482 نموذج اسئلة و اجابة مادة التحكم الآلى م

Benha University
College of Engineering at Benha
Mechanical Eng. Dept.

4^{th} Year Mechanics

Subject :Automatic Control M482 **Date: 28/5/2016**

Questions For Final Examination

Examiner : Dr. Mohamed Elsharnoby

Time :180 min.

Attempt all questions, Number of questions = 4, Number of pages = 2

1-a) For the block diagram shown in Figure 1, draw the equivalent signal flow graph using 5 nodes: input, output, and nodes a, b, and c.

Use masson rule to find the transfer function of the system.

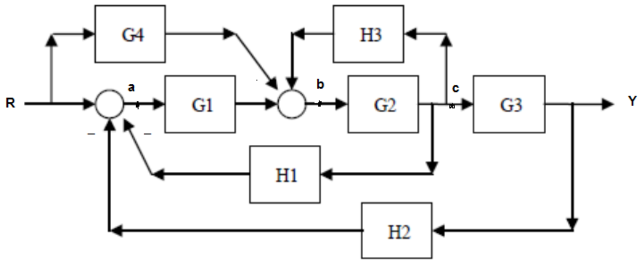

Figure 1

1-b) Consider the system below in figure 2 and **let p=0**.

i) Determine conditions on K and z so that the system is stable.

ii) Determine all possible conditions on K and z so that the system will be marginally stable

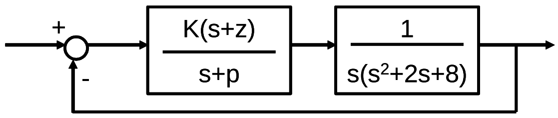

Figure 2

2- a) Consider the block diagram in figure 3.

(a) With $G_c(s) = 1$, r(t)=0, and d(t)=unit step, find the range of gain K such that the steady state output due to the disturbance d(t) is 0.05d(t).

(b) Let d(t)=0. With $KG_c(s) = 18$, find the steady state step error. Also find the steady state ramp error.

(c) What effect would $G_c(s) = \frac{1}{s}$ have on the steady state errors? Note: check the root locus first.

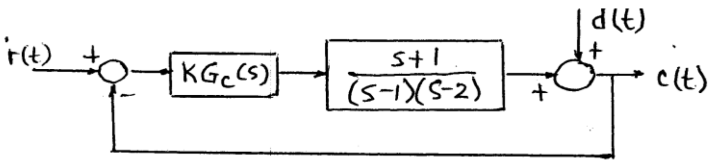

Figure 3

For the system given, find the jw-axis crossing point and the corresponding value of K.

b) User the Routh-Hurwitz criteria to determine the number of roots in the left half complex plane, the right half plane, and on the jw-axis for each of the following polynomials **.**

i- $d(s) = s^5 + s^4 + 2s^3 + 2s^2 + s + 1$

ii- $d(s) = s^4 + 9s^3 + 45s^2 + 87s + 50$

iii- $d(s) = s^6 + 5s^5 + 14s^4 + 40s^3 + 64s^2 + 80s + 96$

3-a)

Hand sketch the root locus of $1 + KG(s) = 0$ as K varies from 0 to $+\infty$, where

$$G(s) = \frac{s+2}{s(s+1)(s+3)^2}$$

Make sure you provide verbal description on the following: open-loop pole/zero map; real axis decision; and asymptotes.

3-b) For the control system shown in Fig.4, find the following :

i) The damping ratio, ζ.

ii) The settling time in response to a step input.

iii) c(t), t > 0 for r is unit step and c(0) = 0

iv) The steady state output in response to r(t) = cos 2t.

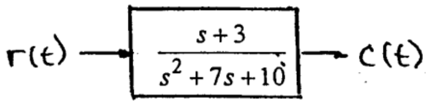

Figure 4

4-a) Given the straight line Bode diagram of magnitude in figure5, find the corresponding transfer function.

