

# Contents

## Preface 15

## 1 An Overview and Brief History of Feedback Control 23

A Perspective on Feedback Control 23

Chapter Overview 24

1.1 A Simple Feedback System 25

1.2 A First Analysis of Feedback 28

1.3 Feedback System Fundamentals 32

1.4 A Brief History 33

1.5 An Overview of the Book 40

Summary 41

Review Questions 42

Problems 42

## 2 Dynamic Models 46

A Perspective on Dynamic Models 46

Chapter Overview 47

2.1 Dynamics of Mechanical Systems 47

2.1.1 Translational Motion 47

2.1.2 Rotational Motion 54

2.1.3 Combined Rotation and Translation 65

2.1.4 Complex Mechanical Systems (W)\*\* 68

2.1.5 Distributed Parameter Systems 68

2.1.6 Summary: Developing Equations of Motion for Rigid Bodies 70

2.2 Models of Electric Circuits 71

2.3 Models of Electromechanical Systems 76

2.3.1 Loudspeakers 76

2.3.2 Motors 78

Δ 2.3.3 Gears 82

Δ 2.4 Heat and Fluid-Flow Models 83

2.4.1 Heat Flow 84

2.4.2 Incompressible Fluid Flow 88

2.5 Historical Perspective 95

Summary 98

Review Questions 98

Problems 99

# 3

## Dynamic Response 111

A Perspective on System Response 111

Chapter Overview 112

- 3.1 Review of Laplace Transforms 112
  - 3.1.1 Response by Convolution 113
  - 3.1.2 Transfer Functions and Frequency Response 118
  - 3.1.3 The  $\mathcal{L}$ -Laplace Transform 128
  - 3.1.4 Properties of Laplace Transforms 130
  - 3.1.5 Inverse Laplace Transform by Partial-Fraction Expansion 132
  - 3.1.6 The Final Value Theorem 134
  - 3.1.7 Using Laplace Transforms to Solve Differential Equations 136
  - 3.1.8 Poles and Zeros 138
  - 3.1.9 Linear System Analysis Using Matlab 139
- 3.2 System Modeling Diagrams 145
  - 3.2.1 The Block Diagram 145
  - 3.2.2 Block-Diagram Reduction Using Matlab 149
  - 3.2.3 Mason's Rule and the Signal Flow Graph (W) 150
- 3.3 Effect of Pole Locations 150
- 3.4 Time-Domain Specifications 159
  - 3.4.1 Rise Time 159
  - 3.4.2 Overshoot and Peak Time 160
  - 3.4.3 Settling Time 161
- 3.5 Effects of Zeros and Additional Poles 164
- 3.6 Stability 174
  - 3.6.1 Bounded Input–Bounded Output Stability 174
  - 3.6.2 Stability of LTI Systems 176
  - 3.6.3 Routh's Stability Criterion 177
- Δ 3.7 Obtaining Models from Experimental Data: System Identification (W) 184
- Δ 3.8 Amplitude and Time Scaling (W) 184
- 3.9 Historical Perspective 184
- Summary 185
- Review Questions 187
- Problems 187

# 4

## A First Analysis of Feedback 208

A Perspective on the Analysis of Feedback 208

Chapter Overview 209

- 4.1 The Basic Equations of Control 210
  - 4.1.1 Stability 211
  - 4.1.2 Tracking 212
  - 4.1.3 Regulation 213
  - 4.1.4 Sensitivity 214

4.2	Control of Steady-State Error to Polynomial Inputs: System Type	216
4.2.1	System Type for Tracking	217
4.2.2	System Type for Regulation and Disturbance Rejection	222
4.3	The Three-Term Controller: PID Control	224
4.3.1	Proportional Control (P)	224
4.3.2	Integral Control (I)	226
4.3.3	Derivative Control (D)	229
4.3.4	Proportional Plus Integral Control (PI)	229
4.3.5	PID Control	233
4.3.6	Ziegler–Nichols Tuning of the PID Controller	238
4.4	Feedforward Control by Plant Model Inversion	244
Δ 4.5	Introduction to Digital Control (W)	246
Δ 4.6	Sensitivity of Time Response to Parameter Change (W)	247
4.7	Historical Perspective	247
	Summary	249
	Review Questions	250
	Problems	251

