

Third Exam, February 16, 1994  
Solution

1. a) Taking the Laplace transform of the differential equation:

$$\frac{1}{\alpha} \cdot s \cdot L(x) = L(u) - L(x)$$

$$L(x) = \left( \frac{\alpha}{s + \alpha} \right) \cdot L(u)$$

$$\begin{aligned} L(y) &= 2 \cdot L(x) - L(u) = \left[ 2 \cdot \left( \frac{\alpha}{s + \alpha} \right) - 1 \right] \cdot L(u) \\ &= \left[ \frac{(\alpha - s)}{(s + \alpha)} \right] \cdot L(u) \end{aligned}$$

Thus,  $G = \frac{\alpha - s}{\alpha + s}$

b)  $G(i \cdot \omega) = \frac{(\alpha - i \cdot \omega)}{(\alpha + i \cdot \omega)} = \left[ \frac{\alpha^2 - \omega^2}{(\alpha^2 + \omega^2)} \right] - i \cdot \frac{2 \cdot \alpha \cdot \omega}{(\alpha^2 + \omega^2)}$

$$|G(i \cdot \omega)| = \sqrt{\left[ \frac{\alpha^2 - \omega^2}{(\alpha^2 + \omega^2)} \right]^2 + \left[ \frac{2 \cdot \alpha \cdot \omega}{(\alpha^2 + \omega^2)} \right]^2}$$

$$= \frac{1}{(\alpha^2 + \omega^2)} \cdot \sqrt{(\alpha^2 - \omega^2)^2 + 4 \cdot \alpha^2 \cdot \omega^2}$$

$$= \frac{1}{(\alpha^2 + \omega^2)} \cdot \sqrt{\alpha^4 - 2 \cdot \alpha^2 \cdot \omega^2 + \omega^4 + 4 \cdot \alpha^2 \cdot \omega^2}$$

$$= \frac{1}{(\alpha^2 + \omega^2)} \cdot \sqrt{\alpha^4 + 2 \cdot \alpha^2 \cdot \omega^2 + \omega^4}$$

$$= \frac{1}{(\alpha^2 + \omega^2)} \cdot \sqrt{(\alpha^2 + \omega^2)^2}$$

$$= 1$$

$$2. \quad G(i \cdot \omega) = 1 - \tau_z \cdot (i \cdot \omega) \quad \arg(G(i \cdot \omega)) = \text{atan}\left(-\tau_z \cdot \omega\right) \cdot \frac{180}{\pi}$$

$$\text{atan}(-\infty) = -90 \cdot \text{deg}$$

$$3. \quad 20 \cdot \log(x) = -20$$

$$x = 10^{-1}$$

$$GM = 10$$

$$PM = 180 - 100 = 80$$

$$4. \quad \text{zero} = \begin{pmatrix} 1. + .4i \\ 1. - .4i \end{pmatrix} \quad \text{poles} = \begin{pmatrix} -1. + .6i \\ -1. - .6i \end{pmatrix}$$

$$Z=2 \quad P=0 \quad N=2 - 0=2$$

Thus there will be 2 clockwise encirclements of the origin.

5. a) with  $K_c=0.5$ , the magnitude ratio at  $-180^\circ$  is  $1.5 \cdot 0.5 = 0.75$ .  
Thus  $K_c G_p$  will not encircle the point  $-1+0i$ , which implies that the feedback system will be stable.

$$b) \quad -2 = 20 \cdot \log(\text{MR}_{\max})$$

$$\text{MR}_{\max} = 10^{\frac{-2}{20}} = K_c \cdot 2$$

$$K_c = 10^{\frac{-2}{20}} \cdot \frac{1}{2} = 0.397$$

6. a) Current  $LM(G_p) @ 180^\circ = 11.67 \text{ dB}$

For  $GM=2$ , we want  $LM(K_c G_p)=20 \log(1/2)$

$$LM(K_c) = 20 \cdot \log\left(\frac{1}{2}\right) - LM(G_p) = -6.021 - 11.67 = -17.691 \text{ dB}$$

$$K_c = 10^{\frac{-17.691}{20}} = 0.13$$

b) For a phase margin of  $45^\circ$ , the corresponding  $LM(G_p) @ -135^\circ$  is  $+20\text{dB}$ .

$$LM(K_c) = -21\text{dB}$$

$$K_c = 10^{\frac{-21}{20}} = 0.09$$

c) use  $K_c=0.09$ , since this is the smaller of the two = more conservative setting.