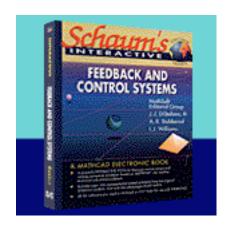
# Feedback and Control Systems

Platform: Windows

Includes the Mathcad Engine; requires 4 MB hard disk space

Available for ground shipment

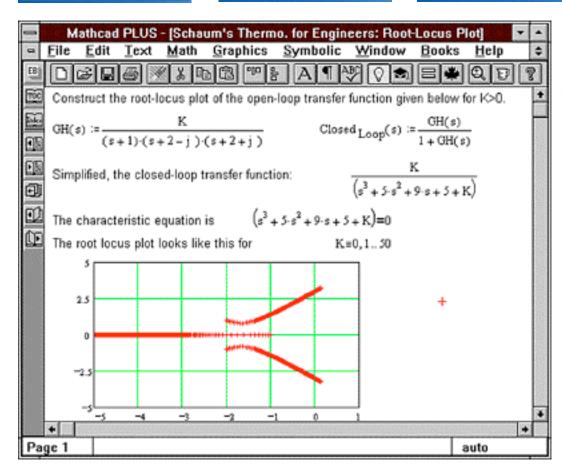


Through more than 100 solved problems in control system design and analysis, several major techniques of analysis and design are developed and demonstrated. For students and educators, this Electronic Book is an excellent tool for exploring and understanding the fundamentals of feedback control systems. Professionals get advanced numerical and symbolic techniques for plotting system behavior and solving for stability and design specifications. The early chapters develop the theoretical foundations while later sections apply this understanding to designing feedback control systems. Plus the Mathcad Engine is built-in so the math is "live" and interactive.

**Table of Contents** 

**Product Sample** 

**Back to Product List** 

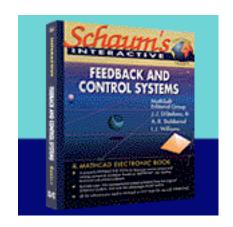


Experiment with graphing techniques for root-locus plots.

Topics include: Differential Equations, Difference Equations and Linear Systems, Stability and Routh-Hurwitz Criteria, Transfer Functions and Characteristics Equations, Block Diagram Algebra Signal Flow Graphs, Nyquist, Bode and Nichols Analysis and Design, and much more.

# Feedback and Control Systems

### TABLE OF CONTENTS (page 1 of 6)



#### **Chapter 1 - Introduction**

Understanding Feedback Control Systems (Schaum's Solved Problem 1.11)
Understanding Feedback Control Terminology (Schaum's Solved Problems 1.1, 1.7, and 1.8)

#### **Chapter 2 - Control System Terminology**

Block Diagrams and Feedback-Control System Terminology I (Schaum's Solved Problem 2.2)

Block Diagrams and Feedback-Control System Terminology II (Schaum's Solved Problem 2.7)

#### Chapter 3 - Differential Equations and their Solutions

The Characteristic Equation (Schaum's Solved Problems 3.12 - 3.13)

Free Response, Distinct Roots (Schaum's Solved Problem 3.16b and 3.20)

Free Response, Repeated Roots (Schaum's Solved Problem 3.16a)

Fundamental Sets (Schaum's Solved Problem 3.17)

Forced Response, the Weighting Function (Schaum's Solved Problems 3.21 - 3.22)

#### Chapter 4 - The Laplace Transform and the z-Transform

Solving a Differential Equation by the Laplace Transform Method I (Schaum's Example 4.17 and Solved Problem 4.27)

Inverse Laplace Transform by Partial Fractions (Schaum's Example 4.24)

Solving a Difference Equation by the z-Transform Method (Schaum's Example 4.41)

Solving a Differential Equation by the Laplace Transform Method II(Schaum's Solved Problems 4.20-4.23)

Pole-Zero Maps (Schaum's Solved Problems 4.32 - 4.33)

Second-Order Systems (Schaum's Solved Problem 4.35)

Approximation by a Second-Order System (Schaum's Solved Problem 4.36)

**Product Sample** 



# Feedback and Control Systems

#### TABLE OF CONTENTS (page 2 of 6)

#### **Chapter 5 - Stability**

Impulse Responses (Schaum's Solved Problem 5.1)
The w-Transform (Schaum's Example 5.8)
Stability of Discrete-Time Systems (Schaum's Solved Problem 5.22)
Approximate vs. Exact Solutions for Roots (Schaum's Solved Problem 5.23)
Stability of Continuous Systems (Schaum's Solved Problem 5.30a)