## 5 The Root-Locus Design Method 270

	A Perspective on the Root-Locus Design Method	270
	Chapter Overview	271
5.1	Root Locus of a Basic Feedback System	271
5.2	Guidelines for Determining a Root Locus	276
5.2.1	Rules for Determining a Positive ( $180^\circ$ ) Root Locus	278
5.2.2	Summary of the Rules for Determining a Root Locus	284
5.2.3	Selecting the Parameter Value	285
5.3	Selected Illustrative Root Loci	288
5.4	Design Using Dynamic Compensation	301
5.4.1	Design Using Lead Compensation	302
5.4.2	Design Using Lag Compensation	307
5.4.3	Design Using Notch Compensation	310
Δ 5.4.4	Analog and Digital Implementations (W)	312
5.5	Design Examples Using the Root Locus	312
5.6	Extensions of the Root-Locus Method	323
5.6.1	Rules for Plotting a Negative ( $0^\circ$ ) Root Locus	323
Δ 5.6.2	Successive Loop Closure	326
Δ 5.6.3	Time Delay (W)	331
5.7	Historical Perspective	331

Summary	333
Review Questions	335
Problems	335

# 6

## The Frequency-Response Design Method 353

A Perspective on the Frequency-Response Design Method	353
Chapter Overview	354
6.1 Frequency Response	354
6.1.1 Bode Plot Techniques	362
6.1.2 Steady-State Errors	374
6.2 Neutral Stability	376
6.3 The Nyquist Stability Criterion	379
6.3.1 The Argument Principle	379
6.3.2 Application of The Argument Principle to Control Design	380
6.4 Stability Margins	393
6.5 Bode's Gain-Phase Relationship	402
6.6 Closed-Loop Frequency Response	407
6.7 Compensation	408
6.7.1 PD Compensation	409
6.7.2 Lead Compensation (W)	410
6.7.3 PI Compensation	420
6.7.4 Lag Compensation	420
6.7.5 PID Compensation	426
6.7.6 Design Considerations	433
6.7.7 Specifications in Terms of the Sensitivity Function	435
6.7.8 Limitations on Design in Terms of the Sensitivity Function	440
6.8 Time Delay	443
6.8.1 Time Delay via the Nyquist Diagram (W)	445
6.9 Alternative Presentation of Data	445
6.9.1 Nichols Chart	445
6.9.2 The Inverse Nyquist Diagram (W)	450
6.10 Historical Perspective	450
Summary	451
Review Questions	453
Problems	454

# 7

## State-Space Design 479

A Perspective on State-Space Design	479
Chapter Overview	480
7.1 Advantages of State-Space	480
7.2 System Description in State-Space	482
7.3 Block Diagrams and State-Space	488
7.4 Analysis of the State Equations	491

	7.4.1	Block Diagrams and Canonical Forms	491
	7.4.2	Dynamic Response from the State Equations	503
	7.5	Control-Law Design for Full-State Feedback	508
	7.5.1	Finding the Control Law	509
	7.5.2	Introducing the Reference Input with Full-State Feedback	518
	7.6	Selection of Pole Locations for Good Design	522
	7.6.1	Dominant Second-Order Poles	522
	7.6.2	Symmetric Root Locus (SRL)	524
	7.6.3	Comments on the Methods	533
	7.7	Estimator Design	534
	7.7.1	Full-Order Estimators	534
	7.7.2	Reduced-Order Estimators	540
	7.7.3	Estimator Pole Selection	544
	7.8	Compensator Design: Combined Control Law and Estimator (W)	547
	7.9	Introduction of the Reference Input with the Estimator (W)	559
	7.9.1	General Structure for the Reference Input	561
	7.9.2	Selecting the Gain	570
	7.10	Integral Control and Robust Tracking	571
	7.10.1	Integral Control	571
Δ	7.10.2	Robust Tracking Control: The Error-Space Approach	573
Δ	7.10.3	Model-Following Design	585
Δ	7.10.4	The Extended Estimator	589
Δ	7.11	Loop Transfer Recovery	592
Δ	7.12	Direct Design with Rational Transfer Functions	598
Δ	7.13	Design for Systems with Pure Time Delay	602
	7.14	Solution of State Equations (W)	605
	7.15	Historical Perspective	607
		Summary	608
		Review Questions	611
		Problems	612

## 8

### Digital Control 636

		A Perspective on Digital Control	636
		Chapter Overview	636
	8.1	Digitization	637
	8.2	Dynamic Analysis of Discrete Systems	640
	8.2.1	$z$ -Transform	640
	8.2.2	$z$ -Transform Inversion	641

