

2b	$\omega_n=0.5, T_d=0.27\text{sec}, \quad \Theta=1.04\text{rad}, \omega_d=4.33$ $\text{rad/sec}, T_r=0.485, T_p=0.72\text{sec}, T_s=1.6\text{sec}, M_p=16\%, c(t)=1-1.5e^{-2.5t}\sin(4.33t+1.04).$
3a	$G(s)H(s) = \frac{K}{s(s+4)(s+6)}$ (i) Poles $\mathbb{P}$, $s=0, s=0, s=-4, s=-6$ Zeros $s=\infty$ (ii) <u>Asymptotes</u>: $\sigma = \frac{\sum P_0 - \sum Z_0}{N_p - N_z} = \frac{-10}{3}$ $\alpha = \frac{\pm n \times 180}{N_p - N_z} = \frac{\pm n \times 60}{3}$ $= 60^\circ, 180^\circ,$ iii) <u>Break-away point</u>: <u>Characteristic equation</u>: $\frac{K_0}{s(s+4)(s+6)} + 1 = 0$

$$K_0 + s(s+4)(s+6) = 0$$

$$\therefore K_0 = -s(s+4)(s+6)$$

$$K_0 = -s(s^2 + 10s + 24)$$

break-away point $\frac{dK_0}{ds} = -s(2s+10) - 1(s^2 + 10s + 24)$

$$\frac{dK_0}{ds} = 0$$

$$\therefore -s(2s+10) - (s^2 + 10s + 24) = 0$$

$$2s^2 + 10s + s^2 + 10s + 24 = 0$$

$$3s^2 + 20s + 24 = 0$$

$$s = -1.5695 \checkmark \quad s = -5.097 \times \rightarrow \text{Not on root locus}$$

$$K_0 \text{ at } s = -1.5695$$

$$\therefore K_0 = 16.9$$

imaginary-axis intersection :

$$3s^3 + 20s^2 + 24s + K_0 = 0$$

substitute $s = j\omega$.

