

Industrial Process Control MDP 454

If you have a smart project, you can say "I'm an engineer" ??

Lecture 7

Staff boarder

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Industrial Process Control MDP 454

• Lecture aims:

- Understand the powerful concept of frequency response and its role in control system design
- Understand performance specifications in the frequency domain and relative stability based on gain and phase margins

Frequency Response

- we examined the use of test signals such as a step and a ramp signal.
- In this lecture, we consider the steady-state response of a system to a **sinusoidal input** test signal.
- We will examine the transfer function G(s) when $s = j \omega$ and develop methods for graphically displaying the complex number $G(j\omega)$ as ω varies. The **Bode plot** is one of the most powerful graphical tools for analyzing and designing control systems.
- The **frequency response** of a system is defined as the steady-state response of the system to a sinusoidal input signal. The **sinusoid is a unique** input signal, and the resulting output signal for a linear system, as well as signals throughout the system, is sinusoidal in the steady state; it differs from the input waveform only in amplitude and phase angle.

Poles and Zeros and Transfer Functions

Transfer Function: A

A transfer function is defined as the ratio of the Laplace transform of the output to the input with all initial conditions equal to zero. Transfer functions are defined only for linear time invariant systems.

Considerations: Transfer functions can usually be expressed as the ratio of two polynomials in the complex variable, s.

Factorization:

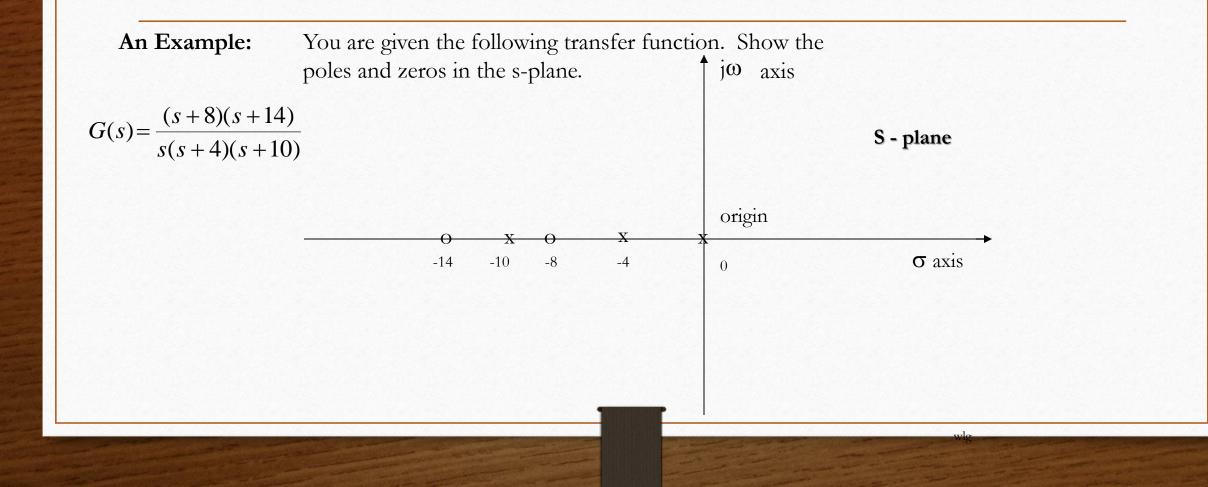
A transfer function can be factored into the following form.

