
1 INTRODUCTION 1

- 1.1 Control Systems Applications 1
- 1.2 Your Study of Control Systems 6
- 1.3 Describing Control Systems 8
- 1.4 Control Systems Analysis and Design Objectives 15
- 1.5 Example of a Closed-Loop System: The Position Control 17
- 1.6 The Design and Analysis Sequence 20
- 1.7 Summary 26
 - Review Questions 27
 - Problems 28
 - Bibliography 32

2 SYSTEM MODELING IN THE FREQUENCY DOMAIN 33

- 2.1 Introduction 33
- 2.2 Laplace Transform Review 35
- 2.3 The Transfer Function 46
- 2.4 Transfer Functions for Electrical Networks 48
- 2.5 Transfer Functions for Translational Mechanical Systems 57
- 2.6 Transfer Functions for Rotational Mechanical Systems 65
- 2.7 Transfer Functions for Systems with Gears 70
- 2.8 Transfer Functions for Electromechanical Systems 76
- 2.9 Nonlinearities 83
- 2.10 Linearization 85
- 2.11 Chapter-Objective Demonstration Problems 91

2.12	Summary	95
	Review Questions	96
	Problems	96
	Bibliography	110

*3 SYSTEM REPRESENTATION IN THE TIME DOMAIN 111

3.1	Introduction	111
3.2	Some Observations	112
3.3	The General State-Space Representation	117
3.4	Applying the State-Space Representation	119
3.5	Converting Transfer Functions to the State-Space, Phase-Variable Form	127
3.6	Converting the State Equations to a Transfer Function	132
3.7	Linearization	134
3.8	Chapter-Objective Demonstration Problems	137
3.9	Summary	141
	Review Questions	142
	Problems	142
	Bibliography	147

4 TIME RESPONSE FOR THE SYSTEM MODEL 149

4.1	Introduction	149
4.2	The Concept of Poles and Zeros and System Response	150
4.3	First-Order System Responses and Specifications	154
4.4	Second-Order System Responses: Some Observations	156
4.5	The General Second-Order System and Its Specifications	161
4.6	Further Analysis for Underdamped Second-Order Systems	165
4.7	System Responses with Additional Poles	176
4.8	System Responses with Zeros	180
*4.9	Solving the State Equations via the Laplace Transform	183
*4.10	Solving the State Equations Directly in the Time Domain	186
*4.11	Numerical Solution of the State Equations for Computer Simulation	192
4.12	Chapter-Objective Demonstration Problems	194

- 4.13 Summary 199
- Review Questions 200
- Problems 201
- Bibliography 209

5 REPRESENTATION AND REDUCTION OF MULTIPLE SUBSYSTEMS

211

- 5.1 Introduction 211
- 5.2 Block Diagram Representation and Reduction
of Multiple Subsystems 212
- 5.3 Analysis and Design of Feedback Systems 222
- *5.4 Signal-Flow Graph Representation and Conversion
from Block Diagrams 225
- *5.5 Mason's Rule for Reduction of Signal-Flow Graphs 228
- *5.6 Signal-Flow Graphs of State Equations 232
- *5.7 Alternate Representations in State Space 233
- *5.8 Similarity Transformations 242
- 5.9 Chapter-Objective Demonstration Problems 251
- 5.10 Summary 258
- Review Questions 259
- Problems 260
- Bibliography 276

6 STABILITY

277

- 6.1 Introduction 277
- 6.2 Routh-Hurwitz Criterion 280
- 6.3 Routh-Hurwitz Criterion: Special Cases 284
- 6.4 Additional Examples Using the Routh-Hurwitz Criterion 290
- *6.5 Stability via Eigenvalues for the State-Space Representation 296
- 6.6 Chapter-Objective Demonstration Problems 298
- 6.7 Summary 300
- Review Questions 301
- Problems 301
- Bibliography 309

7 STEADY-STATE ERRORS

311

- 7.1 Introduction 311
- 7.2 Derivation of the Steady-State Errors for a Unity Feedback Control System 315
- 7.3 Definition of Static Error Constants and System Type 321
- 7.4 Steady-State Error Specifications and Examples 325
- 7.5 The Steady-State Error for Disturbances 327
- 7.6 Steady-State Errors for Non-Unity Feedback Systems 329
- 7.7 Sensitivity 333
- 7.8 Chapter-Objective Demonstration Problems 336
- 7.9 Summary 338
 - Review Questions 339
 - Problems 340
 - Bibliography 351