$$3(j\omega)^3 + 20(j\omega)^2 + 24(j\omega) + K_0 = 0$$

$$-3j\omega^3 + 20j\omega - 20 + K_0 = 0$$

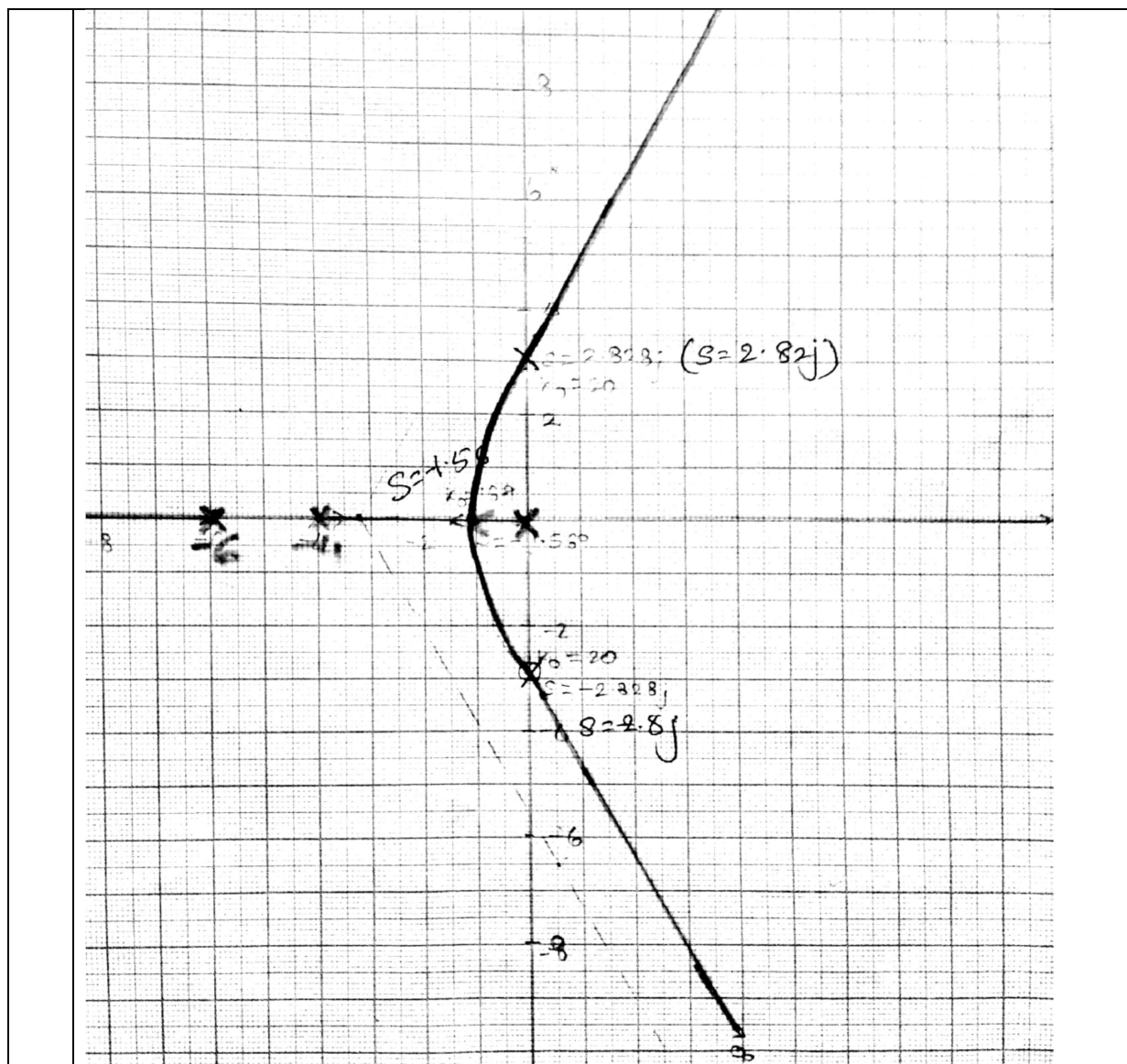
