

CMPE-242

Applied Feedback Control

Gabriel Hugh Elkaim



Gabriel Hugh Elkaim

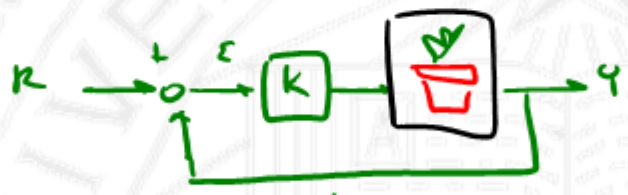
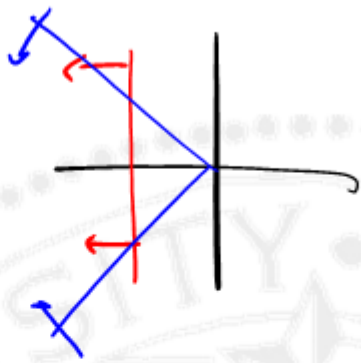


CMPE 242 – Applied Feedback Control

Office Hours

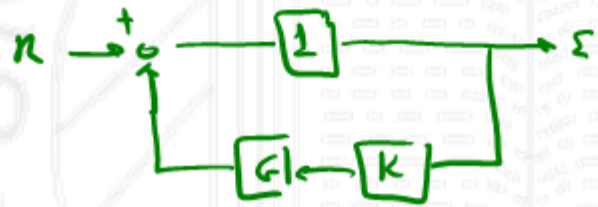
20/Jan/2017

$T_s \rightarrow \frac{d.c}{j\omega_n}$
 $M_p \rightarrow e^{-\pi\zeta/\sqrt{1-\zeta^2}}$
 r_{ss}
 e_{ss}



$$\frac{Y}{R} = \frac{GK}{1+GK}$$

$$\frac{E}{R} = \frac{1}{1+GK}$$



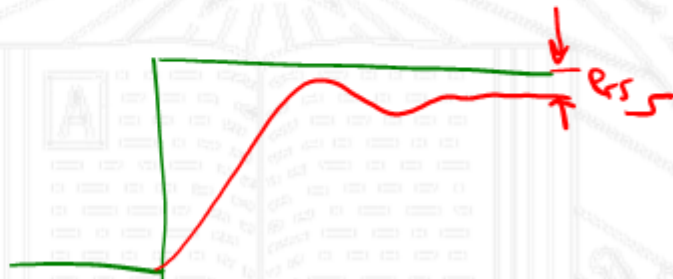
$$e_{ss} \checkmark \Rightarrow \text{FVT} \quad e_{ss}(\infty) = \lim_{s \rightarrow 0} s E(s) = \lim_{s \rightarrow 0} \cancel{s} \frac{E(s)}{\cancel{s}} \cdot \frac{1}{\uparrow} \quad R(s)$$

$$\frac{E}{R} = \frac{1}{1+GK} \quad R = \checkmark = \frac{1}{s}$$

$$e_{ss} \checkmark = \lim_{s \rightarrow 0} \frac{1}{1+GK} < \underline{0.1}$$

e_{cs} ✓

$$R(s) = \frac{1}{s^2}$$



$y \rightarrow \infty$ as $t \rightarrow \infty$
 $\varepsilon \neq \infty$ as $t \rightarrow \infty$



$$FVT \rightarrow y(\infty) = \lim_{s \rightarrow 0} s Y(s)$$

$$\varepsilon(\infty) \rightarrow \left(\frac{\varepsilon(1)}{r(1)} \right) \cdot \frac{r(1)}{s} \cdot s$$

\uparrow
 $\frac{1}{s^2}$



```
sys = tf([1 1],[1 3 5]);
```

```
rlocus(sys);
```

```
k = rlocfind(sys);
```

