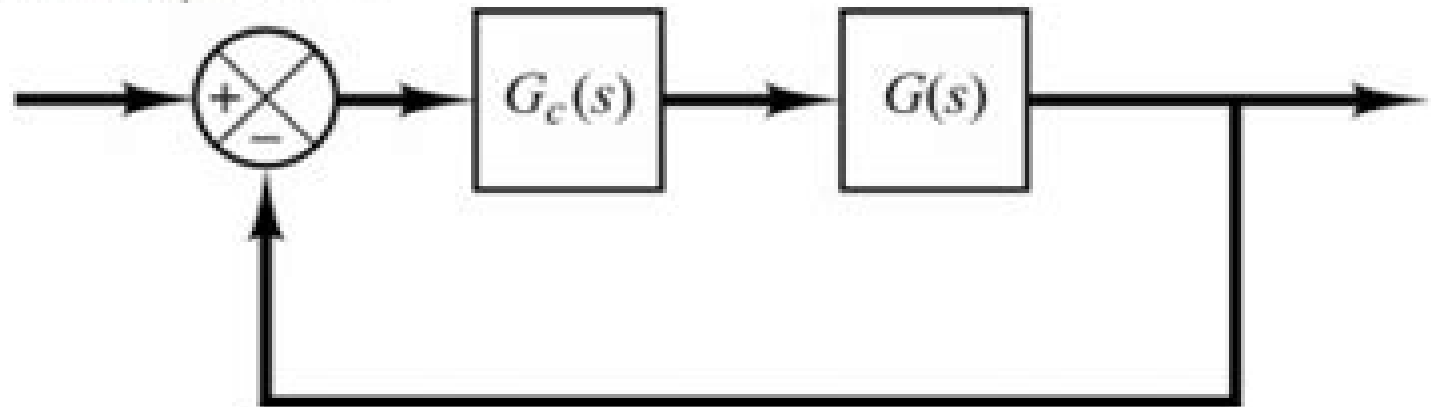


(1) Given the control system—



$$G(s) = \frac{4}{(s + 4)(s + 5)}$$

(a) For $G_c(s) = 1$, find the steady-state error for the following inputs:

- (i) Unit step
- (ii) Unit ramp

(b) A PI controller is given by

$$G_c(s) = 1 + \frac{0.1}{s}$$

Identify the control system type, that is, specify N , and repeat (a).

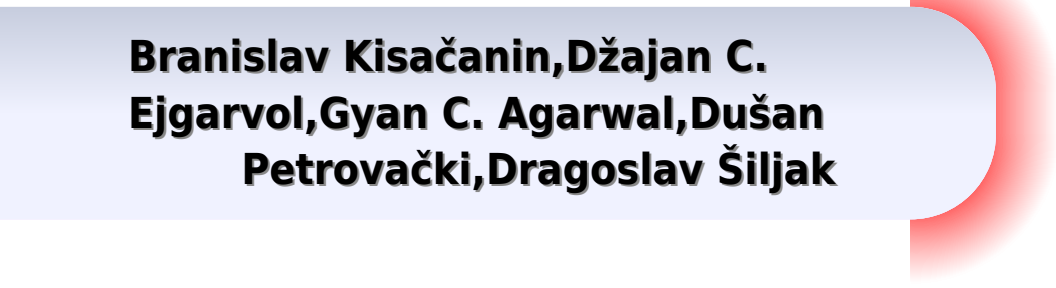
(c) A PD controller is given by

$$G_c(s) = 1 + 0.1s$$

Identify the control system type and repeat (a).