$$-3j\omega^3 = 20j\omega$$

$$K_0 = 20$$

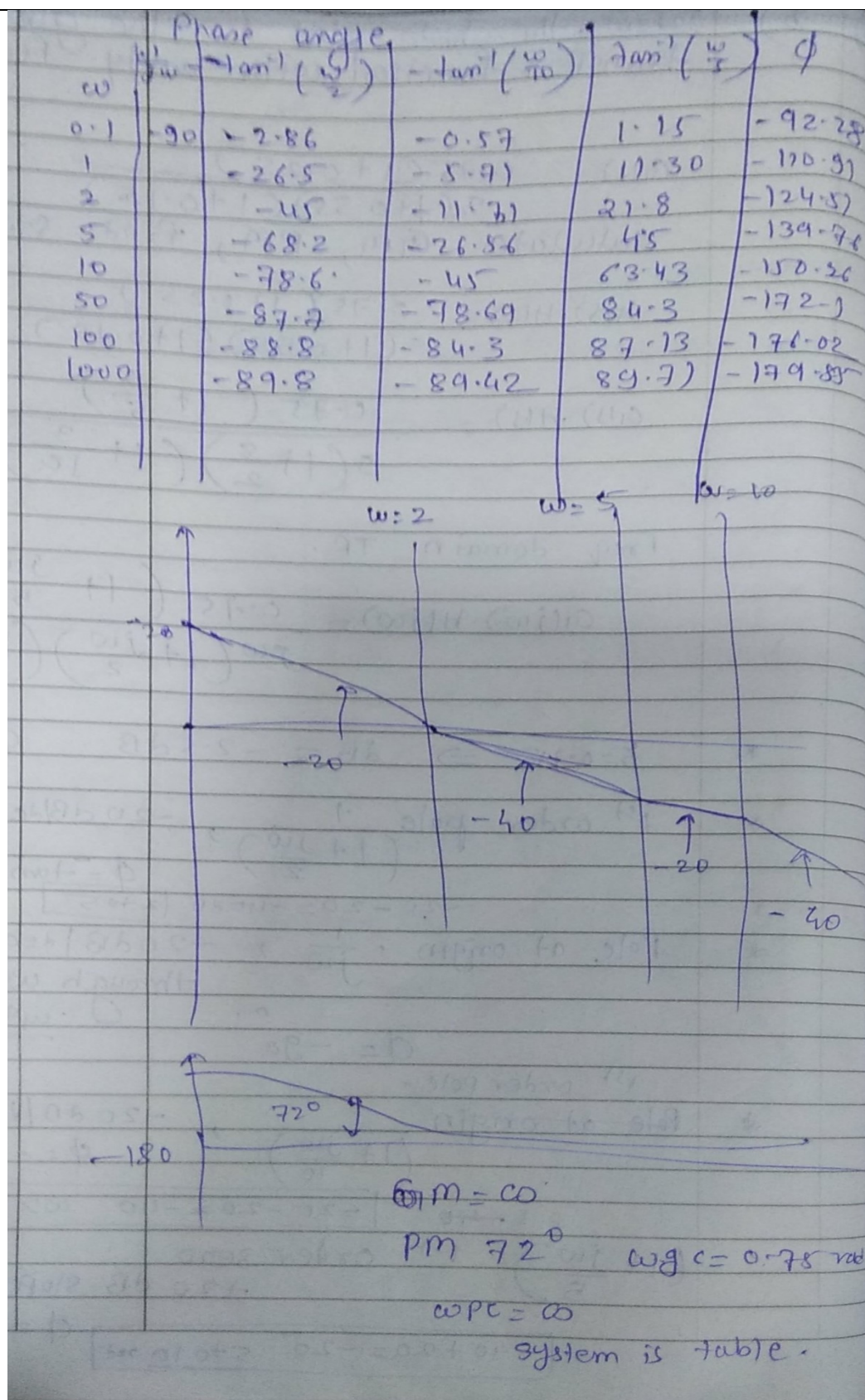
$$\omega^2 = 8$$

$$\omega = \pm 2.828$$

$$z = \pm 2.828$$



3b



4a
ii)

Q2 II)