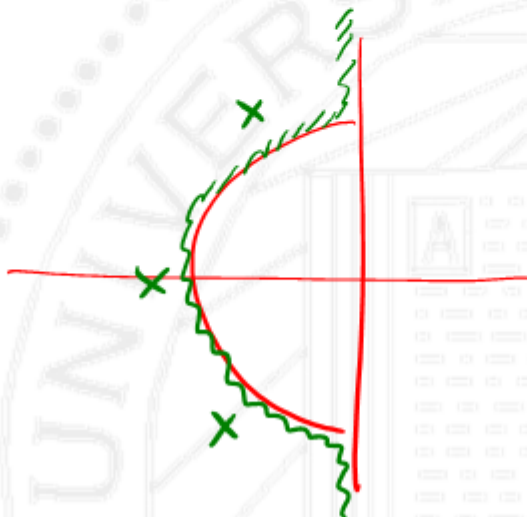
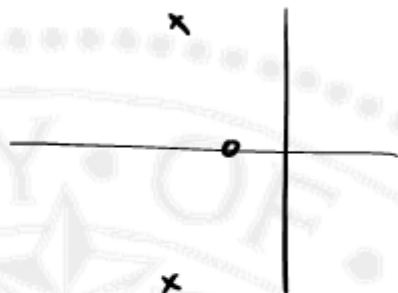
```
sysCL = feedback(k*sys,1);
```

```
step(sysCL);
```

```
sgrid(z,wn);
```