#### **Chapter 6 - Transfer Functions**

Continuous System Frequency Response Plots (Schaum's Examples 6.8 - 6.9)

Lag Compensators (Schaum's Solved Problem 6.13 and 6.16)

Lag-Lead Compensators (Schaum's Solved Problem 6.14)

Unit Step Response Given Poles and Zeros (Schaum's Solved Problems 6.11 and 6.19)

DC Gain (Schaum's Solved Problem 6.21)

Frequency-Dependent Gain and Phase (Schaum's Solved Problems 6.22 - 6.23)

Discrete-Time System Frequency Response (Schaum's Solved Problem 6.27)

#### Chapter 7 - Block Diagrams and Transfer Functions

Unity Feedback System (Schaum's Solved Problem 7.15) Superposition of Multiple Input Systems (Schaum's Solved Problem 7.16) Reduction of Complicated Block Diagrams (Schaum's Solved Problems 7.19)

#### **Chapter 8 - Signal Flow Graphs**

The General Input-Output Gain Formula (Schaum's Solved Problems 8.8 and 8.11)
Transfer Function Computation of Cascaded Components and Block Diagram
Reduction Using Signal Flow Graphs
(Schaum's Solved Problem 8.14)

#### **Chapter 9 - Sensitivity of Feedback Systems**

The Sensitivity of the Transfer Function (Schaum's Examples 9.2 and 9.4)

Comparing Sensitivity of Transfer Functions (Schaum's Solved Problem 9.3)

Open-Loop vs. Closed-Loop Systems (Schaum's Example 9.6)

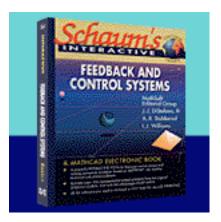
Sensitivity with Respect to |G| (Schaum's Examples 9.7 - 9.8)

**Product Sample** 



# Feedback and Control Systems

TABLE OF CONTENTS (page 3 of 6)



#### Chapter 10 - Analysis and Design of Feedback Control Systems

Gain and Phase Margin (Schaum's Solved Problems 10.2 - 10.3)

Average Delay Time (Schaum's Solved Problem 10.4)

Bandwidth of a Lowpass System (Schaum's Solved Problem 10.5)

Bandwidth of a Resonant System (Schaum's Solved Problem 10.15)

Octaves (Schaum's Solved Problem 10.6)

Resonant Frequency (Schaum's Solved Problem 10.7)

Delay Time and Rise Time (Schaum's Solved Problems 10.8 - 10.9)

Rise Time for a Discrete-Time System (Schaum's Solved Problem 10.10)

Frequency vs. Time-Domain Specifications (Schaum's Examples 10.2 - 10.3)

A Deadbeat System (Schaum's Example 10.7)

#### Chapter 11 - Nyquist Analysis

Nyquist Stability for a Discrete-Time System (Schaum's Examples 11.11 and 11.14)

Nyquist Stability for a Continuous System (Schaum's Solved Problems 11.43 and 11.55)

Relative Stability (Schaum's Solved Problem 11.59)

Nyquist Stability for a Discrete-Time System II (Schaum's Solved Problem 11.67)

Nyquist Analysis of Time-Delayed Systems (Schaum's Supplementary Problem 11.80)

#### Chapter 12 - Nyquist Design

Gain Factor Compensation (Schaum's Solved Problems 12.1 - 12.3)

Continuous System Lead Compensation (Schaum's Example 12.4)

Digital Lag Compensator (Schaum's Solved Problem 12.12)

Digital Compensation Networks (Schaum's Example 12.7 and Solved Problem 12.16)

Continuous System Lag Compensation (Schaum's Example 12.5)

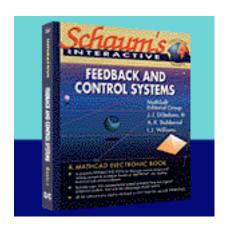
General Compensation Issues (Schaum's Solved Problem 12.10)

**Product Sample** 



# Feedback and Control Systems

#### TABLE OF CONTENTS (page 4 of 6)



#### Chapter 13 - Root-Locus Analysis

Angle and Magnitude Criteria (Schaum's Example 13.1 and Solved Problem 13.4) Gain Margin from the Root-Locus Plot (Schaum's Example 13.8 and Solved Problem 13.35)

Departure Angles (Schaum's Solved Problems 13.24 and 13.26)

Root-Locus with Poles and Zeros (Schaum's Example 13.9)

