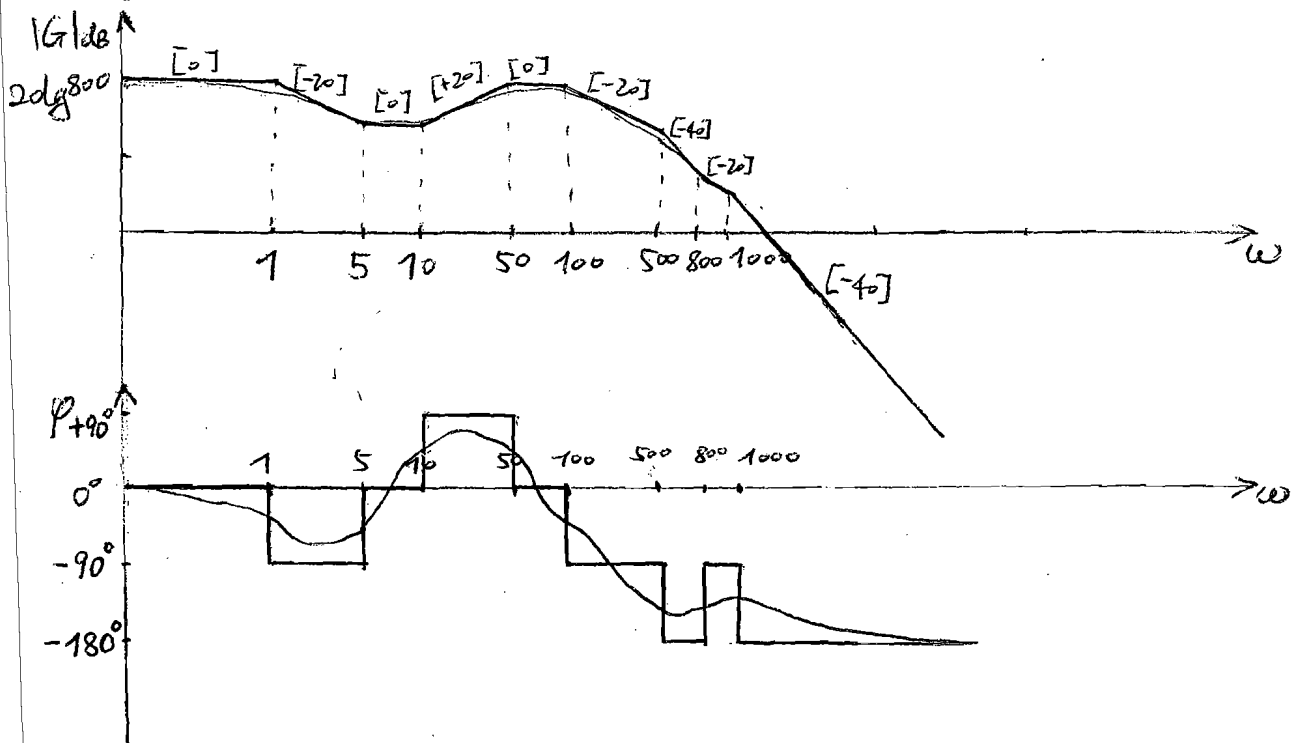


with  $G_{R2}$

$$\begin{aligned}
 G_{of}(s) &= G_s(s) G_{R2}(s) \\
 &= \frac{5 \times 10^7 (s+5)(s+10)(s+800)}{(s+1)(s+50)(s+100)(s+500)(s+1000)} \\
 &= \frac{800(\frac{s}{5} + 1)(\frac{s}{10} + 1)(\frac{s}{800} + 1)}{(s+1)(\frac{s}{50} + 1)(\frac{s}{100} + 1)(\frac{s}{500} + 1)(\frac{s}{1000} + 1)} \quad (*2)
 \end{aligned}$$

## Problem 5

a) with  $G_{R2}$



Bode-diagram (see also in the end of the solution).

b) Phase margin ( $G_{01}$ )

gain of  $G_{01}(s)$ :  $K_{G_{01}} = 1$  (from Eq. (\*.1))

$$|G_{01}(0)| = 0 \text{ dB} \Rightarrow \angle G_{01}(0) = 0^\circ$$

$$\varphi_{R, G_{01}} = 0^\circ - (-180^\circ) = 180^\circ$$

Amplitude margin ( $G_{02}$ )

$\varphi_{G_{02}}$  doesn't cross  $-180^\circ$  for  $\omega: 0 \rightarrow \infty$

$$\Rightarrow A_{R, G_{02}} = \infty$$

## Problem 5

c) Yes.