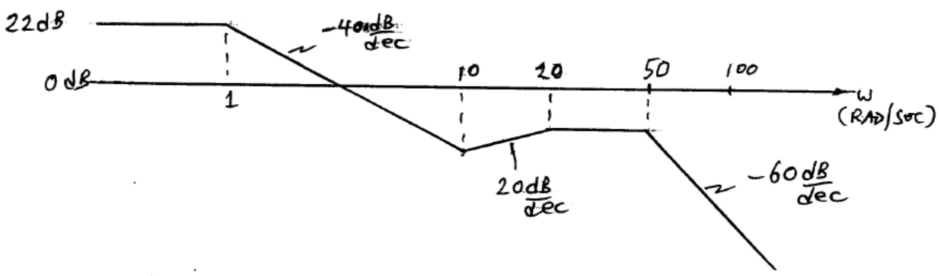

Figure 5

4-b) For the system given below in figure 6, estimate the values of K and K_t so that a maximum percentage overshoot of 9.6% and a settling time of 0.05 sec for a tolerance band of 1% are achieved.

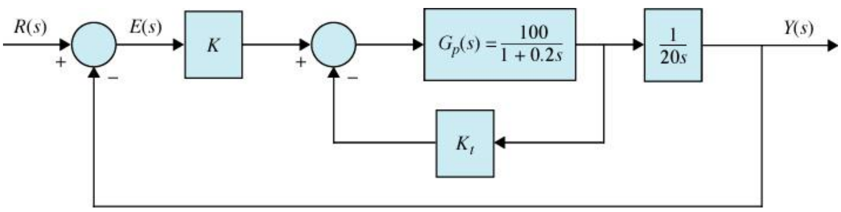

Figure 6

c) Consider the standard feedback system shown below in figure 7.

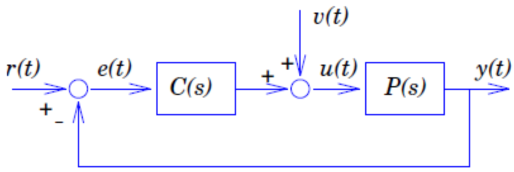

Figure 7

Let the transfer function of the plant is $G_p(s) = \dfrac{1}{s(s+5)}$,

Design a PI controller whose T.F of the form $Gc(s) = k_p + \dfrac{k_i}{s}$ such that

such that the closed loop system is stable with one pole at $r_1 = -4$ and the other two poles are at $r_{2,3} = -\zeta\omega_o \pm j\omega_o\sqrt{1-\zeta^2}$ with $\omega_o \geq 2$, $\zeta > 0$, and ζ is as large as possible.

Draw the Bode plots of the system with and without controller.

Good Luck

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Model Answer of The Final Corrective Exam

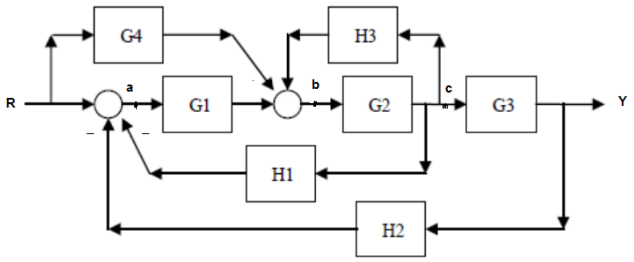
Elaborated by: Dr. Mohamed Elsharnoby

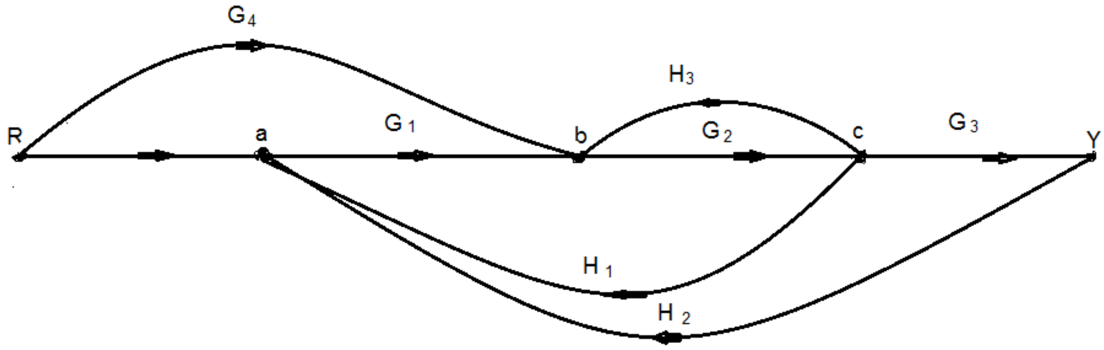
نموذج الاجابة لمادة : التحكم الآلى م 482

التاريخ السبت 28 مايو 2016

أستاذ المادة : د. محمد عبد اللطيف الشرنوبى

1-a)