Root-Locus for a Discrete System (Schaum's Solved Problem 13.31)

Root-Locus for Positive and Negative Gain (Schaum's Solved Problem 13.28)

#### Chapter 14 - Root-Locus Design

Gain Factor Compensation (Schaum's Solved Problem 14.1)

Dominant Pole-Zero Approximation (Schaum's Solved Problem 14.12)

Feedback Compensation (Schaum's Solved Problem 14.17)

Point Design (Schaum's Solved Problem 14.14)

Feedback Compensation and Point Design (Schaum's Solved Problem 14.16)

Digital Compensation (Schaum's Example Problem 14.5)

Lead Compensation on the Root-Locus (Schaum's Example Problem 14.2)

Lag Compensation on the Root-Locus (Schaum's Example Problem 14.3)

#### **Chapter 15 - Bode Analysis**

The Bode Form and the Bode Gain (Schaum's Solved Problem 15.2)

Constructing Bode Plots (Schaum's Solved Problems 15.7 and 15.10)

Relative Stability (Schaum's Solved Problems 15.8 and 15.11)

Discrete-Time Frequency Response (Schaum's Solved Problem 15.13)

Second Order System Peak Frequency Response (Schaum's Solved Problem 15.5 and Section 15.4)

#### Chapter 16 - Bode Design

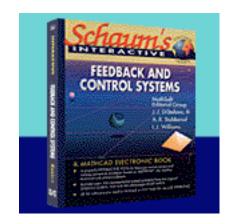
Gain Factor Compensation (Schaum's Solved Problem 16.2) Lead and Lag Parameters (Schaum's Sections 16.3 and 16.4) Lead and Gain Compensation (Schaum's Solved Problem 16.5) Lag and Gain Compensation (Schaum's Solved Problem 16.8) Lag-Lead Compensation (Schaum's Solved Problem 16.10) Digital System Compensation (Schaum's Example 16.6)

**Product Sample** 



# Feedback and Control Systems

### TABLE OF CONTENTS (page 5 of 6)



#### Chapter 17 - Nichols Chart Analysis

Magnitude-Phase Plots and Relative Stability - Type 1 System (Schaum's Solved Problems 17.2 and 17.6)

Magnitude-Phase Plots and Relative Stability - Type 2 System (Schaum's Solved Problems 17.4 and 17.7)

Discrete-Time Gain Phase Plots (Schaum's Solved Problems 17.5 and 17.9) Closed-Loop Frequency Response Functions (Schaum's Solved Problem 17.14) Nichols Charts (Schaum's Solved Problem 17.15)

#### Chapter 18 - Nichols Chart Design

Gain Factor Compensation (Schaum's Solved Problem 18.1) Closed-Loop Gain Factor Compensation (Schaum's Solved Problem 18.4) Lead and Lag Compensator Magnitude-Phase Plots (Schaum's Sections 18.4 and 18.5)

Lead and Gain Network Compensation (Schaum's Solved Problem 18.7) Lag and Gain Network Compensation (Schaum's Example Problem 18.4)

#### Chapter 19 - Introduction to Nonlinear Control Systems

Taylor Series Expansion (Schaum's Solved Problem 19.4) Phase Plane Methods (Schaum's Solved Problem 19.9) Frequency Response Methods (Schaum's Solved Problem 19.19)

# Chapter 20 - Introduction to Advanced Topics in Control System Analysis and Design

**Appendix A - Some Laplace Transform Pairs and Properties Useful for Control Systems Analysis** 

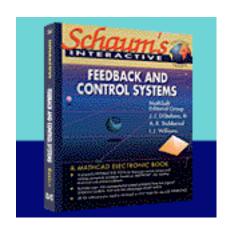
Appendix B - Some z-Transform Pairs and Properties Useful for Control Systems Analysis

**Product Sample** 



## Feedback and Control Systems

TABLE OF CONTENTS (page 6 of 6)



Appendix C - Block Diagram Transformation Theorems

Appendix D - Solving Polynomials Using the Companion Matrix

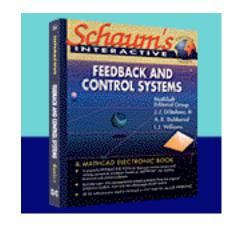
References and Bibliography

**Index** 

**Product Sample** 

# Feedback and Control Systems

SAMPLE PAGE (page 1 of 3)



### **Constructing Bode Plots**

#### **Statement**

Construct the Bode plot for the frequency response function given below. Also, determine the gain and phase margins for the system.

