CONTENTS

Preface List of Symbols and Abbreviations

CHAPTER 1: Mathematical Model of Control System

- 1.1 Control System 1.1
- 1.2 Examples of Control Systems 1.2
- 1.3 Mathematical Models of Control System 1.5
- 1.4 Mechanical Translational Systems 1.6
- 1.5 Mechanical Rotational Systems 1.14
- 1.6 Electrical System 1.20
- 1.7 Transfer Function of Armature Controlled DC Motor 1.21
- 1.8 Transfer Function of Field Controlled DC Motor 1.24

CHAPTER 2: Time Response Analysis

- 2.1 Time Respone 2.1
- 2.2 Test Signal 2.1
- 2.3 Impulse Response 2.3
- 2.4 Order of a System 2.3
- 2.5 Review of Partial Fraction Expansion 2.4
- 2.6 Response of First Order System for Unit Step Input 2.7
- 2.7 Second Order System 2.9
 - 2.7.1 Response of Undamped Second Order System for Unit Step Input 2.10
 - 2.7.2 Response of Underdamped Second Order System for Unit Step Input 2.11
 - 2.7.3 Response of Critically Damped Second Order System for Unit Step Input 2.13
 - 2.7.4 Response of Over Damped Second Order System for Unit Step Input 2.14
- 2.8 Time Domain Specifications 2.16
- 2.9 Type Number of Control System 2.33
- 2.10 Steady State Error 2.33
- 2.11 Static Error Constant 2.34

CHAPTER 3: Frequency Analysis

- 3.1 Sinusoidal Transfer Function and Frequency Response 3.1
- 3.2 Frequency Domain Specifications 3.2
- 3.3 Frequency Domain Specifications of Second Order System 3.4

- 1.9 Electrical Analogous of Mechanical Translational Systems 1.25
- 1.10 Electrical Analogous of Mechanical Rotational Systems 1.40
- 1.11 Block Diagrams 1.49
- 1.12 Block Diagrams Reduction using MATLAB 1.70
- 1.13 Signal Flow Graph 1.73
- 1.14 Short Answers Questions 1.91
- 1.15 Exercises 1.96
- 2.12 Steady State Error when the Input is Unit Step Signal 2.34
- 2.13 Steady State Error when the Input is Unit Ramp Signal 2.35
- 2.14 Steady State Error when the Input is Unit Parabolic Signal 2.36
- 2.15 Generalized Error Coefficients 2.37
- 2.16 Evaluation of Generalized Error Coefficients 2.39
- 2.17 Correlation between Static and Dynamic Error Coefficients 2.40
- 2.18 Alternate Method for Generalized Error Coefficients 2.40
- 2.19 Components of Automatic Control System 2.49
- 2.20 Controllers 2.49
- 2.21 Response with P, PI, PD and PID Controllers 2.61
- 2.22 Time Response Analysis using MATLAB 2.64
- 2.23 Short Answers Questions 2.73
- 2.24 Exercies 2.82

3.1-3.98

- 3.4 Correlation between Time and Frequency Response 3.7
- 3.5 Frequency Response Plots 3.9
- 3.6 Bode Plot 3.9
- 3.7 Polar Plots 3.37

xiii

vii

1.1-1.102

2.1-2.84

- Appendix 1: Laplace Transform Pairs and Appendix 2: Roots of Algebric Equation
- Properties A.1 by Lin's Method A.3
- **Appendices**
- (Pulse Transfer Function) 7.33

- 6.7 State Space Representation using
- 7.1 Introduction 7.1

7.6 Z-Transform 7.9

- 7.2 Sampling Process 7.2

- 7.3 Analysis of Sampling Process in Frequency Domain 7.3

7.7 Linear Discrete Time Systems 7.31

7.8 Transfer Function of LDS System

- 7.4 Reconstruction of Sampled Signals using Hold Circuits 7.5

7.5 Discrete Sequence (Discrete Time Signal) 7.6

- Canonical Variables 6.31 **CHAPTER 7: Sampled Data Control Systems**
- 6.2 State Space Formulation 6.1
- 6.1 Introduction 6.1

6.3 State Model of Linear System 6.2

6.5 State Space Representation using

6.6 State Space Representation using

Physical Variables 6.6

Phase Variables 6.20

- **CHAPTER 6: State Space Analysis**

3.8 Nichols Plot 3.61

Response 3.65

3.10 M and N Circles 3.65

3.11 Nichols Chart 3.70

3.9 Closed Loop Response from Open Loop

4.1 Impulse Response and Stability 4.1

Nyquist Stability Criterion 4.26

CHAPTER 5: Linear System Design

4.3 Routh Hurwitz Criterion 4.8

4.6 Relative Stability 4.54

4.4 Mathematical Preliminaries for

4.5 Nyquist Stability Criterion 4.29

4.2 Location of Poles on S-Plane for Stability 4.3

5.1 Introduction to Design using Compensators 5.1

CHAPTER 4: Concepts of Stability and Root Locus

5.2 Lag Compensator 5.4

6.4 State Diagram 6.4

- 5.4 Lag-Lead Compensator 5.49

xii

- 5.3 Lead Compensator 5.26

5.8 Exercises 5.101

6.1-6.106

5.5 PI, PD and PID Controllers 5.64

5.6 Feedback Compensation 5.82

5.7 Short Answers Questions 5.95

- 6.8 Solution of State Equations 6.37
- 6.9 Transformation of State Model 6.48
- 6.10 Concepts of Controllability and
- Observability 6.57 6.11 State Space Representation of
- Discrete Time System 6.66 6.12 State Space Analysis
- using MATLAB 6.80
- 6.13 Short Answers Questions 6.88
- 6.14 Exercises 6.101
- 7.9 Analysis of Sampler and Zero-Order Hold 7.37
- 7.10 Analysis of Systems with Impulse Sampling 7.38
- 7.11 Analysis of Sampled Data Control Systems using Z-Transform 7.43
- 7.12 The Z- and S-Domain Relationship 7.51
- 7.13 Stability Analysis of Sampled Data Control Systems 7.52
- 7.14 Short Answers Questions 7.59
- 7.15 Exercises 7.66
- A.1-A.11

1.1-1.5

7.1-7.66

Appendix 3: Matrix Fundamentals A.4 Appendix 4: Z-Tranform Pairs and Properties A.7 Appendix 5: MATLAB Commands A.9

3.13 Short Answers Questions 3.93

4.1-4.106

5.1-5.102

Control Systems Engineering

3.14 Excercises 3.98

3.12 Frequency Response Analysis Using

MATLAB 3.82

4.8 Root Locus 4.60

MATLAB 4.95

4.11 Exercises 4.105

4.7 Gain Margin and Phase Margin 4.55

4.9 Nyquist and Root Locus Plots using

4.10 Short Answers Questions 4.101