Contents

1 Introduction to Linear Feedback Controls 1
1.1 What are Feedback Control Systems? 4
1.2 Some Terminology 6
1.3 Design of Feedback Control Systems 8
1.4 Two-Point Control 10

2 Systems and Signals 15
2.1 Example First-Order System: The RC-Lowpass 17
2.2 Example Second-Order System: The Spring-Mass-Damper System . 19
2.3 Obtaining the System Response from a Step Input 20
2.4 State-Space Models 22
2.5 Systems and Signals in Scilab 24

3 Solving Differential Equations in the Laplace Domain 27
3.1 The Laplace Transform 27
3.2 Fourier Series and the Fourier Transform 32
3.3 Representation of the RC Lowpass and Spring-Mass-Damper Systems in the Laplace Domain 37
3.4 Transient and Steady-State Response 41
3.5 Partial Fraction Expansion 45
3.5.1 Partial Fraction Expansion Examples 47
3.5.2 Partial Fraction Expansion in Scilab 51
3.6 Building Blocks of Linear Systems 52
3.6.1 Gain Blocks 52
3.6.2 Differentiators 53
3.6.3 Integrators 53
3.6.4 Phase-Lag System, First-Order Lowpass 54
3.6.5 First-Order Highpass 54
3.6.6 PD System or Phase-Lead Compensator 55
3.6.7 Allpass Compensator 56
3.6.8 Second-Order System 56

3.6.9 Dead-Time System (Time-Delay System) 57

4 Time-Discrete Systems 59
4.1 Analog-to-Digital Conversion and the Zero-Order Hold 60
4.2 The *z*-Transform 63
4.3 The Relationship between Laplace- and z-domains 68
4.4 The *w*-Transform 72
4.5 Building Blocks for Digital Controllers 73
4.5.1 Gain Block 74
4.5.2 Differentiator 75
4.5.3 Integrator 75
4.5.4 PID Controller 76
4.5.5 Time-Lag System 77
4.5.6 Time-Lead System 78
4.5.7 Lead-Lag Compensator 78

5 First Comprehensive Example:
The Temperature-Controlled Waterbath 81
5.1 Mathematical Model of the Process 82
5.2 Determination of the System Coefficients 83
5.3 Determining the Transfer Function – General Remarks 87
5.4 Introducing Feedback Control 88
5.5 Comparison of the Open-Loop and Closed-Loop Systems 90

6 Laplace- and *z*-Domain Description of the Waterbath Example 93
6.1 Laplace-Domain Description of the Process 93
6.2 The Closed-Loop System 96
6.3 Sensitivity and Tracking Error 97
6.4 Using a PI-Controller 99
6.5 Time-Discrete Control 103
6.5.1 Time-Discrete Control with the Bilinear Transform 105

7 Block Diagrams:
Formal Graphical Description of Linear Systems 107
7.1 Symbols of a Block Diagram 107
7.2 Block Diagram Manipulation 108
7.3 Block Diagram Simplification Examples 111
7.4 Signal Flow Graphs 115

8 Linearization of Nonlinear Components 119
8.1 Linearization of Components with Analytical Description 120
8.2 Linearization of Tabular Data 122
8.3 Linearization of Components with Graphical Data 124
8.4 Saturation Effects 124

9 A Tale of Two Poles: The Positioner Example and the Significance of the Poles in the *s*-Plane 127
9.1 A Head-Positioning System 128
9.2 Introducing Feedback Control 129
9.3 Dynamic Response of the Closed-Loop System 131
9.4 Dynamic Response Performance Metrics 134
9.5 Time-Integrated Performance Metrics 137
9.6 Feedback Control with a Time-Discrete Controller 140

10 Stability Analysis for Linear Systems 145
10.1 The Routh-Hurwitz Scheme 146
10.2 Routh Arrays for Low-Order Systems 148
10.3 Stability of Time-Discrete Systems with the *w*-Transform 150
10.4 The Jury Test 150
10.5 Jury Arrays for Low-Order Systems 151
10.6 Example Applications 153

11 Frequency-Domain Analysis and Design Methods 157
11.1 Frequency Response of LTI Systems 157
11.2 Frequency Response and Stability 160
11.3 Bode Plots 161
11.4 Definition of Phase and Gain Margin 161
11.5 Construction of Bode Diagrams 164
11.6 Frequency Response of a Second-Order System 166
11.7 Frequency Response of Digital Filters 170
11.8 The Nyquist Stability Criterion 173
11.8.1 The Nyquist Stability Criterion for Time-Discrete Systems . 179
11.8.2 Nyquist Stability in Scilab 181

12 The Root Locus Method 183
12.1 Graphical Construction of Root Locus Plots 184
12.1.1 Prepare the Characteristic Equation in Root-Locus Form . . . 185
12.1.2 Open-Loop Poles and Zeros, and Asymptotes 186
12.1.3 Branches of the Root Locus on the Real Axis 187
12.1.4 Branch-off Points 188
12.1.5 Departure Angles for Complex Poles 189
12.2 Root-Locus Diagrams in Scilab 189
12.3 Design Example: Positioner with PI Control 191
12.4 Design Example: Resonance Reduction 194
12.5 The Root Locus Method for Time-Discrete Systems 198

13 The PID Controller 201
13.1 Intuitive Introduction 201
13.2 Transfer Functions with PID Control 202
13.2.1 PID control of a First-Order Process 203
13.2.2 PID control of a Second-Order Process 204
13.3 Frequency-Domain Aspects of PID Control 207
13.4 Time-Discrete PID Contollers 208
13.5 PID Controller Tuning 212
13.5.1 Iterative Adjustment With an Oscilloscope 212
13.5.2 Ziegler-Nichols Tuning Method 214
13.5.3 Cohen-Coon Tuning Method 215
13.6 Variations and Alternatives of PID Control 215
13.6.1 Integral Windup 215
13.6.2 Nonlinear Processes 216
13.6.3 Pole Cancellation 216
13.7 Conclusion 217

14 Design Examples 219
14.1 Precision Temperature Control 219
14.2 Fast-Tracking Temperature Control 222
14.3 Motor Speed and Position Control 225
14.3.1 Open-Loop Control with Step Motors 225
14.3.2 Closed-Loop Control with DC Motors 228
14.4 Resonant Sine Oscillator 232
14.5 Low-Distortion (HiFi) Amplifiers with Feedback 240
14.6 Phase-Locked Loop Systems 245
14.7 Stabilizing an Unstable System 250

Laplace Correspondence Tables 259

Z-Transform Correspondence Tables 265

Introduction to Operational Amplifiers 269

Relevant Scilab Commands 275

References and Further Reading 277

Glossary 279