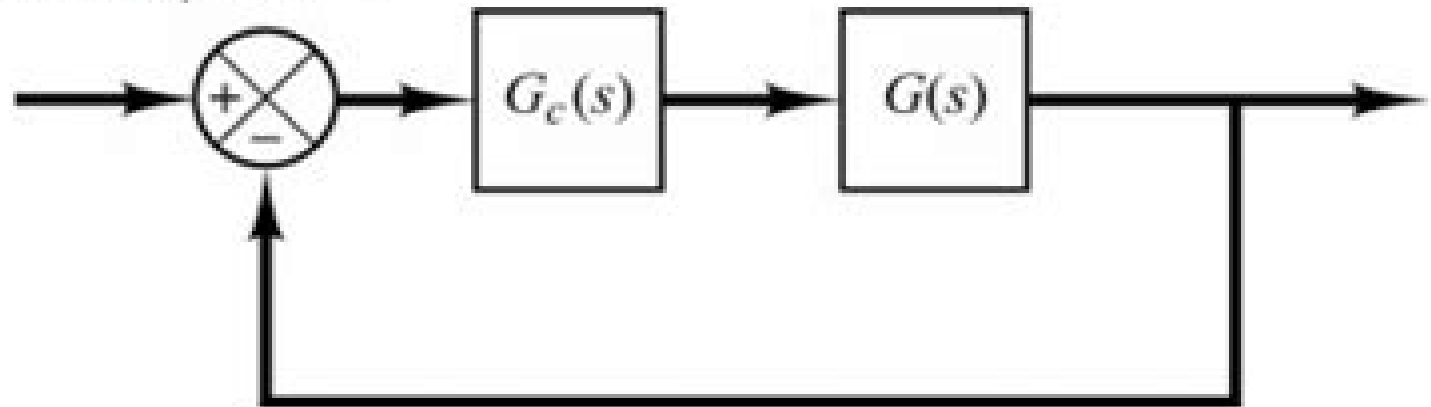


(1) Given the control system—



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

(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

Stefano Battilotti



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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

Linear Control Systems: For PTU , INTRODUCTION TO LINEAR AND DIGITAL CONTROL SYSTEMS ARUN K. GHOSH,2007-05-02 This book presents comprehensive coverage of linear control systems along with an introduction to digital control systems It is designed for undergraduate courses in control systems taught in departments of electrical engineering electronics and instrumentation electronics and communication instrumentation and control and computer science and engineering The text discusses the important concepts of control systems transfer functions and system components It describes system stability employing the Hurwitz Routh stability criterion root locus technique Bode plot and polar and Nyquist plots In addition this student friendly book features in depth coverage of controllers compensators state space modelling and discrete time systems KEY FEATURES Includes a brief tutorial on MATLAB in an appendix to help students learn how to use it for the analysis and design of control systems Provides an abundance of worked out examples and review questions culled from university examination papers Gives answers to selected chapter end questions at the end of the book **Linear Control System Analysis and Design** John Joachim D'Azzo,Constantine H. Houpis,1975 **Linear Control Systems Engineering** Morris Driels,1995 **Notes on Linear Control Systems** Stefano Battilotti,2016

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