#### **System Parameters**

$$GH(\omega) := \frac{2}{j \cdot \omega \cdot \left(1 + \frac{j \cdot \omega}{2}\right) \cdot \left(1 + \frac{j \cdot \omega}{5}\right)}$$

#### **Solution**

To create the Bode plot for this function, plot the magnitude in decibels and the phase using the phase function shown in Chapter 15.

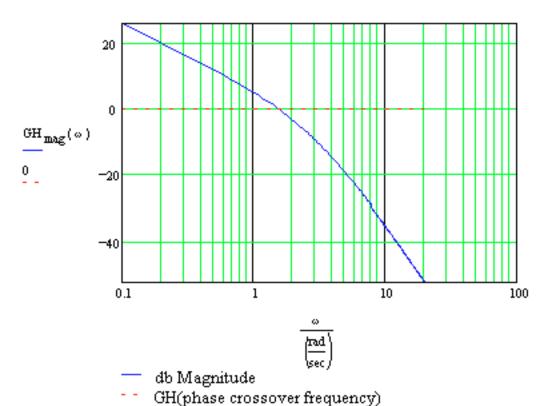
$$\text{GH}_{\text{mag}}(\omega) \coloneqq 20 \cdot \log \left| \text{GH}(\omega) \right| ) \qquad \qquad \text{phase}(f) \coloneqq \text{if}(\text{arg}(f) > 0, \text{arg}(f) - 2 \cdot \pi, \text{arg}(f))$$

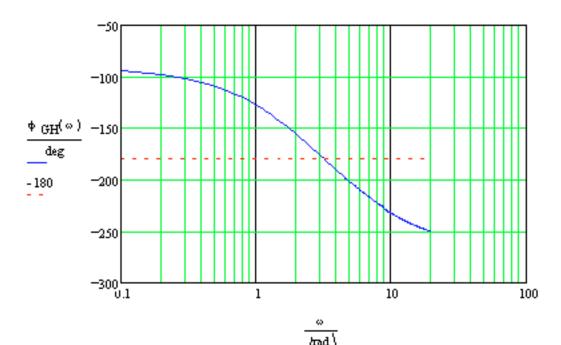
$$\phi_{GH}(\omega) := phase(GH(\omega))$$
  $\omega := .1,.2...20$ 

**Table of Contents** 

# Feedback and Control Systems

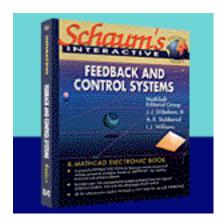
SAMPLE PAGE (page 2 of 3)





— Phase Angle

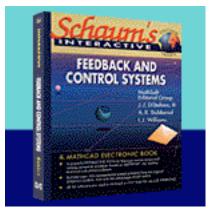
GH(gain crossover frequency)



**Table of Contents** 

# Feedback and Control Systems

#### SAMPLE PAGE (page 3 of 3)



Now find the gain and phase crossover frequencies. There are two ways to do this. First, from the magnitude and phase angle plots, we can make a good guess at where  $\mathbf{w}_1$  and wp are, respectively, and solve the necessary equations. Or, we could find where the two curves plotted on each the magnitude and phase angle plots intersect by setting them equal to each other and solving for  $\mathbf{w}$ . Both ways are shown here. Solve for  $\mathbf{w}_1$  by using the graph and for  $\mathbf{w}_p$  by using the equations.

Input a guess value for  $\mathbf{w}_1$  based on the magnitude plot intersection and change it until the answer to the  $|\mathbf{GH}(\mathbf{w})|$  function is unity.

$$\omega_1 := 1.52$$
  $\left| GH(\omega_1) \right| = 1$ 

For  $\mathbf{w}_{\mathbf{p}'}$  set the phase equation equal to -180° (or -p) and use the **root** function.

Guess:

$$\omega_g := 1$$
  $\omega_\pi := root(phase(GH(\omega_g)) + \pi, \omega_g)$ 

$$\omega_{\pi} = 3.2$$
  $\omega_{\pi} = 1 - \sqrt{10}$ 

Therefore, the gain margin is

$$gain_{margin} := -20 \cdot log(|GH(\omega_{\pi})|)$$
  $gain_{margin} = 10.9$ 

And the phase margin is

phase 
$$_{\text{margin}} := 180 \cdot \text{deg} + \text{arg}(GH(\omega_1))$$
 phase  $_{\text{margin}} = 35.9 \cdot \text{deg}$ 

**Table of Contents** 

