

Contents

Preface

- [Feedback Control of Dynamic Systems](#)
- [Copyright](#)
- [Dedication](#)
- [Preface](#)
- [Contents](#)

Chapter 1 An Overview and Brief History of Feedback Control

- [A Perspective on Feedback Control](#)
- [Chapter Overview](#)
- [1.1 A Simple Feedback System](#)
- [1.2 A First Analysis of Feedback](#)
 - [1.2.1 Open-Loop Control](#)
 - [1.2.2 Closed-Loop Control](#)
 - [1.2.3 Feedback Control Feature Video](#)
- [1.3 Feedback System Fundamentals](#)
- [1.4 A Brief History](#)
 - [1.4.1 Beginnings of Control Theory](#)
 - [1.4.2 Frequency Response](#)
 - [1.4.3 PID and On-Off Control](#)
 - [1.4.4 Root Locus](#)
 - [1.4.5 State-variable Design](#)
- [1.5 An Overview of the Book](#)
 - [1.5.1 Chapters](#)
 - [1.5.2 Computer Aided Design](#)
 - [1.5.3 Scope](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 2 Dynamic Models

- [A Perspective on Dynamic Models](#)
- [Chapter Overview](#)

- [2.1 Dynamics of Mechanical Systems](#)
 - [2.1.1 Translational Motion](#)
 - [2.1.2 Rotational Motion](#)
 - [2.1.3 Combined Rotation and Translation](#)
 - [2.1.4 Complex Mechanical Systems \(W\)**](#)
 - [2.1.5 Distributed Parameter Systems](#)
 - [2.1.6 Summary: Developing Equations of Motion for Rigid Bodies](#)
 - [2.1.7 Plant Dynamic Model Video](#)
- [2.2 Models of Electric Circuits](#)
- [2.3 Models of Electromechanical Systems](#)
 - [2.3.1 Loudspeakers](#)
 - [2.3.2 DC Motors](#)
 - [2.3.3 AC Motors](#)
 - [2.3.4 Gears](#)
- [2.4 Heat and Fluid-Flow Models](#)
 - [2.4.1 Heat Flow](#)
 - [2.4.2 Incompressible Fluid Flow](#)
 - [2.4.3 Hydraulic Actuators \(W\)](#)
- [2.5 Historical Perspective](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 3 Dynamic Response

- [A Perspective on System Response](#)
- [Chapter Overview](#)
- [3.1 Review of Laplace Transforms](#)
 - [3.1.1 Response by Convolution](#)
 - [3.1.2 The L- Laplace Transform](#)
 - [3.1.3 Properties of Laplace Transforms](#)
 - [3.1.4 Inverse Laplace Transform by Partial-Fraction Expansion](#)
 - [3.1.5 The Final Value Theorem](#)
 - [3.1.6 Using Laplace Transforms to Solve Differential Equations](#)
 - [3.1.7 Transfer Functions](#)
 - [3.1.8 Poles and Zeros](#)
 - [3.1.9 Linear System Analysis Using Matlab](#)
- [3.2 System Modeling Diagrams](#)

- [3.2.1 The Block Diagram](#)
 - [3.2.2 Block-Diagram Reduction Using Matlab](#)
 - [3.2.3 Block Diagram Reduction in Simulink](#)
 - [3.2.4 Mason's Rule and the Signal Flow Graph \(W\)](#)
- [3.3 Effect of Pole Locations](#)
 - [3.3.1 Effect of Pole Location Video](#)
- [3.4 Time-Domain Specifications](#)
 - [3.4.1 Rise Time](#)
 - [3.4.2 Overshoot and Peak Time](#)
 - [3.4.3 Settling Time](#)
 - [3.4.4 Mapping of Design Specifications to the Complex Plane](#)
- [3.5 Effects of Zeros and Additional Poles](#)
 - [3.5.1 Effects of Zeros](#)
 - [3.5.2 Effect of an Extra Pole](#)
- [3.6 Stability](#)
 - [3.6.1 Bounded Input–Bounded Output Stability](#)
 - [3.6.2 Stability of LTI Systems](#)
 - [3.6.3 Routh's Stability Criterion](#)
- [3.7 Obtaining Models from Experimental Data: System Identification \(W\)](#)
- [3.8 Amplitude and Time Scaling \(W\)](#)
- [3.9 Historical Perspective](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 4 A First Analysis of Feedback