- the open loops are stable, because they have same stable poles  $s_1 = -1$   $s_2 = -50$   $s_3 = -100$   $s_4 = -500$   $s_5 = -1000$ .

- no poles at the origin.

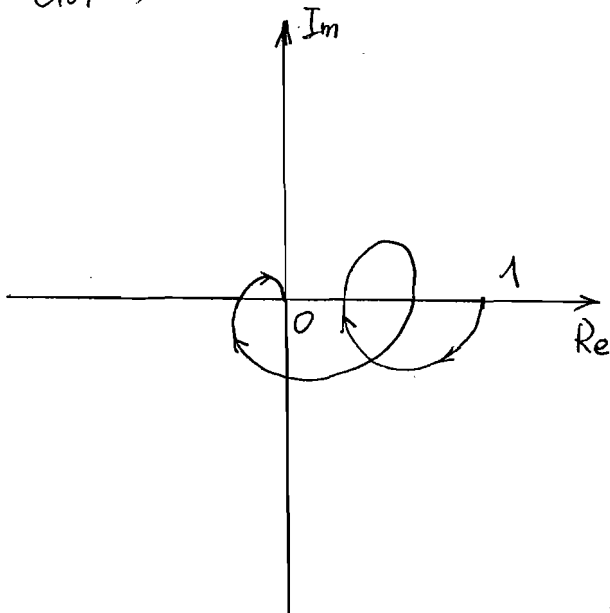
- negative feedback

d) The close-loop with  $G_p(s)$  and  $G_{r1}(s)$  is stable, because the phase margin  $\gamma_{R, G_{01}} > 0^\circ$ .

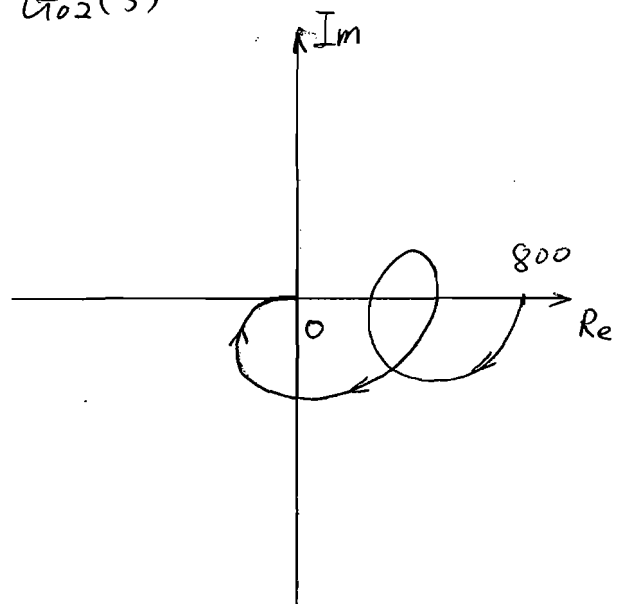
The close-loop with  $G_p(s)$  and  $G_{r2}(s)$  is stable, because the amplitude margin  $A_{R, G_{02}} > 1$ .

e) polar plot

$G_{01}(s)$



$G_{02}(s)$



( see next page )

Zeros:

a)  $s_{01} = -3$

$s_{02} = 1$

$s_{03} = 2$

poles:

$s_1 = 0$

$s_2 = -0,5$

$s_3 = -2$

$s_4 = -4$

$$s_{5/6} = -1 \pm \sqrt{-1}$$

$$= -1 \pm i$$

The plant is boundary stable  $\rightarrow s_1 = 0$

b)  $p_1 = 0$  :  $D_1 = 1$  ,  $\omega_{01} = 0 \text{ s}^{-1}$

$p_2 = -0,5$  :  $D_2 = 1$  ,  $\omega_{02} = 0,5 \text{ s}^{-1}$

$p_3 = -2$  :  $D_3 = 1$  ,  $\omega_{03} = 2 \text{ s}^{-1}$

$p_4 = -3$  :  $D_4 = 1$  ,  $\omega_{04} = 3 \text{ s}^{-1}$

$p_{5/6} = -1 \pm i$  :  $D_{5/6} = \cos \delta = \frac{\text{Re}\{\lambda\}}{\sqrt{\text{Re}\{\lambda\}^2 + \text{Im}\{\lambda\}^2}} = \frac{1}{\sqrt{2}}$

$\omega_{5/6} = \sqrt{\text{Re}\{\lambda\}^2 + \text{Im}\{\lambda\}^2} = \sqrt{2}$

6)

c)  $y(t) = k_p \cdot u(t)$       P

$$\frac{1}{2} \ddot{y}(t) - \frac{3}{2} \dot{y}(t) + y(t) = k_D \dot{u}(t) \quad \text{D-T}_2$$

$$G_p(s) = k_p \quad \Rightarrow \quad \begin{array}{l} \text{no poles} \\ \text{no zeros} \end{array}$$

$$0,5 \cdot y(s) \cdot s^2 - 1,5 y(s) \cdot s + y(s) = k_D \cdot u(s) \cdot s$$

$$G_D(s) = \frac{y(s)}{u(s)} = \frac{2k_D \cdot s}{s^2 - 3s + 2}$$

$$s_{1/2} = 1,5 \pm \sqrt{0,25}$$

$$= 1,5 \pm 0,5$$

$$s_1 = 1, \quad s_2 = 2 \quad \Rightarrow \quad \text{poles}$$

$$s_{0,1} = 0 \quad \Rightarrow \quad \text{zero}$$

$$G_D(s) = \frac{2k_D \cdot s}{(s-1)(s-2)}$$

$$d) G_{o1}(s) = G_s(s) \cdot G_p(s)$$

$$= \frac{K_p (s+3)(s-1)(s-2)}{s(s+0,5)(s+2)(s+4)(s^2+2s+2)}$$

$$s_{o1} = -3 \quad s_1 = 0$$

$$s_{o2} = 1 \quad s_2 = -0,5$$

$$s_{o3} = 2 \quad s_3 = -2$$

$$s_4 = -1 \pm j$$

$$s_{s/6} = -1 \pm j$$

$$G_{o2}(s) = G_s(s) \cdot G_D(s)$$

$$= \frac{2 \cdot K_D (s+3)}{(s+0,5)(s+2)(s+4)(s^2+2s+2)}$$

$$s_{o1} = -3 \quad s_1 = -0,5$$

$$s_2 = -2$$

$$s_3 = -4$$

$$s_{4,5} = -1 \pm j$$

e) System 1: Number of Poles  $n = 6$   
 Number of zeros  $m = 3$   
 $\rightarrow 6$  separate branches  
 $n - m = 3$  branches go to infinity

System 2: Number of poles  $n = 5$   
 Number of zeros  $m = 1$   
 $\rightarrow 5$  separate branches  
 $n - m = 4$  branches go to infinity

f) System 1:

$$\hat{\sigma}_{w_1} = \frac{\sum_{i=1}^n s_i - \sum_{i=1}^m s_{0i}}{n-m}$$

$$= \frac{(0 - 0,5 - 2 - 4 - 1 - 1 - 1 + i) - (-3 + 1 + 2)}{3}$$

$$= \frac{-8,5}{3}$$

$$\varphi_{hi} = \frac{180^\circ + i \cdot 360}{n-m} \quad ; \quad i = 0, 1 \dots (n-m-1)$$

$$\Rightarrow \varphi_{h1} = 60^\circ$$

$$\varphi_{h2} = 180^\circ$$

$$\varphi_{h3} = 300^\circ$$

System 2:  $\hat{\sigma}_{w_2} = \frac{(-0,5 - 2 - 4 - 1 - 1 - 1 + i) - (-3)}{4}$