Loops

$L_1 = -G_1G_2H_1$ $L_2 = - G_1G_2G_3H_2$ $L_3 = - G_2H_3$

Paths

$M_1 = G_1G_2G_3$ $M_2 = G_4G_2G_3$

$\Delta = 1 + G_1G_2H_1 + G_1G_2G_3H_2 + G_2H_3$

$\Delta_1 = 1$

$\Delta_2 = 1$

$TF = (M_1 \Delta_1 + M_2 \Delta_2)/ \Delta = (G_1G_2G_3+ G_4G_2G_3)/(1 + G_1G_2H_1 + G_1G_2G_3H_2 + G_2H_3)$

1-b)

FOR P=0, the characteristic equation is given by:

$S^2(S^2+2S+8) + K(S+Z) = 0$

$S^4+2S^3+8S^2+KS+KZ=0$

Construct the Huwarth array

s^4	1	8	KZ
s^3	2	K	0
s^2	(16-k)/2	KZ	0
s	$\frac{(16k-k^2-2kz)(2)}{16-k}$	0	
s^0	kz		

For stable systen

$16 > K > 0$, $Z>0$

$\frac{(16k-k^2-2kz)(2)}{16-k} > 0$

$16-K-2z > 0$

$16 > k + 2z$

ii For marginally stable system

Put $S = j\omega$

$\omega^4 -2j\omega^3-8\omega^2+jk\omega +kz=0$

$-2\omega^3+k\omega = 0$ $\qquad k=2\omega^2$

$\omega^4 -8\omega^2+kz=0$

$\omega^4 +(2z-8)\omega^2+ =0$

$\omega^4 +(2z-8)\omega^2+ =0$ $\quad \omega=0.$ $\quad \omega=\pm (8-2z)^{1/2}$ $\quad$, $K = 16-4z$

$4 > z >0$, $16 > k > 0$

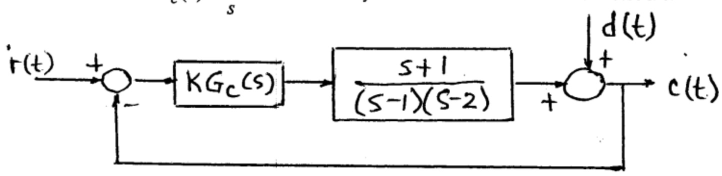
2-a)

Consider the block diagram below.

(a) With $G_c(s) = 1$, r(t)=0, and d(t)=unit step, find the range of gain K such that the steady state output due to the disturbance d(t) is 0.05d(t).

(b) Let d(t)=0. With $KG_c(s) = 18$, find the steady state step error. Also find the steady state ramp error.

(c) What effect would $G_c(s) = \frac{1}{s}$ have on the steady state errors? Note: check the root locus first.



$$\frac{C(s)}{D(s)} = \frac{1}{1 + \frac{K(s+1)}{(s-1)(s-2)}} = \frac{(s-1)(s-2)}{(s-1)(s-2) + K(s+1)} \qquad D(s) = \frac{1}{s}$$

$$\lim_{s\to 0} sC(s) = \lim_{s\to 0} \frac{(s-1)(s-2)}{(s-1)(s-2) + K(s+1)} = \frac{2}{2+K} = 0.05$$

$$\Rightarrow \quad 40 = 2 + K \Rightarrow \boxed{K = 38}$$

b) $$K_p = \lim_{s\to 0} KG_c(s)G_p(s) = \lim_{s\to 0} \frac{18(s+1)}{(s-1)(s-2)} = 9$$

$$e_{ss\,step} = \frac{1}{1+K_p} = \frac{1}{10} = \boxed{0.1 = e_{ss\,step}}$$

$e_{ss\,ramp} = \infty$ FOR A TYPE 0 CONTROL SYSTEM. TO SEE THIS,

$$K_v = \lim_{s\to 0} sKG_c(s)G_p(s) = \lim_{s\to 0} s\frac{18(s+1)}{(s-1)(s-2)} = 0$$

$$e_{ss\,ramp} = \frac{1}{K_v} = \infty$$

$$e_{ss} = \lim_{s\to 0} sE(s)$$

$$\frac{E(s)}{R(s)} = \frac{1}{1 + \frac{18(s+1)}{(s-1)(s-2)}} = \frac{(s-1)(s-2)}{(s-1)(s-2) + 18(s+1)}$$