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

1 1
1 3 5



$$G(s) = \frac{s+3}{s^3(s+4)}$$

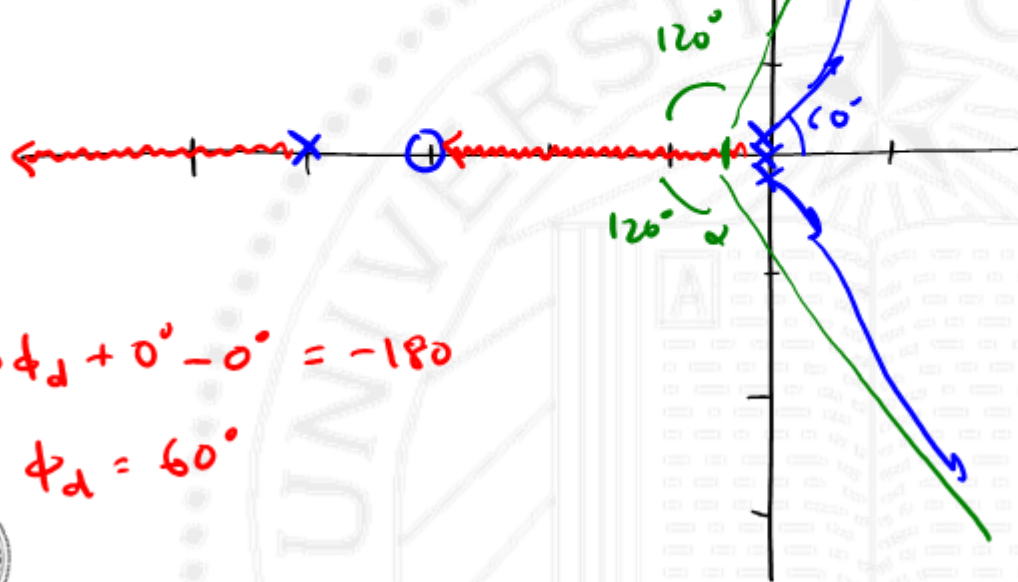
(1) $x \rightarrow 0$

(2) Real Axis

(3) Asymptotes

$$\alpha = \frac{\sum P_i - \sum Z_i}{n-m} = \frac{-1}{3}$$

(a) ϕ_d



$$-3\phi_d + 0^\circ - 0^\circ = -180^\circ$$