- [A Perspective on the Analysis of Feedback](#)
- [Chapter Overview](#)
- [4.1 The Basic Equations of Control](#)
 - [4.1.1 Stability](#)
 - [4.1.2 Tracking](#)
 - [4.1.3 Regulation](#)
 - [4.1.4 Sensitivity](#)
- [4.2 Control of Steady-State Error to Polynomial Inputs: System Type](#)
 - [4.2.1 System Type for Tracking](#)
 - [4.2.2 System Type for Regulation and Disturbance Rejection](#)
 - [4.2.3 System Type Determination Video](#)
- [4.3 The Three-Term Controller: PID Control](#)
 - [4.3.1 Proportional Control \(P\)](#)
 - [4.3.2 Integral Control \(I\)](#)
 - [4.3.3 Derivative Control \(D\)](#)
- •
- [4.3.2 Integral Control \(I\)](#)
- [4.3.3 Derivative Control \(D\)](#)
- [4.3.4 Proportional Plus Integral Control \(PI\)](#)
- [4.3.5 PID Control](#)
- [4.3.6 Ziegler–Nichols Tuning of the PID Controller](#)
- [4.3.7 AMIGO Tuning Rules for PID Controllers](#)
- [4.3.8 SMIC Tuning Rules for PID Controllers](#)
- [4.4 Feedforward Control by Plant Model Inversion](#)
- [4.5 Introduction to Digital Control](#)
- [4.6 Sensitivity of Time Response to Parameter Change \(W\)](#)
- [4.7 Historical Perspective](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 5 The Root-Locus Design Method

- [A Perspective on the Root-Locus Design Method](#)
- [Chapter Overview](#)
- [5.1 Root Locus of a Basic Feedback System](#)
- [5.2 Guidelines for Determining a Root Locus](#)
 - [5.2.1 Rules for Determining a Positive 180° Root Locus](#)
 - [5.2.2 Summary of the Rules for Determining a Root Locus](#)
 - [5.2.3 Selecting the Parameter Value](#)
- [5.3 Selected Illustrative Root Loci](#)
 - [5.3.1 Double Integrator Plants with Various Derivative Feedback](#)
 - [5.3.2 Double Integrator Plant with Actuator Dynamics](#)
 - [5.3.3 Sensor Collocation Effects](#)
 - [5.3.4 A Locus with Complex Multiple Roots](#)
 - [5.3.5 Root Locus Sketch for 1903 Wright Flyer Video](#)
- [5.4 Design Using Dynamic Compensation](#)
 - [5.4.1 Design Using Lead Compensation](#)
 - [5.4.2 Design Using Lag Compensation](#)
 - [5.4.3 Design Using Notch Compensation](#)
 - [5.4.4 Analog and Digital Implementations \(W\)](#)
- [5.5 Design Examples Using the Root Locus](#)
 - [5.5.1 Control of a Quadrotor Drone](#)
 - [5.5.2 Control of a Mars Helicopter](#)
 - [5.5.3 Control of a Small Airplane](#)
- [5.6 Extensions of the Root-Locus Method](#)
 - [5.6.1 Rules for Plotting a Negative 0° Root Locus](#)
 - [5.6.2 Successive Loop Closure](#)
 - [5.6.3 Time Delay \(W\)](#)
- [5.7 Historical Perspective](#)
- [Summary](#)

Chapter 6 The Frequency-Response Design Method

- [A Perspective on the Frequency-Response Design Method](#)
- [Chapter Overview](#)
- [6.1 Introduction to Frequency Response](#)

- [6.1.1 Frequency Response Using Convolution](#)
 - [6.1.2 Frequency Response Using Laplace](#)
 - [6.1.3 Bode Plot Techniques](#)
 - [6.1.4 Steady-State Errors](#)
- [6.2 Neutral Stability](#)
- [6.3 The Nyquist Stability Criterion](#)
 - [6.3.1 The Argument Principle](#)
 - [6.3.2 Application of The Argument Principle to Control Design](#)
- [6.4 Stability Margins](#)
 - [6.4.1 Bode Sketch and Stability Margin Example Video](#)
- [6.5 Bode's Gain-Phase Relationship](#)

- [6.6 Closed-Loop Frequency Response](#)