$$e_{ss\,STEP} = \lim_{s\to 0} \cancel{s} \frac{(s-1)(s-2)}{(s-1)(s-2)+18(s+1)} \frac{1}{\cancel{s}} = \frac{2}{20} = \frac{1}{10} = 0.1.$$

$$e_{ss\,ramp} = \lim_{s\to 0} \cancel{s} \frac{(s-1)(s-2)}{(s-1)(s-2)+18(s+1)} \cdot \frac{1}{s^{\cancel{2}}} = \lim_{s\to 0} \frac{(s-1)(s-2)}{s[(s-1)(s-2)+18(s+1)]}$$

$$= \infty$$

2-b)

S^5	**1**	**2**	**1**
S^4	**1**	**2**	**1**
S^3	**0**	**0**	
	4	**4**	
S^2	**1**	**1**	
	0	**0**	
S	**2**	**0**	
S^0	**1**		

Stable, Number of poles on the Imaginary line = 4

ii)

s^4	1	45	50
s^3	9	87	0
s^2	35.33	50	
s	74.26	0	
s^0	50		

The system is stable with all four poles on the left half plane

iii)

s^6	1	14	64	96
s^5	5	40	80	0
s^4	6	48	96	
s^3	0	0		
	2 4	96		
s^2	4	16		
s	0	0		
	8	0		
s^0	16			

The system is stable with 2 pole in the LHP and 4 on the imaginary ax

3)

a) Hand sketch the root locus of $1 + KG(s) = 0$ as K varies from 0 to $+\infty$, where

$$G(s) = \frac{s+2}{s(s+1)(s+3)^2}$$

→ open loop poles are 0, −1, −3, −3

" " zero are −2 =

Number of asymptotes are $n - m = 3$

asymptotes angle $= \frac{(2K+1)\pi}{3} = 60^\circ, 180^\circ, 300^\circ$.

Intersection of asymptotes on real axis

$$\alpha = \frac{\sum \text{poles} - \sum \text{zeros}}{n-m} = \frac{-1, -3-3+2}{3} = \frac{-5}{3}$$

The characteristic eqn. is

$$1 + K\,G(s) = 0 \Rightarrow 1 + \frac{K(s+2)}{(s^2+s)(s^2+6s+9)} = 0$$

$$s^4 + 7s^3 + 15s^2 + 9s + Ks + 2K = 0$$

Construct the array.

s^4	1	15	$2K$
s^3	7	$(9+K)$	0
s^2	$\frac{105-9K-9}{7}$	$2K$	
s	$\frac{(96-9K)(9+K)-98K}{96-9K}$	0	
1	$2K$		

$$96 - 9K > 0 \Rightarrow K < \frac{96}{9}$$

$$(96-9K)(9+K) - 98K > 0 \Rightarrow$$

$$864 - 81K - 98K - 9K^2 > 0$$

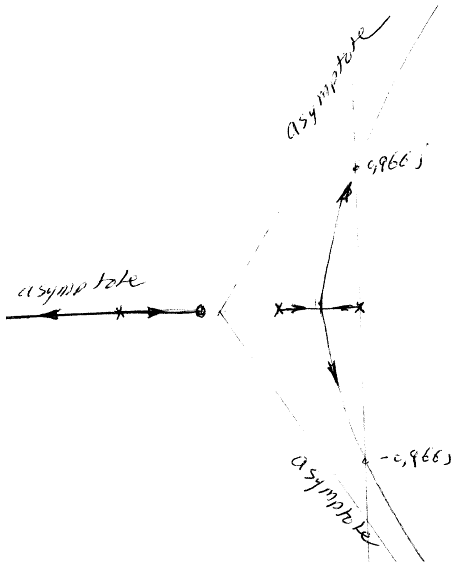
$$864 - 179K - 9K^2 > 0 \quad K \leqslant 4,$$

For $K = 4$

The Auxiliary Eqn. is $\frac{60}{7}s^2 + 8 = 0$

$$s = \pm\sqrt{\frac{14}{15}}\,j \qquad \text{points intersect The Imaginary line.}$$

$$= \pm\, 0{,}966j$$



The root locus

3-b)

$$r(t) \longrightarrow \boxed{\frac{s+3}{s^2+7s+10}} \longrightarrow c(t)$$

i) $2\zeta\omega_n = 7 \quad \omega_n^2 = 10 \Rightarrow \omega_n = \sqrt{10} = 3.16$

ii) $\zeta = \frac{7}{2\omega_n} = \frac{7}{2(3.16)} = \underline{\underline{1.107}} \Rightarrow$ <u>OVERDAMPED</u> SYSTEM

$\Rightarrow$ NEGATIVE, REAL, DISTINCT ROOTS.