$$= \frac{-8,5 + 3}{4}$$

$$\Rightarrow \varphi_{21} = 45^\circ$$

$$\varphi_{22} = 135^\circ$$

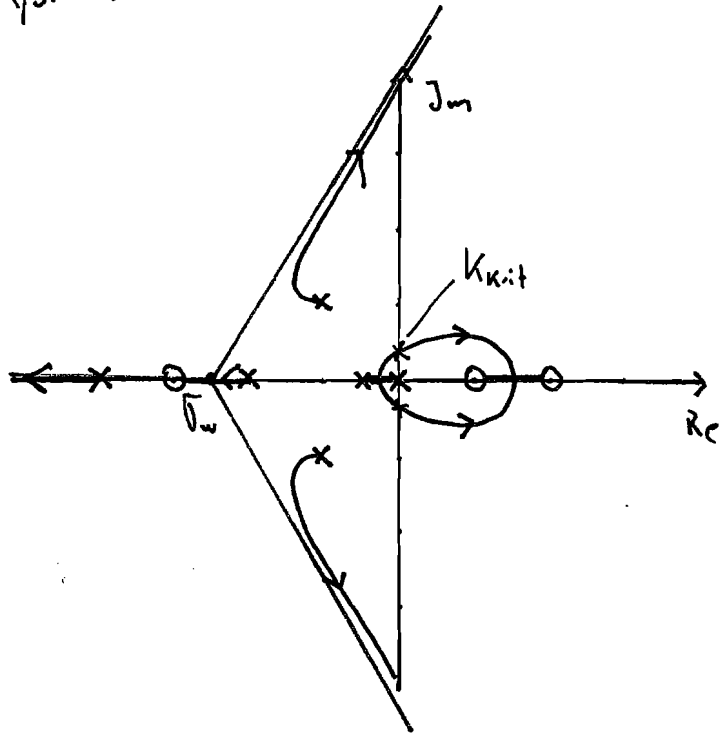
$$\varphi_{23} = 225^\circ$$

$$\varphi_{24} = 315^\circ$$

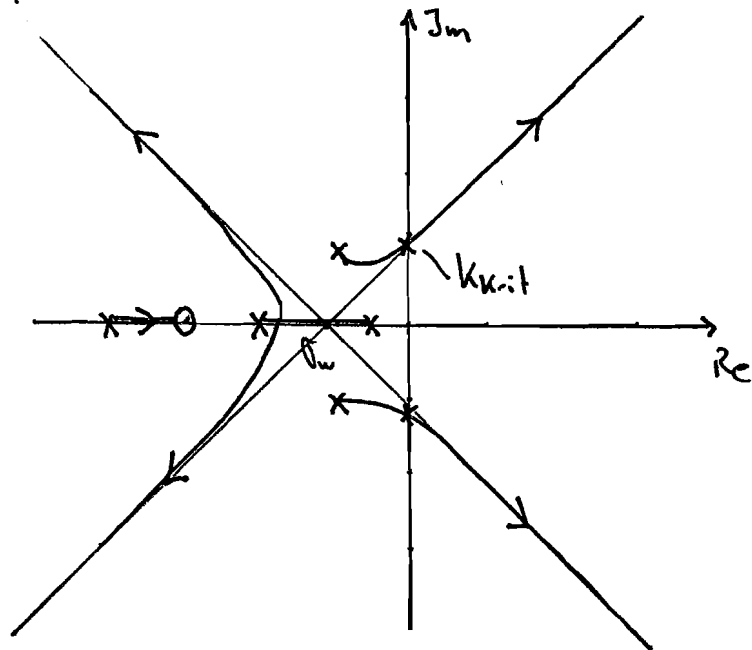


9)

System 1:



System 2:



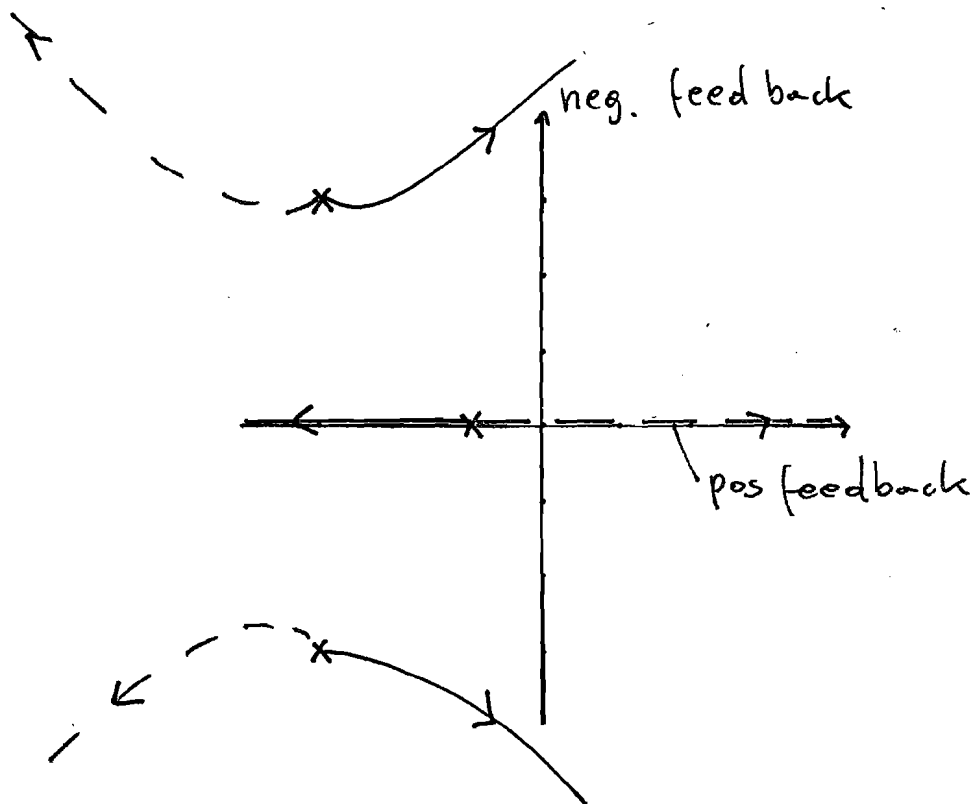
$$h) G_s(s) = \frac{1}{(s+1)(s^2+6s+18)}$$

$$\Rightarrow k_s = \frac{1}{18}$$

$$s_1 = -1$$

$$s_{2,3} = -3 \pm \sqrt{9-18}$$
$$= -3 \pm 3i$$

no zeros



i)