Viva And Short Questions For Linear Control System

**Branislav Kisačanin, Džajan C.
Ejgarvol, Gyan C. Agarwal, Dušan
Petrovački, Dragoslav Šiljak**



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Control Systems Smarajit Ghosh, Ghosh, 2004-09 *2000 IEEE International Conference on Acoustics, Speech and Signal Processing* IEEE Signal Processing Society, 2000 **Cumulated Index Medicus**, 1977 Spring Meeting American Geophysical Union. Meeting, 2000 International Books in Print, 1990 American Book Publishing Record, 1977-03-31 Here's quick access to more than 490 000 titles published from 1970 to 1984 arranged in Dewey sequence with sections for Adult and Juvenile Fiction Author and Title indexes are included and a Subject Guide correlates primary subjects with Dewey and LC classification numbers These cumulative records are available in three separate sets *Agrindex*, 1982

Engineering, 1961 The British National Bibliography Arthur James Wells, 1973 Books in Print Supplement, 1977 Linear Control System Analysis and Design Constantine H. Houpis, Stuart N. Sheldon, John J. D'Azzo, 2003-08-14

Thoroughly classroom tested and proven to be a valuable self study companion Linear Control System Analysis and Design Fifth Edition uses in depth explanations diagrams calculations and tables to provide an intensive overview of modern control theory and conventional control system design The authors keep the mathematics to a minimum while stressing real world engineering challenges Completely updated and packed with student friendly features the Fifth Edition presents a wide range of examples using MATLAB and TOTAL PC as well as an appendix listing MATLAB functions for optimizing control system analysis and design Eighty percent of the problems presented in the previous edition have been revised to further reinforce concepts necessary for current electrical aeronautical astronautical and mechanical applications **Introduction to Linear Control Systems** Yazdan Bavafa-Toosi, 2017-09-19 Introduction to Linear Control Systems is designed as a standard introduction to linear control systems for all those who one way or another deal with control systems It can be used as a comprehensive up to date textbook for a one semester 3 credit undergraduate course on linear control systems as the first course on this topic at university This includes the faculties of electrical engineering mechanical engineering aerospace engineering chemical and petroleum engineering industrial engineering civil engineering bio engineering economics mathematics physics management and social sciences etc The book covers foundations of linear control systems their raison detre different types modelling representations computations stability concepts tools for time domain and frequency domain analysis and synthesis and fundamental limitations with an emphasis on frequency domain methods Every chapter includes a part on further readings where more advanced topics and pertinent references are introduced for further studies The presentation is theoretically firm contemporary and self contained Appendices cover Laplace transform and differential equations dynamics MATLAB and SIMULINK treatise on stability concepts and tools treatise on Routh Hurwitz method random optimization techniques as well as convex and non convex problems and sample midterm and endterm exams The book is divided to the sequel 3 parts plus appendices PART I In this part of the book chapters 1 5 we present foundations of linear control systems This includes the introduction to control systems their raison detre their different types modelling of

control systems different methods for their representation and fundamental computations basic stability concepts and tools for both analysis and design basic time domain analysis and design details and the root locus as a stability analysis and synthesis tool PART II In this part of the book Chapters 6-9 we present what is generally referred to as the frequency domain methods This refers to the experiment of applying a sinusoidal input to the system and studying its output There are basically three different methods for representation and studying of the data of the aforementioned frequency response experiment these are the Nyquist plot the Bode diagram and the Krohn Manger Nichols chart We study these methods in details We learn that the output is also a sinusoid with the same frequency but generally with different phase and magnitude By dividing the output by the input we obtain the so called sinusoidal or frequency transfer function of the system which is the same as the transfer function when the Laplace variable s is substituted with $j\omega$ Finally we use the Bode diagram for the design process PART III In this part Chapter 10 we introduce some miscellaneous advanced topics under the theme fundamental limitations which should be included in this undergraduate course at least in an introductory level We make bridges between some seemingly disparate aspects of a control system and theoretically complement the previously studied subjects Appendices The book contains seven appendices Appendix A is on the Laplace transform and differential equations Appendix B is an introduction to dynamics Appendix C is an introduction to MATLAB including SIMULINK Appendix D is a survey on stability concepts and tools A glossary and road map of the available stability concepts and tests is provided which is missing even in the research literature Appendix E is a survey on the Routh Hurwitz method also missing in the literature Appendix F is an introduction to random optimization techniques and convex and non convex problems Finally appendix G presents sample midterm and endterm exams which are class tested several times

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Linear Control Systems Branislav Kisačanin, Džajan C. Ejgarvol, Gyan C. Agarwal, Dušan Petrovački, Dragoslav Šiljak, 2002

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