$s^2 + 7s + 10 = (s+5)(s+2) \Rightarrow \tau_1 = \frac{1}{5}, \; \tau_2 = \frac{1}{2}$

$T_s = 4\tau_{max} = 4\left(\frac{1}{2}\right) = \underline{\underline{2 \text{ sec}}}$

iii) $C(s) = \frac{s+3}{s(s+2)(s+5)} = \frac{A}{s} + \frac{B}{s+2} + \frac{C}{s+5}$

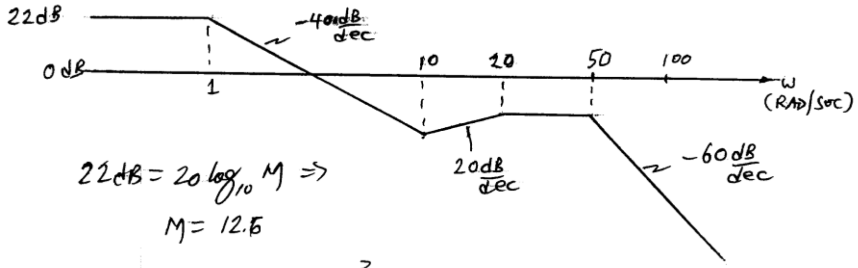
$A = \left.\frac{s+3}{(s+2)(s+5)}\right|_{s=0} = \frac{3}{10}; \quad B = \left.\frac{s+3}{s(s+5)}\right|_{s=-2} = \frac{1}{-2(3)} = -$

$C = \left.\frac{s+3}{s(s+2)}\right|_{s=-5} = \frac{-2}{-5(-3)} = -\frac{2}{15}$

$c(t) = \frac{3}{10} - \frac{1}{6}e^{-2t} - \frac{2}{15}e^{-5t}, \; t \geq 0$

iv) $C_{ss} = \left|\frac{3+j2}{(5+j2)(2+j2)}\right| \cos(2t+\theta), \quad \theta = \tan^{-1}\frac{2}{3} - \tan^{-1}\frac{2}{5} - \tan^{-1}\frac{2}{2}$

4-a)



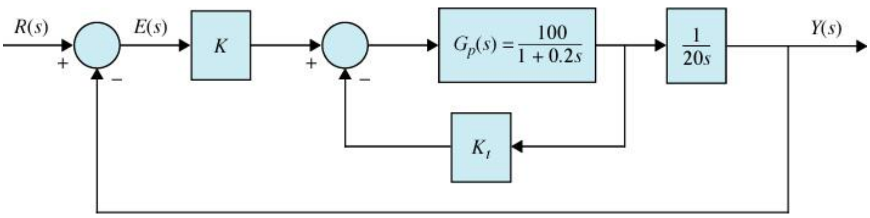
$$22\,dB = 20\log_{10} M \Rightarrow$$

$$M = 12.6$$

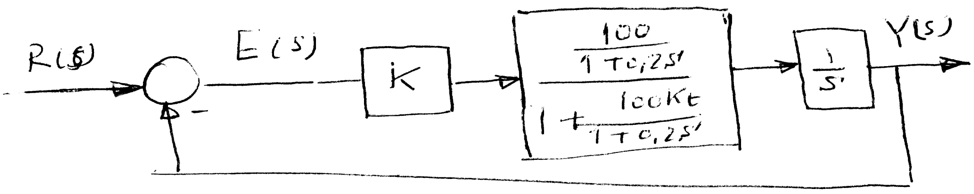
$$\frac{12.6\left(1+\frac{s}{10}\right)^3}{\left(1+\frac{s}{1}\right)^2\left(1+\frac{s}{20}\right)\left(1+\frac{s}{50}\right)^3}$$