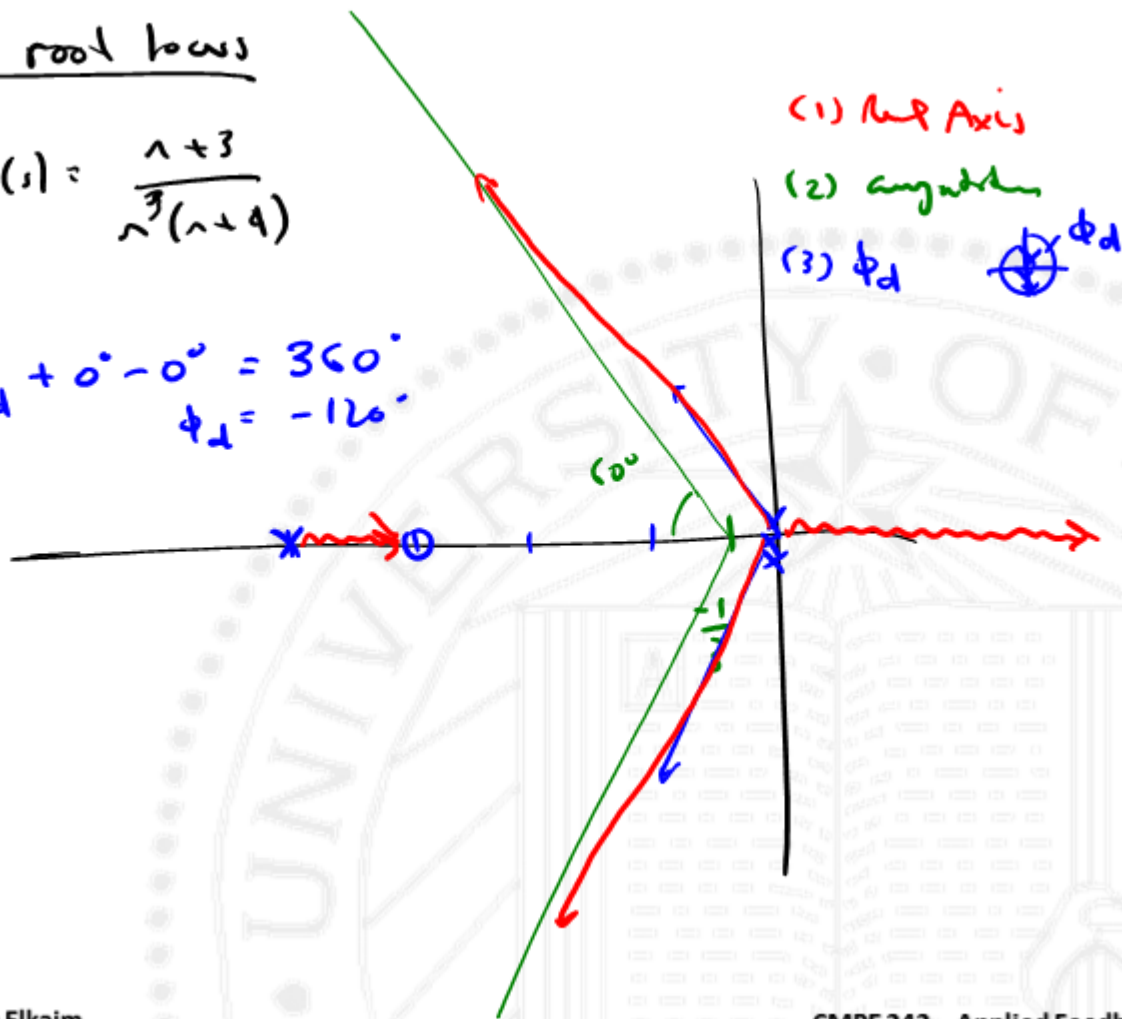
$$\phi_d = 60^\circ$$

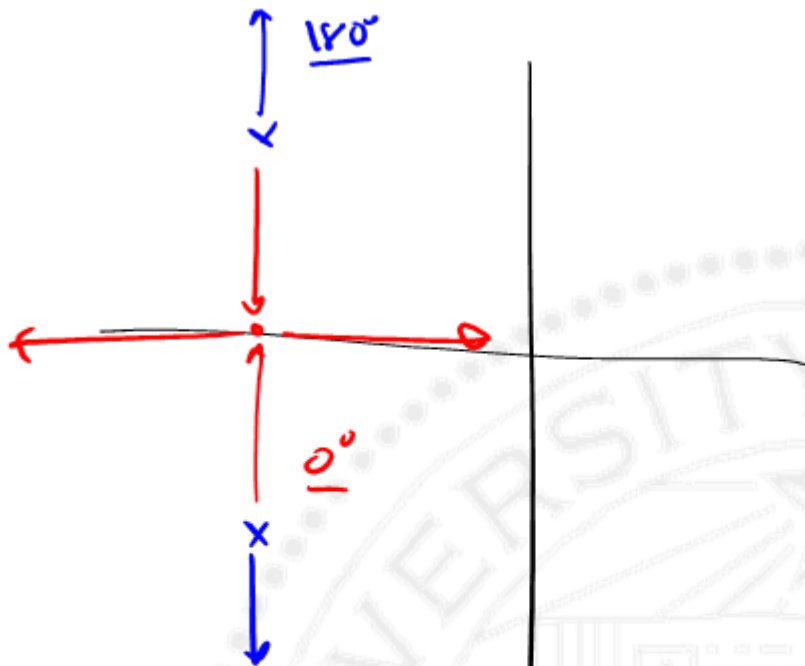


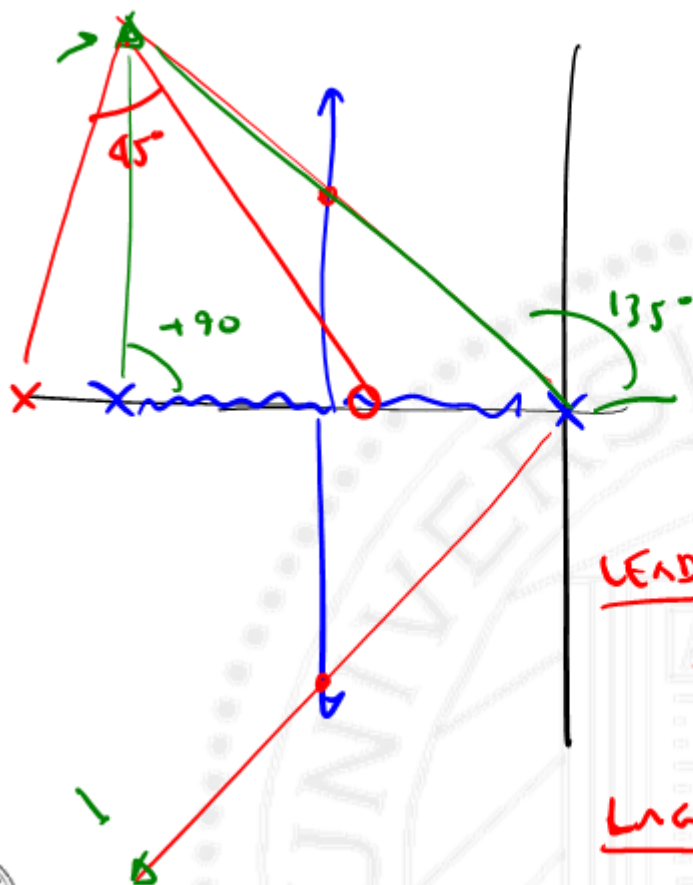
0° root locus

$$G(s) = \frac{s+3}{s^3(s+4)}$$

$$\begin{aligned} -3\phi_d + 0^\circ - 0^\circ &= 360^\circ \\ \phi_d &= -120^\circ \end{aligned}$$