Using Routh Stability
stability of the system w
eqn 3

$$s^6 + 2s^5 + 8s^4 + 12s^3 + 20s^2 + 16s + 16$$

s^6	1	8	20	16
s^5	2	12	16	0
s^4	2	12	16	0
s^3	0	0	0	0

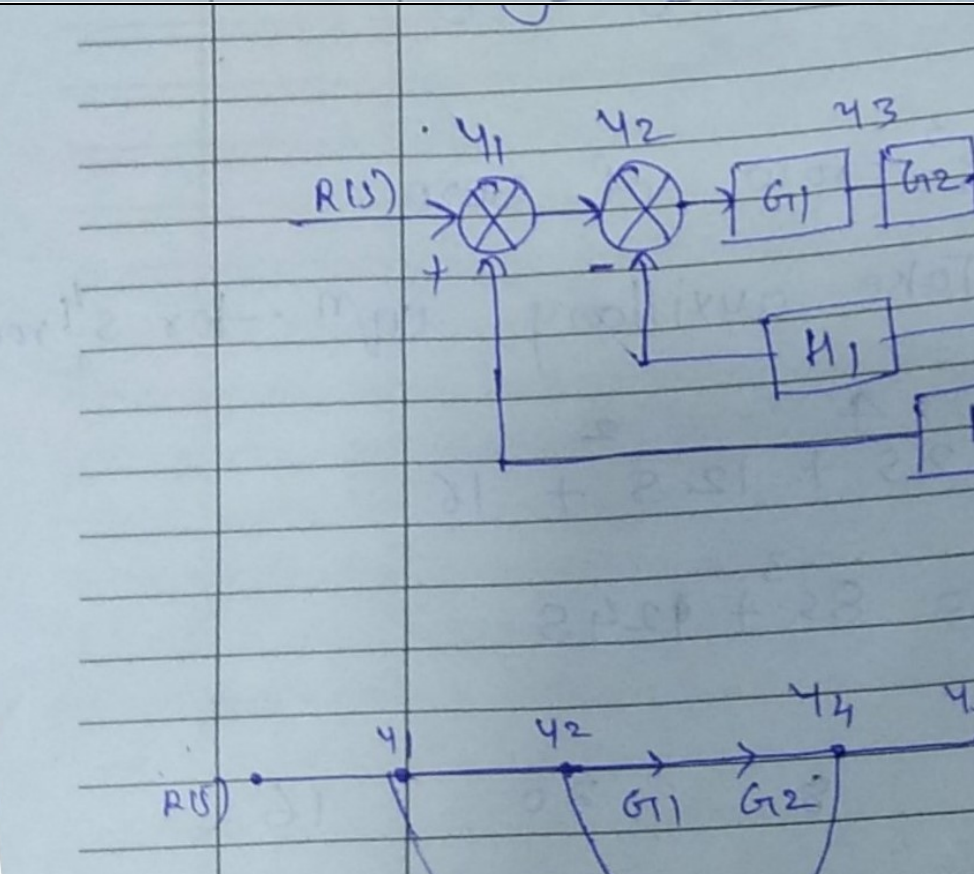
s^3 row of zero

Take auxillary e

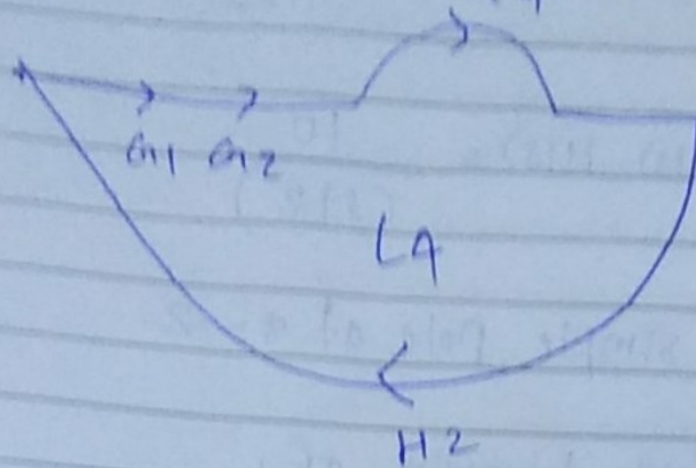
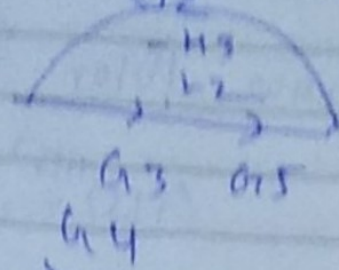
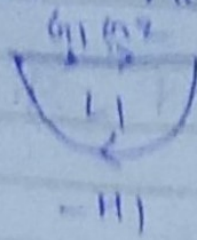
$$A(s) = 2s^4 + 12s^2 + 16$$

$$\frac{dA(s)}{ds} = 8s^3 + 24s$$

s^3	1	8	20
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	<table border="1"> <thead> <tr> <th>for Marks</th><th>Question No.</th></tr> </thead> <tbody> <tr> <td></td><td> Aux. eqn. $2s^4 + 12s^2 + 16 = 0$ $s = \pm j2$ </td></tr> </tbody> </table>	for Marks	Question No.		Aux. eqn. $2s^4 + 12s^2 + 16 = 0$ $s = \pm j2$
for Marks	Question No.				
	Aux. eqn. $2s^4 + 12s^2 + 16 = 0$ $s = \pm j2$				
5a	 The diagram shows a control system with two representations. The top representation is a block diagram where the reference $R(s)$ enters a summing junction at node y_1. The output of y_1 goes to a second summing junction at node y_2. The output of y_2 passes through blocks G_1 and G_2 to reach node y_3. A feedback path from y_3 passes through block H_1 back to node y_1. The bottom representation is a root locus plot on the s-plane. It shows poles at $s = \pm j2$ and $s = \pm j2$ (labeled y_1, y_2, y_4 at the poles) and zeros at $s = \pm j2$ (labeled G_1, G_2 at the zeros). The root locus branches are shown as vertical lines connecting the poles and zeros.				

Total No of single loop



$$L1) = - G_1 G_2 H_1$$

$$L2) = - G_3 G_5 H_3$$

$$L3) = G_1 G_2 G_3 H_2$$

$$L4) = G_1 G_2 G_4 H_2$$

* No of two non touching

$L1$ & $L2$ are two n

$$\therefore L_{12}^{12} = L1 \times L2 =$$

$$= (-G_1 G_2 H_1) (-G_3 G_5 H_3)$$

(b)

II)

Draw Polar Plot of given

$$G(s)H(s) = \frac{10}{s+2}$$

⇒

$$G(s)H(s) = \frac{10}{(s+2)}$$

Simple pole at $s = -2$

Freq domain tf.

$$G(j\omega) \cdot H(j\omega) = \frac{10 + 0j}{j\omega + 2}$$

$$|H G(j\omega) H(j\omega)| = \frac{10}{\sqrt{4 + \omega^2}}$$

$$\angle G(j\omega) \cdot H(j\omega) = -\tan^{-1}\left(\frac{\omega}{2}\right)$$

$$= -\tan^{-1}\left(\frac{\omega}{2}\right)$$

at $\omega = 0$