	8.2.3	Relationship Between $s$ and $z$	643
	8.2.4	Final Value Theorem	645
8.3		Design Using Discrete Equivalents	647
	8.3.1	Tustin's Method	647
	8.3.2	Zero-Order Hold (ZOH) Method	651
	8.3.3	Matched Pole-Zero (MPZ) Method	653
	8.3.4	Modified Matched Pole-Zero (MMPZ) Method	657
	8.3.5	Comparison of Digital Approximation Methods	658
	8.3.6	Applicability Limits of the Discrete Equivalent Design Method	659
8.4		Hardware Characteristics	659
	8.4.1	Analog-to-Digital (A/D) Converters	660
	8.4.2	Digital-to-Analog Converters	660
	8.4.3	Anti-Alias Prefilters	661
	8.4.4	The Computer	662
8.5		Sample-Rate Selection	663
	8.5.1	Tracking Effectiveness	664
	8.5.2	Disturbance Rejection	665
	8.5.3	Effect of Anti-Alias Prefilter	665
	8.5.4	Asynchronous Sampling	666
Δ 8.6		Discrete Design	666
	8.6.1	Analysis Tools	667
	8.6.2	Feedback Properties	668
	8.6.3	Discrete Design Example	670
	8.6.4	Discrete Analysis of Designs	672
8.7		Discrete State-Space Design Methods (W)	674
8.8		Historical Perspective	674
		Summary	675
		Review Questions	677
		Problems	677

## 9 Nonlinear Systems 683

		A Perspective on Nonlinear Systems	683
		Chapter Overview	684
9.1		Introduction and Motivation: Why Study Nonlinear Systems?	685
9.2		Analysis by Linearization	687
	9.2.1	Linearization by Small-Signal Analysis	687
	9.2.2	Linearization by Nonlinear Feedback	692
	9.2.3	Linearization by Inverse Nonlinearity	693
9.3		Equivalent Gain Analysis Using the Root Locus	694
	9.3.1	Integrator Antiwindup	701

9.4	Equivalent Gain Analysis Using Frequency Response: Describing Functions	706
9.4.1	Stability Analysis Using Describing Functions	712
Δ 9.5	Analysis and Design Based on Stability	716
9.5.1	The Phase Plane	717
9.5.2	Lyapunov Stability Analysis	723
9.5.3	The Circle Criterion	731
9.6	Historical Perspective	737
	Summary	738
	Review Questions	739
	Problems	739

# 10

## Control System Design: Principles and Case Studies 751

	A Perspective on Design Principles	751
	Chapter Overview	751
10.1	An Outline of Control Systems Design	753
10.2	Design of a Satellite's Attitude Control	759
10.3	Lateral and Longitudinal Control of a Boeing 747	777
10.3.1	Yaw Damper	782
10.3.2	Altitude-Hold Autopilot	789
10.4	Control of the Fuel–Air Ratio in an Automotive Engine	795
10.5	Control of a Quadrotor Drone	803
10.6	Control of RTP Systems in Semiconductor Wafer Manufacturing	819
10.7	Chemotaxis, or How <i>E. Coli</i> Swims Away from Trouble	833
10.8	Historical Perspective	843
	Summary	845
	Review Questions	847
	Problems	847

## Appendix A Laplace Transforms 865

A.1	The $\mathcal{L}$ - Laplace Transform	865
A.1.1	Properties of Laplace Transforms	866
A.1.2	Inverse Laplace Transform by Partial-Fraction Expansion	874
A.1.3	The Initial Value Theorem	877
A.1.4	Final Value Theorem	878

**Appendix B Solutions to the Review Questions 880**

**Appendix C Matlab Commands 897**

**Bibliography 903**

**Index 912**

**List of Appendices on the web at [www.pearsonglobaleditions.com](http://www.pearsonglobaleditions.com)**

**Appendix WA: A Review of Complex Variables**

**Appendix WB: Summary of Matrix Theory**

**Appendix WC: Controllability and Observability**

**Appendix WD: Ackermann's Formula for Pole Placement**

**Appendix W2.1.4: Complex Mechanical Systems**

**Appendix W3.2.3: Mason's Rule and the Signal-Flow Graph**

**Appendix W.3.6.3.1: Routh Special Cases**

**Appendix W3.7: System Identification**

**Appendix W3.8: Amplitude and Time Scaling**

**Appendix W4.1.4.1: The Filtered Case**

**Appendix W4.2.2.1: Truxal's Formula for the Error Constants**

**Appendix W4.5: Introduction to Digital Control**

**Appendix W4.6: Sensitivity of Time Response to Parameter Change**

**Appendix W5.4.4: Analog and Digital Implementations**

**Appendix W5.6.3: Root Locus with Time Delay**

**Appendix W6.7.2: Digital Implementation of Example 6.15**

**Appendix W6.8.1: Time Delay via the Nyquist Diagram**

**Appendix W6.9.2: The Inverse Nyquist Diagram**

**Appendix W7.8: Digital Implementation of Example 7.31**

**Appendix W7.9: Digital Implementation of Example 7.33**

**Appendix W7.14: Solution of State Equations**

**Appendix W8.7: Discrete State-Space Design Methods**