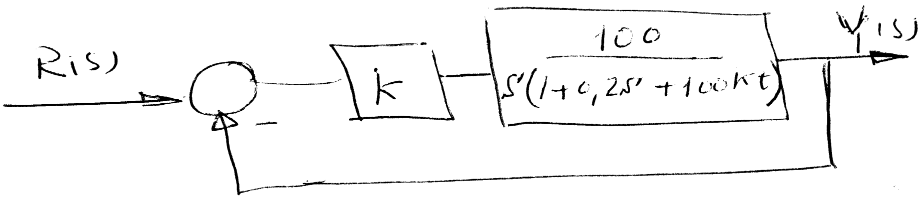
4 - b)

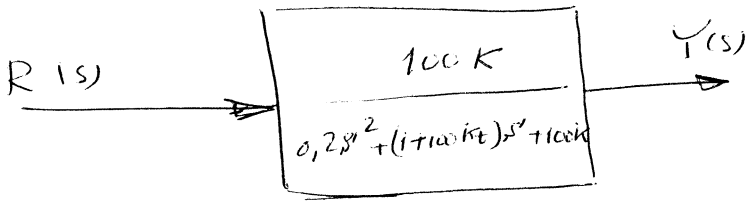
For the system given below in figure 5, estimate the values of K and K_t so that a maximum percentage overshoot of 9.6% and a settling time of 0.05 sec for a tolerance band of 1% are achieved.

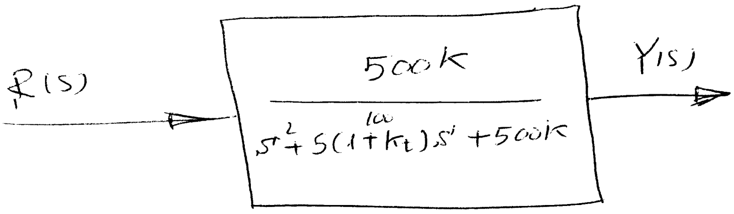


The system is reduced to









$$\omega_n^2 = 500K$$
$$2\zeta\omega_n = (5 + 500K_t)$$

for 1% settling time we know

$$t_s = \frac{4.6}{\zeta\omega_n} = 0,05$$

$$\therefore \zeta\omega_n = 92$$

$$\boxed{\therefore K_t = 0,358}$$

$$M_p = \frac{1}{2\zeta\sqrt{1-\zeta^2}} = 0.096$$

$$= e^{-\pi\zeta/\sqrt{1-\zeta^2}} = 0,096$$

$$\zeta = 0,5979 \Longrightarrow \omega_n = 153.87$$

$$\boxed{K = \frac{\omega_n^2}{500} = 47.35}$$

c) Consider the standard feedback system shown below in figure 6.

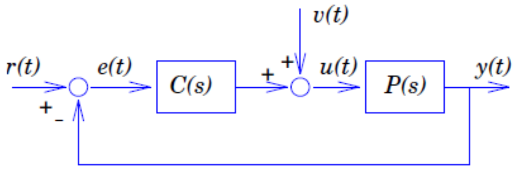
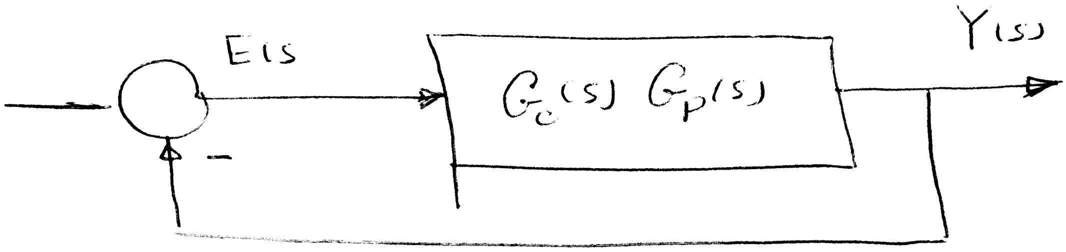


Figure 6



The characteristic Eqn. is given by:

$$1 + G_c(s)\,G_p(s) = 0$$

$$1 + \frac{K_p s + K_i}{s}\,\frac{1}{(s^2+5s)} = 0$$

$$s^3 + 5s^2 + K_p s + K_i = 0$$

$s = -4$ satisfies the eqn.