- [6.7 Compensation](#)
 - [6.7.1 PD Compensation](#)
 - [6.7.2 Lead Compensation](#)
 - [6.7.3 PI Compensation](#)
 - [6.7.4 Lag Compensation](#)
 - [6.7.5 PID Compensation](#)
 - [6.7.6 Design Considerations](#)
 - [6.7.7 Specifications in Terms of the Sensitivity Function](#)
 - [6.7.8 Limitations on Design in Terms of the Sensitivity Function](#)

- [6.8 Time Delay](#)
 - [6.8.1 Time Delay via the Nyquist Diagram \(W\)](#)

- [6.9 Alternative Presentation of Data](#)
 - [6.9.1 Nichols Chart](#)
 - [6.9.2 The Inverse Nyquist Diagram \(W\)](#)

- [6.10 Historical Perspective](#)

- [Summary](#)

- [Review Questions](#)

- [True False Questions](#)

- [Problems](#)

[Chapter 7 State-Space Design](#)

- [A Perspective on State-Space Design](#)
- [Chapter Overview](#)
- [7.1 Advantages of State-Space](#)
- [7.2 System Description in State-Space](#)
- [7.3 Block Diagrams and State-Space](#)
- [7.4 Analysis of the State Equations](#)
 - [7.4.1 Block Diagrams and Canonical Forms](#)
 - [7.4.2 Dynamic Response from the State Equations](#)
- [7.5 Control-Law Design for Full-State Feedback](#)
 - [7.5.1 Finding the Control Law](#)
 - [7.5.2 Introducing the Reference Input with Full-State Feedback](#)
- [7.6 Selection of Pole Locations for Good Design](#)
 - [7.6.1 Dominant Second-Order Poles](#)
 - [7.6.2 Symmetric Root Locus \(SRL\)](#)

- [7.7 Estimator Design](#)
 - [7.7.1 Full-Order Estimators](#)
 - [7.7.2 Reduced-Order Estimators](#)
 - [7.7.3 Estimator Pole Selection](#)

- [7.8 Compensator Design: Combined Control Law and Estimator](#)

- [7.9 Introduction of the Reference Input with the Estimator](#)
 - [7.9.1 General Structure for the Reference Input](#)
 - [7.9.2 Selecting the Gain](#)

- [7.10 Integral Control and Robust Tracking](#)
 - [7.10.1 Integral Control](#)
 - [7.10.2 Robust Tracking Control: The Error-Space Approach](#)
 - [7.10.3 Model-Following Design](#)
 - [7.10.4 The Extended Estimator](#)

- [7.11 Loop Transfer Recovery](#)

- [7.12 Direct Design with Rational Transfer Function](#)

- [7.13 Design for Systems with Pure Time Delay](#)

- [7.14 Solution of State Equations \(W\)](#)
 - [7.14.1 Solution of State Equations Video](#)

- [7.15 Historical Perspective](#)

- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 8 Control System Design: Principles and Case Studies

- [A Perspective on Design Principles](#)
- [Chapter Overview](#)
- [8.1 An Outline of Control Systems Design](#)
- [8.2 Design of a Satellite's Attitude Control](#)
- [8.3 Lateral and Longitudinal Control of a Boeing](#)
 - [8.3.1 Yaw Damper](#)
 - [8.3.2 Altitude-Hold Autopilot](#)
- [8.4 Control of the Fuel–Air Ratio in an Automotive Engine](#)
- [8.5 Control of a Quadrotor Drone](#)
 - [8.5.1 Hexacopter Example Video](#)
- [8.6 Control of RTP Systems in Semiconductor Wafer Manufacturing](#)
- [8.7 Chemotaxis, or How *E. Coli* Swims from Trouble](#)
- [8.8 Design of an Autonomous Steering System for a Research Vehicle](#)
- [8.9 Historical Perspective](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Chapter 9 Digital Control

- [A Perspective on Digital Control](#)
- [Chapter Overview](#)
- [9.1 Digitization](#)
- [9.2 Dynamic Analysis of Discrete Systems](#)
 - [9.2.1 z-Transform](#)
 - [9.2.2 Discrete Transfer Function of a Sampled Data System](#)
 - [9.2.3 z-Transform Inversion](#)
 - [9.2.4 Relationship Between \$s\$ and \$z\$](#)
 - [9.2.5 Final Value Theorem](#)
- [9.3 Design Using Discrete Equivalents](#)
 - [9.3.1 Tustin's Method](#)
 - [9.3.2 Zero-Order Hold \(ZOH\) Method](#)