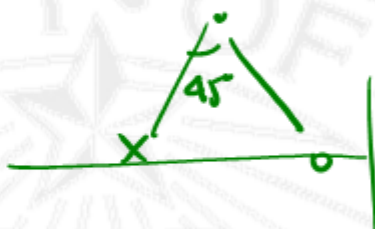






$$\phi_D = -90 - 135 = -225 \text{ degrees}$$

$$\frac{225}{-180} = 45^\circ$$



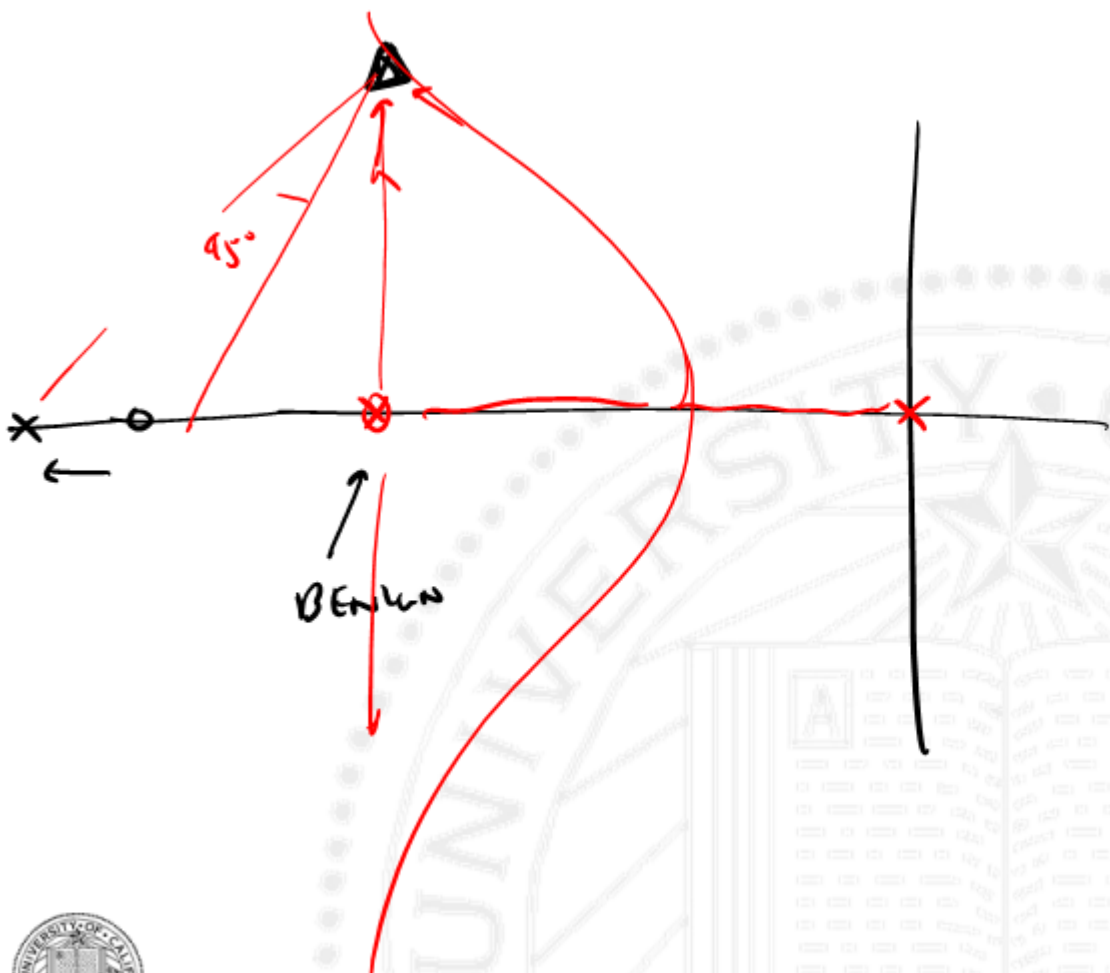
LEAD

zero closer to origin +
adds phase

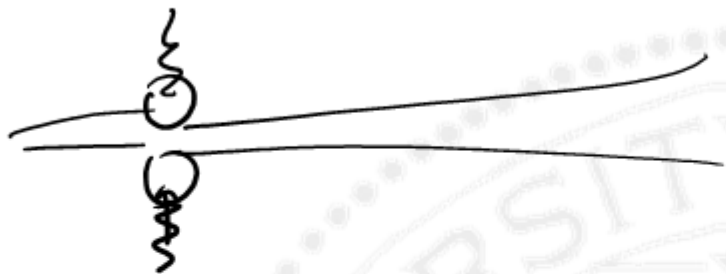
LAG

pole closer to the origin
subtracts phase.