$$-64 + 80 - 4K_p + K_i = 0$$

$$16 - 4K_p + K_i = 0$$

$$K_i = 4K_p - 16$$

$$s^3 + 5s^2 + K_p s + 4K_p - 16 = 0$$

$K_p > 4$

$$(s^3 + 4s^2) + (s^2 - 16) + K_p(s+4) = 0$$

$$s^2(s+4) + (s+4)(s-4) + K_p(s+4) = 0$$

$$(s+4)\left[s^2 + s + (K_p - 4)\right] = 0$$

$$r_{2,3} = \frac{-1 \pm \sqrt{1 + 16 - 4K_p}}{2}$$

$$-\frac{1}{2} \pm j\sqrt{K_p - \frac{17}{4}} = -\xi\omega_n \pm j\,\omega_n\sqrt{1-\xi^2}$$

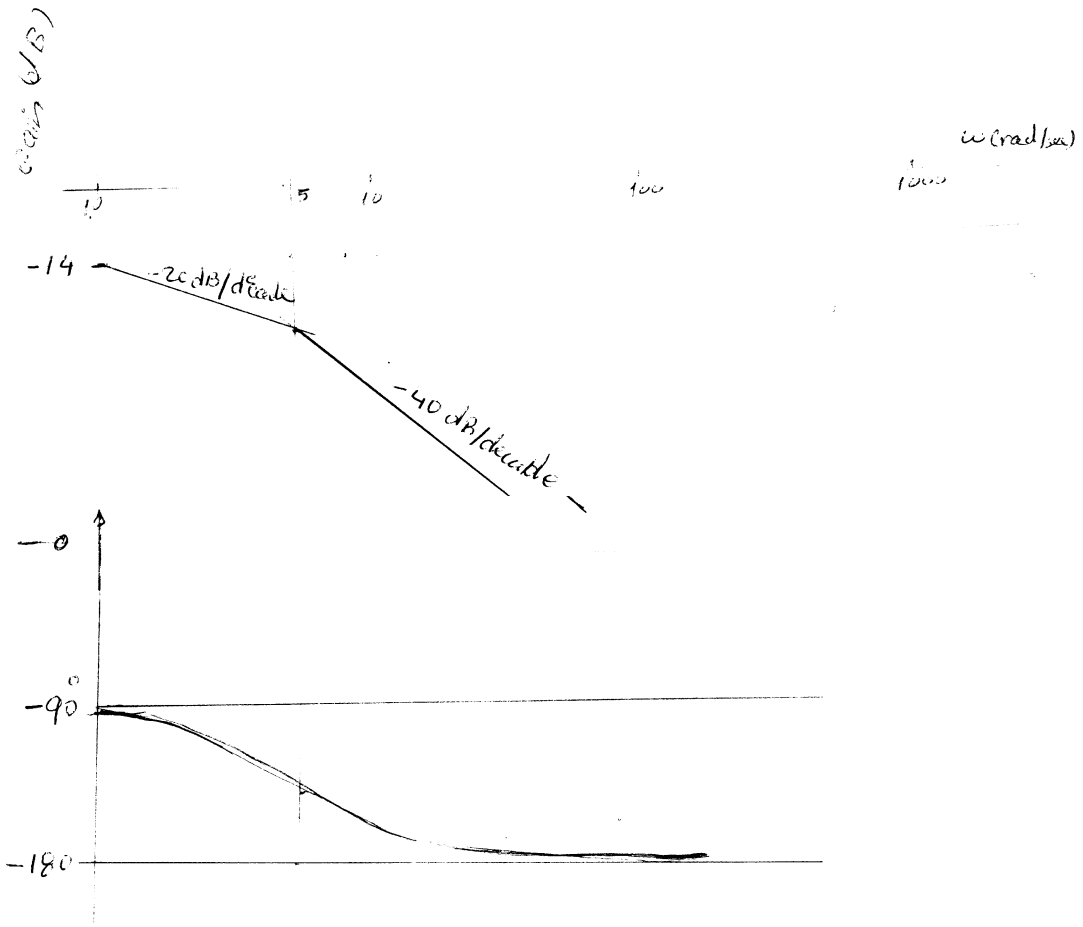
choose $\omega_n = 2 \longrightarrow \xi = 0.25$

$$4(1-\xi^2) = K_p - \frac{17}{4} \Rightarrow \frac{15}{4} + \frac{17}{4} = K_p \Rightarrow$$

$$\boxed{K_p = 8}$$

The transfer function $\frac{1}{s'(s+5)}$

$$= \frac{1}{5} \frac{1}{(s')} \frac{1}{(0,2s+1)}$$



The required B0de diagram