$$G_o = k_p \cdot \frac{1}{(s+1)(s^2+6s+18)} = -1$$

$$\Leftrightarrow k + s^3 + 6s^2 + 18s + s^2 + 6s + 18 = 0$$

$$\Leftrightarrow k + s^3 + 7s^2 + 24s + 18 = 0$$

$$H = \begin{pmatrix} 7 & 18+k & 0 \\ 1 & 24 & 0 \\ 0 & 7 & 18+k \end{pmatrix}$$

$$a_i > 0 \Rightarrow k > -18$$

$$|H_1| = 7 > 0 \quad \checkmark$$

$$|H_2| = 7 \cdot 24 - 18 - k > 0$$

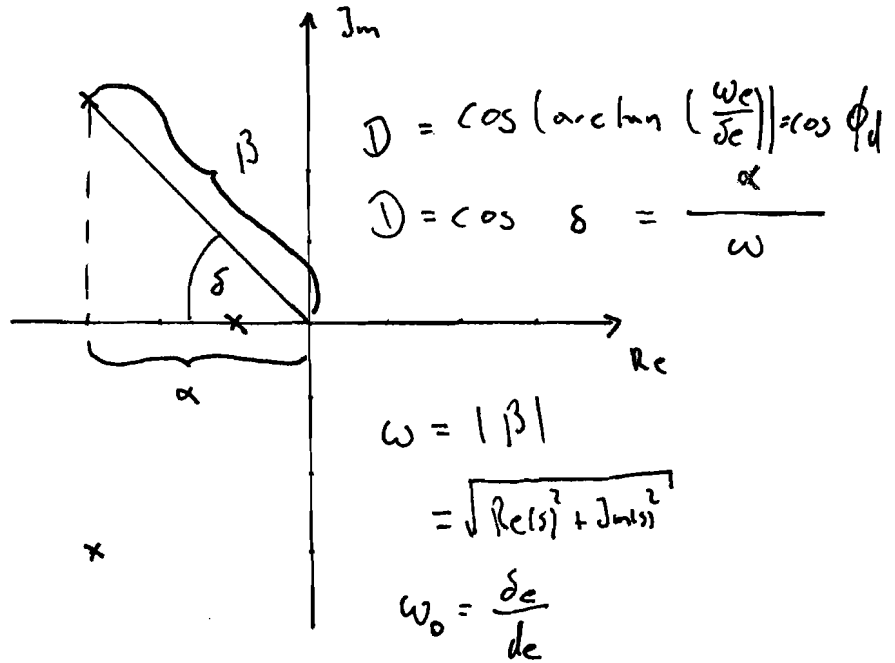
$$150 > k$$

$$|H_3| = |H_2| \cdot a_0 = 150 \cdot (18+k) > 0$$

$$\Rightarrow k > -18$$

$$\Rightarrow -18 < k < 150$$

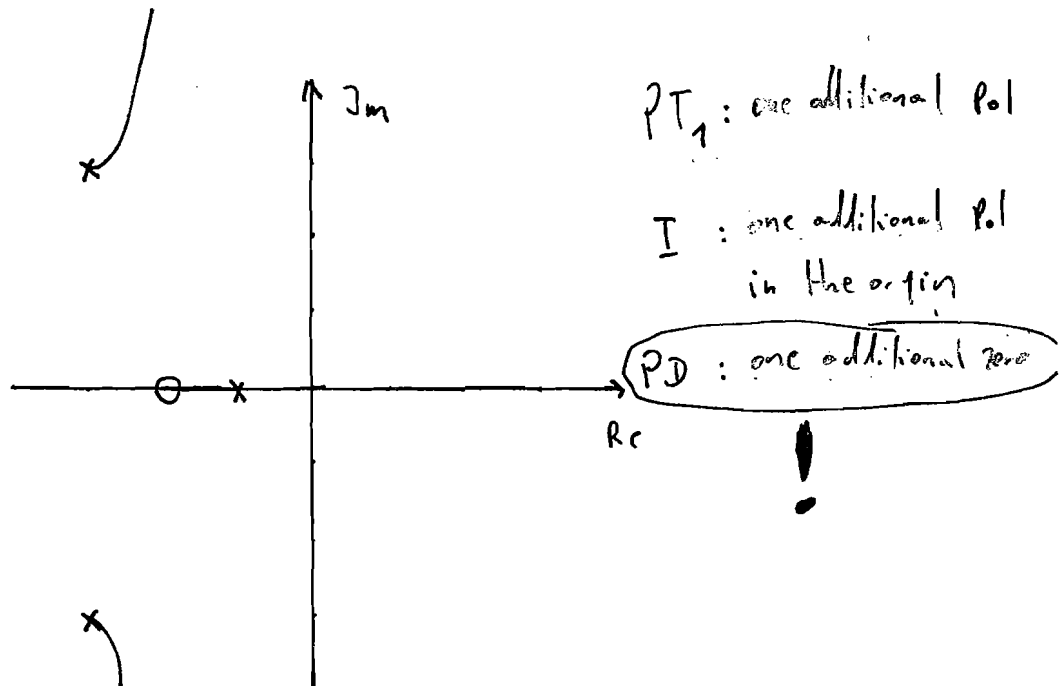
j)



k)

$$\begin{aligned}
 k &= |(-4+1)((-4)^2 + 6(-4) + 18)| \\
 &= |(-3)(16 - 24 + 18)| \\
 &= |-30| = \underline{\underline{30}}
 \end{aligned}$$