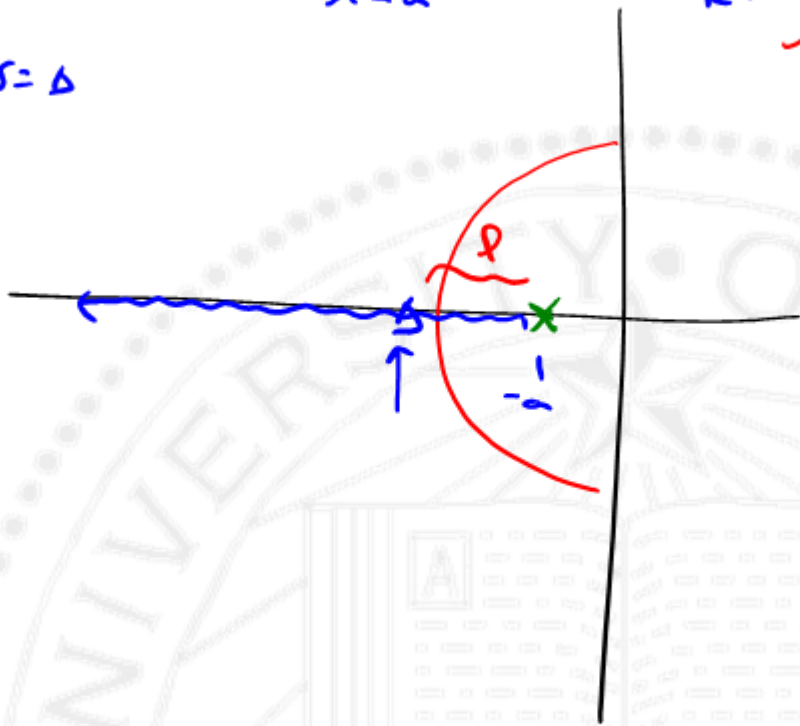
PLANT → Paper mills / Process control.

