

University of Saskatchewan
EE 480.3 Digital Control Systems

Final Examination, April 14, 2010

3 hour open-book exam

Instructor: K. Takaya

1. (25) A continuous time system is defined as follows for input $x(t)$ and output $y(t)$.

$$Y(s) = G(s)X(s), \quad G(s) = \frac{1}{s(s+1)(s+2)}.$$

We apply unity gain negative feedback to this system, and adjust gain K . The discrete time model of this system with zero-order-hold ZOH for a sampling time $T_s = 0.01$ sec. is calculated as

$$G(z) = \frac{1.6542 \times 10^{-7}(z + 0.2659)(z + 3.7042)}{(z - 1)(z - 0.9900)(z - 0.9802)}.$$

1. Show if the unity gain feedback applied to $G(s)$, i.e. $\frac{KG(s)}{1 + KG(s)}$ is stable or not by a method to check stability.
2. The discrete time transfer function $G(z)$ was mapped to the w -domain by the bilinear transformation as given below. Apply Ruth-Hurwitz's stability criterion to find the stable range of the gain K .

$$G(w) = \frac{-0.005w + 1}{w^3 + 3w^2 + 2w}$$

2. (25) A second order digital control system, $G(s) = \frac{1}{s(s+1)}$ is shown in Fig. P2 (a). The discrete model of the open loop system combined with a ZOH (Zero Order Hold) has been calculated for $T = 0.1$ as follows:

$$G(z) = 0.0048 \frac{z + 0.9672}{(z - 1)(z - 0.9048)}.$$

The root locus was plotted for the following compensated system with a phase lead compensator having a pole at $z = 0$ and a zero at $z = 0.7$.

$$G_c(z) = K \frac{(z + 0.9672)(z - 0.7)}{z(z - 1)(z - 0.9048)}.$$

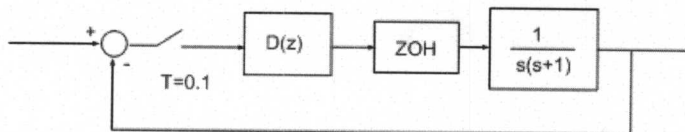


Fig. P2 (a) Block diagram of a control system

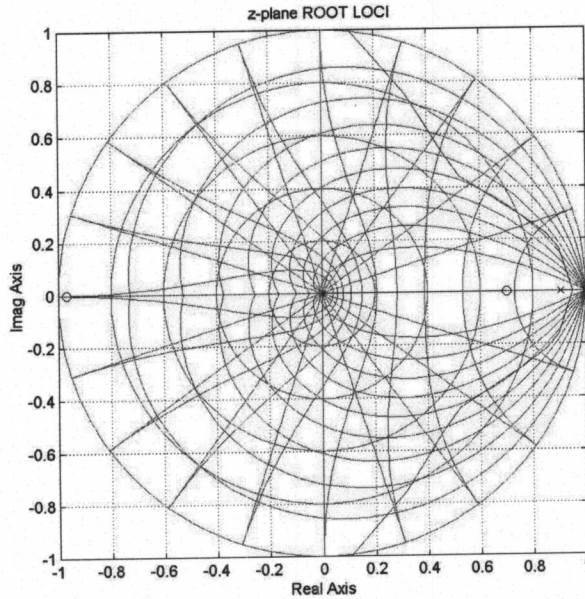


Fig. P2 (b) Root Locus plot of the phase lead compensated system

At the gain $K = 0.323$, the closed loop poles found from the root locus are $z = 0.4608$ and $z = 0.5605 \pm j0.4005$. Calculate the following values with respect to the dominant poles of the closed loop system.

1. Damping ratio ζ
 2. % Overshoot
 3. Time constant τ
 4. Natural frequency ω_n
 5. Damped natural frequency ω_d
 6. Settling time for 3% criterion T_s
3. (25) An analog system with the transfer function,

$$G(s) = \frac{1}{s^2 + s + 1}$$

has state feedback to form a feedback control system as shown in Fig. P3. The state variables are x_1 and x_2 . The sampling rate is 10 samples per second.

1. Using the state variables defined by $\begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} y \\ \dot{y} \end{bmatrix}$, obtain the analog state equation of $G(s)$ which takes the form of

$$\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{b}u(t)$$

and the output equation which gives $y(t)$.

2. Obtain the state transition matrix $\Phi(t)$ from \mathbf{A} .
3. Obtain the discrete time state equation expressed in the form of

$$\mathbf{x}(k+1) = \mathbf{P}\mathbf{x}(k) + \mathbf{q}u(k)$$

To calculate \mathbf{P} and \mathbf{q} , consider only up to the second order term of the Taylor series expansion,

$$\mathbf{P} = \Phi(T) = \mathbf{I} + \mathbf{A}T + \mathbf{A}^2 \frac{T^2}{2!} + \mathbf{A}^3 \frac{T^2}{3!} + \dots$$

4. Determine the state feedback gain vector $\mathbf{K} = [K_1, K_2]^T$ that makes the system in Figure 2 critical damping with the two poles at $z = 0.9$ by using the Ackermann's formula.

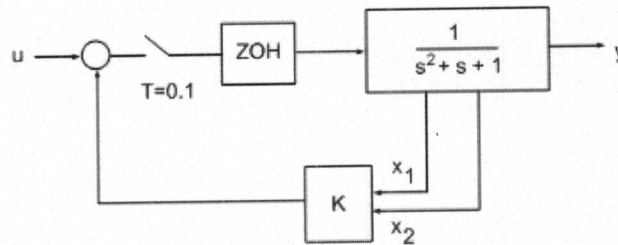


Fig. P3 A state feedback control system

4. (25) An antenna positioning system shown in Fig. P4 (a) consists of a physical system,

$$G(s) = \frac{100}{s(s+6)}$$

and a first order digital compensator given by

$$D(z) = K_d \frac{z - z_0}{z - z_p} \iff D(w) = \frac{a_1 w + a_0}{b_1 w + 1}$$

The digital compensator $D(z)$ is transformed by the bilinear transformation into the w -domain as $D(w)$ to facilitate design.

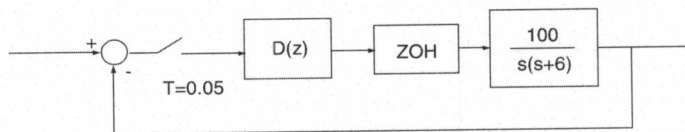


Fig. P4 (a) Block diagram of an antenna control system

The antenna positioning system preceded with a ZOH (Zero Order Hold) is described by the step invariant z -transform as

$$G(z) = 0.1134 \frac{z + 0.9049}{(z - 1)(z - 0.7408)}$$