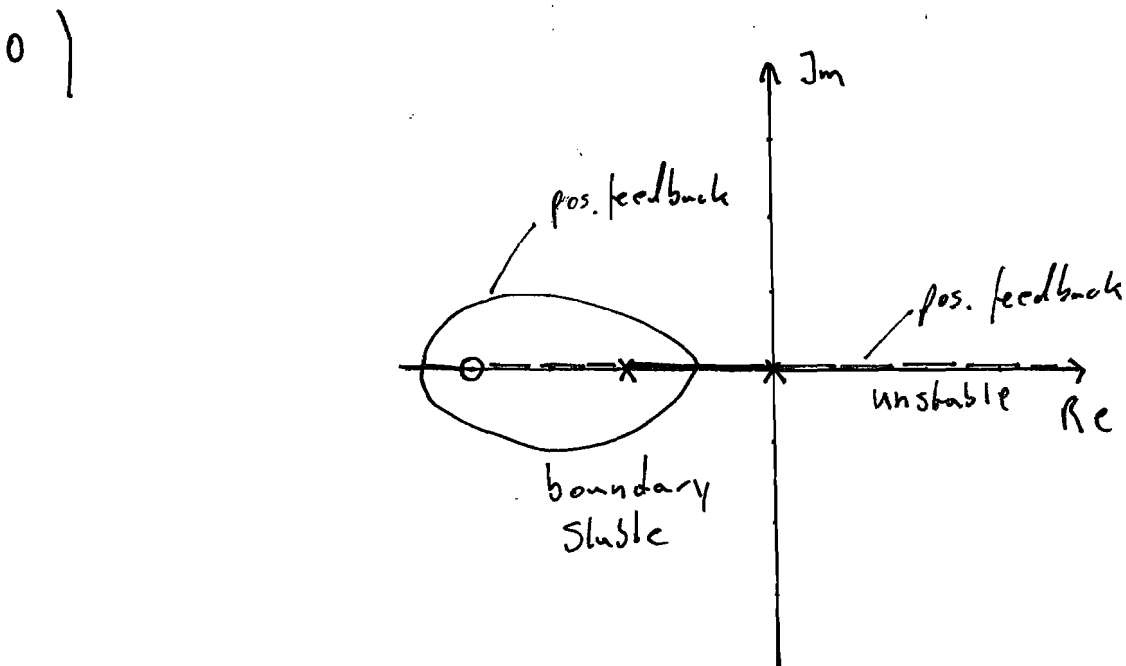
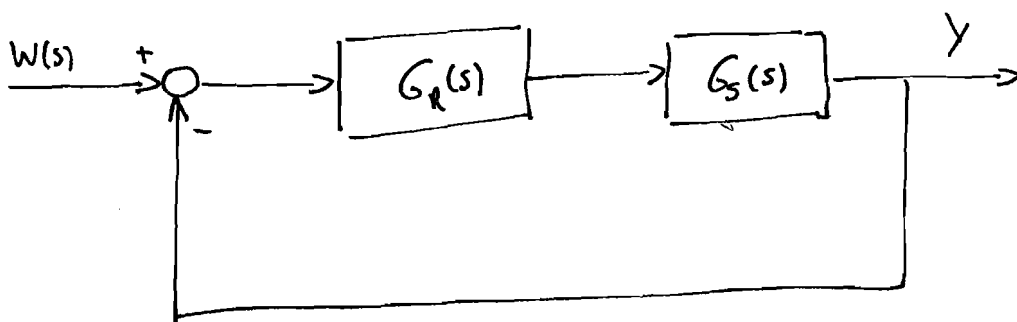
l)



$$m) \quad G_S(s) = \frac{1}{T_I s (1 + s T_1)} = \frac{2}{s(1 + s \cdot \frac{1}{3})}$$

$$G_R(s) = k (1 + s T_D) = 3(1 + s \cdot \frac{1}{4})$$

$$k_0 = k_I \cdot k = 2 \cdot 3 = 6$$



$$) \quad \frac{1}{s} + \frac{1}{s+3} = \frac{1}{s+4}$$

$$\Leftrightarrow (s+4)(s+3) + s(s+4) = s(s+3)$$

$$s^2 + 7s + 12 + s^2 + 4s = s^2 + 3s$$

$$s^2 + 8s + 12 = 0$$

$$s_{1,2} \pm = -4 \pm \sqrt{16 - 12}$$

$$s_1 = -2 \quad \wedge \quad s_2 = -6$$

p) No, the system has no complex poles.