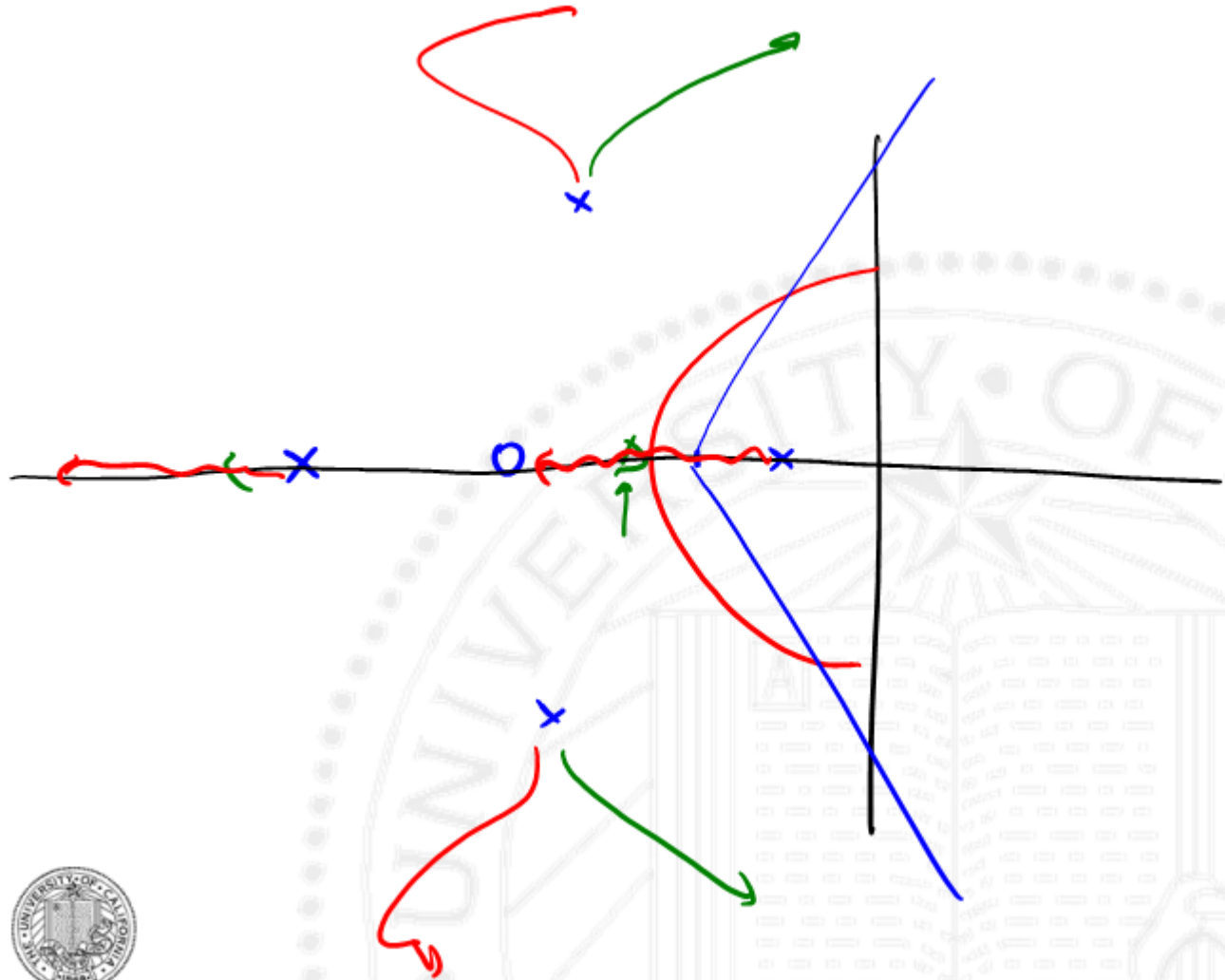


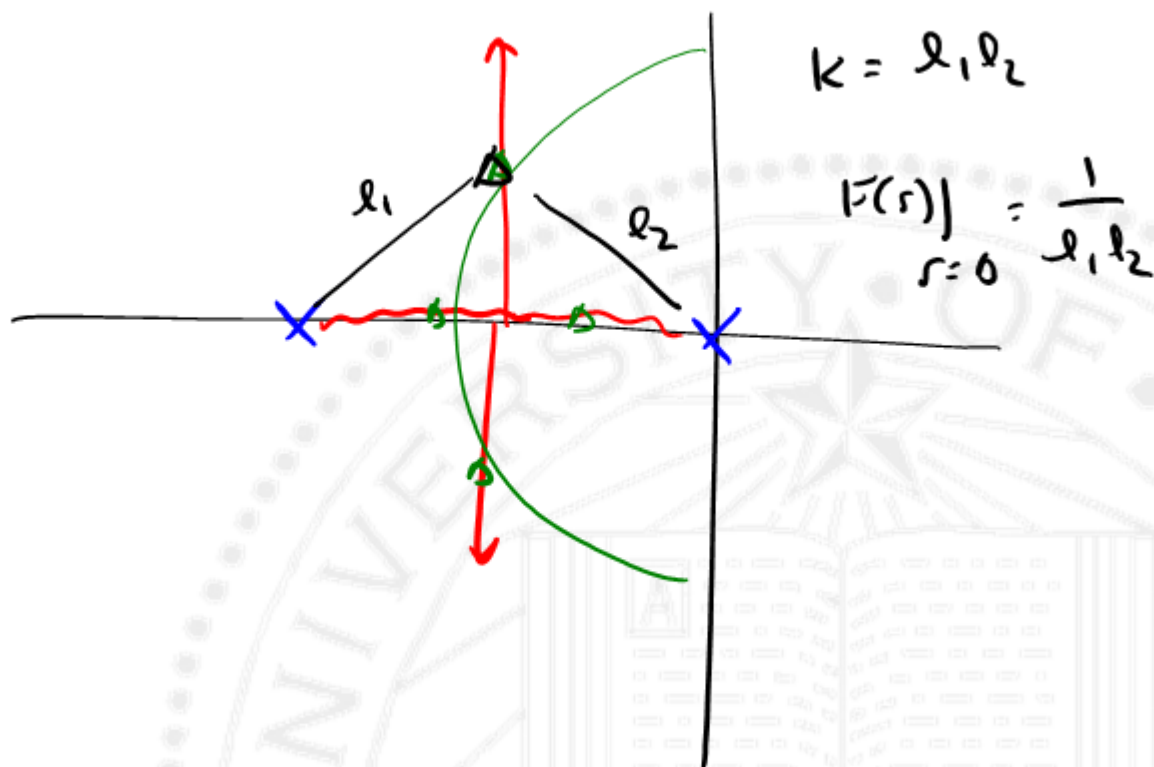
$$K = \frac{1}{|F(s)|_{s=\Delta}}$$

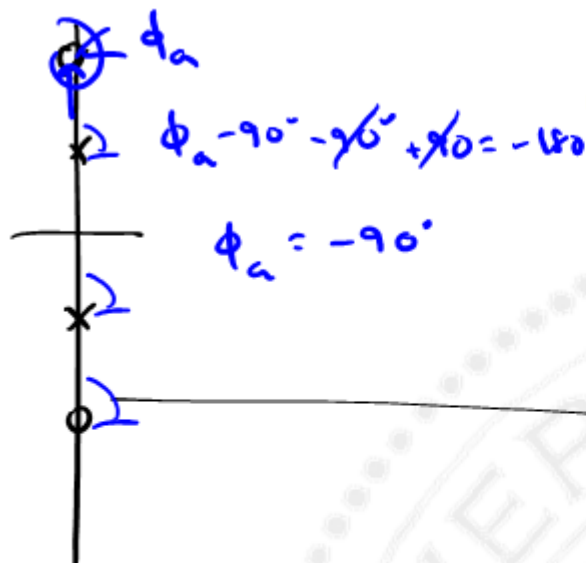
$$F(s) = \frac{1}{s+a}$$

$$K = \frac{1}{a}$$









- (1) $x \rightarrow 0$
- (2) Real Axis - walking
- (3) $\alpha = \text{not defined}$



- (4) ϕ_d
- -90