- [9.3.3 Matched Pole–Zero \(MPZ\) Method](#)
- [9.3.4 Modified Matched Pole–Zero \(MMPZ\) Method](#)
- [9.3.5 Comparison of Digital Approximation Methods](#)
- [9.3.6 Applicability Limits of the Discrete Equivalent Design Method](#)
- [9.3.7 Equivalent Comparison Video](#)

- [9.4 Hardware Characteristics](#)
 - [9.4.1 Analog-to-Digital \(A/D\) Converters](#)
 - [9.4.2 Digital-to-Analog Converters](#)
 - [9.4.3 Anti-Alias Prefilters](#)
 - [9.4.4 The Computer](#)

- [9.5 Sample-Rate Selection](#)
 - [9.5.1 Tracking Effectiveness](#)
 - [9.5.2 Disturbance Rejection](#)
 - [9.5.3 Effect of Anti-Alias Prefilter](#)
 - [9.5.4 Asynchronous Sampling](#)

- [9.6 Discrete Design](#)
 - [9.6.1 Analysis Tools](#)
 - [9.6.2 Feedback Properties](#)
 - [9.6.3 Discrete Design Example](#)
 - [9.6.4 Discrete Analysis of Designs](#)

- [9.7 Discrete State-Space Design Methods \(W\)](#)

- [9.8 Historical Perspective](#)
 - [Summary](#)
 - [Review Questions](#)
 - [True -False Quiz](#)
 - [Problems](#)

Chapter 10 Nonlinear Systems

- [A Perspective on Nonlinear Systems](#)
- [Chapter Overview](#)
- [10.1 Introduction and Motivation: Why Study Nonlinear Systems?](#)
- [10.2 Analysis by Linearization](#)
 - [10.2.1 Linearization by Small-Signal Analysis](#)
 - [10.2.2 Linearization by Nonlinear Feedback](#)
 - [10.2.3 Linearization by Inverse Nonlinearity](#)
 - [10.2.4 Linearization Example Video](#)

- [10.3 Equivalent Gain Analysis Using the Root Locus](#)
 - [10.3.1 Integrator Antiwindup](#)
- [10.4 Equivalent Gain Analysis Using Frequency Response: Describing Functions](#)
 - [10.4.1 Stability Analysis Using Describing Functions](#)
- [10.5 Analysis and Design Based on Stability](#)
 - [10.5.1 The Phase Plane](#)
 - [10.5.2 Lyapunov Stability Analysis](#)
- [10.6 Historical Perspective](#)
- [Summary](#)
- [Review Questions](#)
- [True False Questions](#)
- [Problems](#)

Appendix A Laplace Transforms

- [A.1 The L- Laplace Transform](#)
 - [A.1.1 Properties of Laplace Transforms](#)
 - [A.1.2 Inverse Laplace Transform by Partial-Fraction Expansion](#)
 - [A.1.3 The Initial Value Theorem](#)
 - [A.1.4 Final Value Theorem](#)

Appendix B Design Aids

Appendix C Matlab Commands

- [10.5.1 The Phase Plane](#)
- [10.5.2 Lyapunov Stability Analysis](#)

Appendix A Laplace Transforms

- [A.1 The L- Laplace Transform](#)
 - [A.1.1 Properties of Laplace Transforms](#)
 - [A.1.2 Inverse Laplace Transform by Partial-Fraction Expansion](#)
 - [A.1.3 The Initial Value Theorem](#)
 - [A.1.4 Final Value Theorem](#)

Appendix B Design Aids

Appendix C Matlab Commands

- [Bibliography](#)

List of Appendices on the web at www.PEI9e.com and www.pearsonhighered.com/engineering-resources

- 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 W2.4.3 Hydraulic Actuators
- Appendix W3.2.4: Mason's Rule and Signal Flow Graph
- Appendix W3.6.3.1: 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 W4.6: 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 W6.8.1: Time Delay via the Nyquist Diagram
- Appendix W6.9.2: The Inverse Nyquist Diagram
- Appendix W7.14: Solution of State Equations
- Appendix W8.4: Control of the Fuel-Air Ratio in an Automotive Engine
- Appendix W8.7 Chemotaxis, A Biological Feedback Example
- Appendix W9.7: Discrete State-Space Design Methods