8 ROOT LOCUS TECHNIQUES FOR STABILITY AND TRANSIENT RESPONSE

353

- 8.1 Introduction 353
- 8.2 Defining the Root Locus 358
- 8.3 Properties of the Root Locus 361
- 8.4 Rules for Sketching the Root Locus 364
- 8.5 Calculation of the $j\omega$ -Axis Crossing 372
- 8.6 Plotting and Calibrating the Root Locus 373
- 8.7 Real-Axis Breakaway and Break-in Points 374
- 8.8 An Example 378
- 8.9 Transient Response Design via Root Locus and Gain Adjustment 380
- 8.10 Generalized Root Locus 384
- 8.11 Root Locus for Positive-Feedback Systems 386
- 8.12 Pole Sensitivity 389
- 8.13 Chapter-Objective Demonstration Problems 391
- 8.14 Summary 398
 - Review Questions 399
 - Problems 399
 - Bibliography 412

9 DESIGN OF COMPENSATORS VIA THE ROOT LOCUS

413

- 9.1 Introduction and Definition of the Problem 413
- 9.2 Cascade Compensation to Improve Steady-State Error 417
- 9.3 Cascade Compensation to Improve Transient Response 429
- 9.4 Cascade Compensation to Improve Both Steady-State Error and Transient Response 445
- 9.5 Feedback Compensation 458
- 9.6 Physical Realization of Compensation 468
- 9.7 Chapter-Objective Demonstration Problems 474
- 9.8 Summary 481
 - Review Questions 482
 - Problems 483
 - Bibliography 492

10 FREQUENCY RESPONSE METHODS

493

- 10.1 Introduction 493
- 10.2 Asymptotic Approximations: The Bode Plots 500
- 10.3 Derivation of the Nyquist Criterion for Stability 517
- 10.4 Sketching the Nyquist Diagram 523
- 10.5 Determining Stability via the Nyquist Diagram 529
- 10.6 Gain Margin and Phase Margin 534
- 10.7 Stability Calculations Using Bode Plots 536
- 10.8 Relation between Closed-Loop Transient and Closed-Loop Frequency Responses 540
- 10.9 Relation between Closed-Loop Frequency and Open-Loop Frequency Responses 543
- 10.10 Relation between Closed-Loop Transient and Open-Loop Frequency Responses 550
- 10.11 Finding the Steady-State Error Specifications from the Frequency Response 554
- 10.12 Frequency Response Methods for Systems with Time Delay 559
- 10.13 Chapter-Objective Demonstration Problem 562

- 10.14 Summary 564
- Review Questions 565
- Problems 566
- Bibliography 573

11 DESIGN VIA FREQUENCY RESPONSE METHODS 575

- 11.1 Introduction 575
- 11.2 Gain Adjustment to Improve Transient Response 576
- 11.3 Lag Compensation to Improve Steady-State Error 579
- 11.4 Lead Compensation to Improve Transient Response 584
- 11.5 Lag-Lead Compensation to Improve Steady-State Error and Transient Response 590
- 11.6 Chapter-Objective Demonstration Problems 595
- 11.7 Summary 597
- Review Questions 598
- Problems 599
- Bibliography 602

*12 DESIGN VIA THE STATE-SPACE APPROACH 603

- 12.1 Introduction 603
- 12.2 Controller Design 605
- 12.3 Controllability 612
- 12.4 Controller Design for Systems Not Represented in Phase-Variable Form 616
- 12.5 Observer Design 622
- 12.6 Observability 629
- 12.7 Observer Design for Systems Not Represented in Dual Phase-Variable Form 633
- 12.8 Steady-State Error Analysis and Design 639
- 12.9 Chapter-Objective Demonstration Problem 646
- 12.10 Summary 652

Review Questions 653

Problems 654

Bibliography 659

13 DIGITAL CONTROL SYSTEMS

661

-
- 13.1 Introduction 661
 - 13.2 Modeling the Digital Computer 666
 - 13.3 The z -Transform 669
 - 13.4 The Transfer Function of Sampled-Data Systems 674
 - 13.5 Block Diagram Manipulation of Sampled-Data Systems 677
 - 13.6 Stability of Sampled-Data Systems 680
 - 13.7 Steady-State Errors for Sampled-Data Systems 686
 - 13.8 Transient Response on the z -Plane 690
 - 13.9 The Root Locus on the z -Plane and Design
via Gain Adjustment 693
 - 13.10 Chapter-Objective Demonstration Problems 696
 - 13.11 Summary 700
 - Review Questions 701
 - Problems 701
 - Bibliography 706

APPENDIX A LIST OF SYMBOLS

707

APPENDIX B MATRICES, DETERMINANTS, AND SYSTEMS OF EQUATIONS

710

-
- B.1 Matrix Definitions and Notations 710
 - B.2 Matrix Operations 714
 - B.3 Matrix and Determinant Identities 716
 - B.4 Systems of Equations 717

APPENDIX **C** COMPUTER PROGRAMS

719

C.1 Program to Plot the Step Response of a System Represented
in State Space 719

C.2 Root Locus and Frequency Response 725

Glossary 731

Answers to Selected Problems 739

Index 745