- $-\phi_d + 2 \cdot 90^\circ - 90^\circ + 90^\circ = -180^\circ$

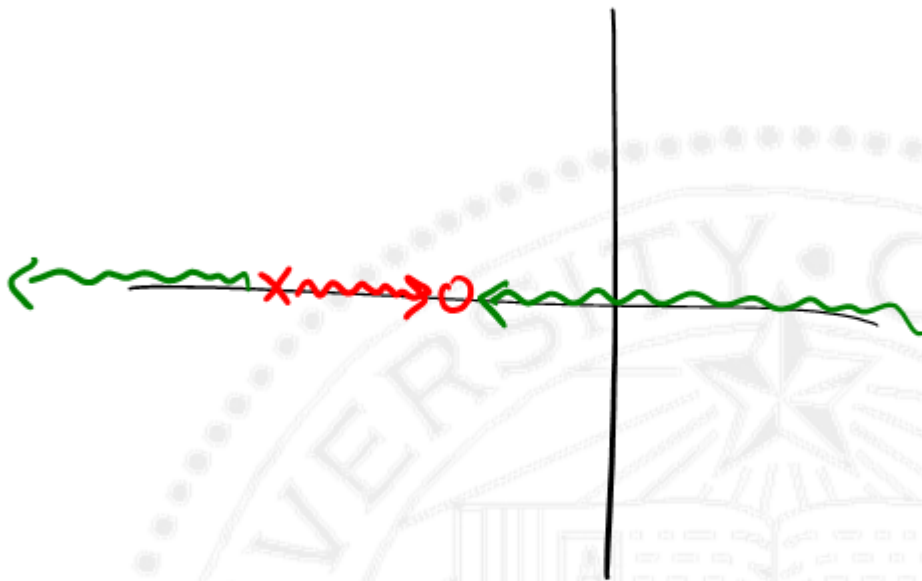
$-\phi_d - 90 - 90 + 90 = 0$
 $-\phi_d = 90$
 $\phi_d = -90$

$-\phi_d = -90$
 $\phi_d = 90^\circ$



$\phi_a = 90 - 90 + 90 = 0 \rightarrow \phi_a =$







Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control



Gabriel Hugh Elkaim



CMPE 242 – Applied Feedback Control