$$G(s) = \frac{K(s+z_1)(s+z_2)...(s+z_m)}{(s+p_1)(s+p_2)...(s+p_n)}$$

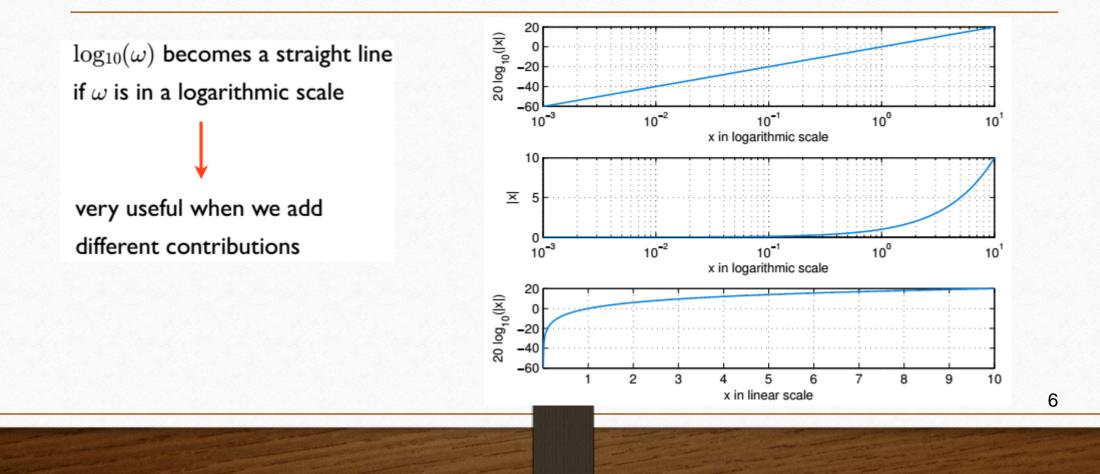
The roots of the numerator polynomial are called zeros.

The roots of the denominator polynomial are called <u>poles</u>.

Poles, Zeros and the S-Plane



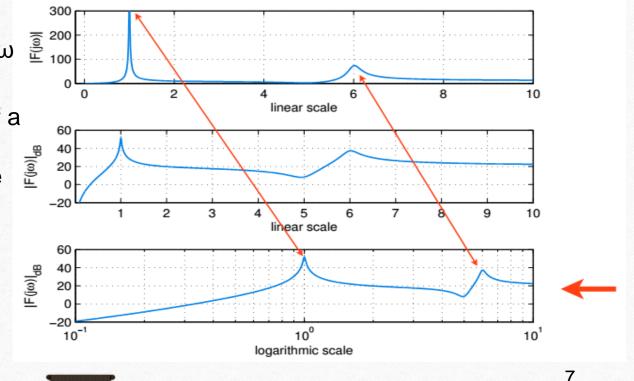
Logarithmic coordinate



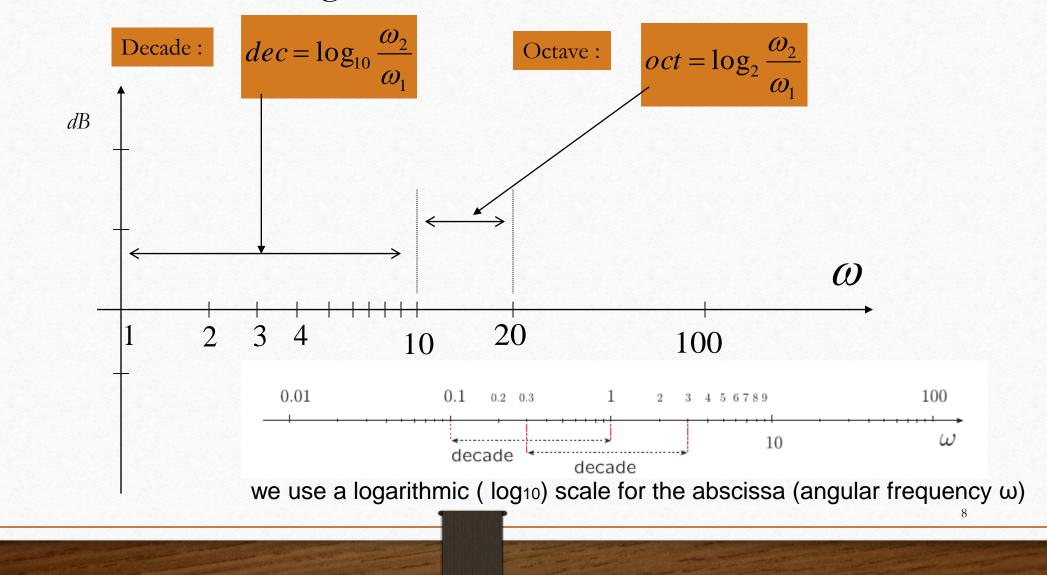
Logarithmic coordinate

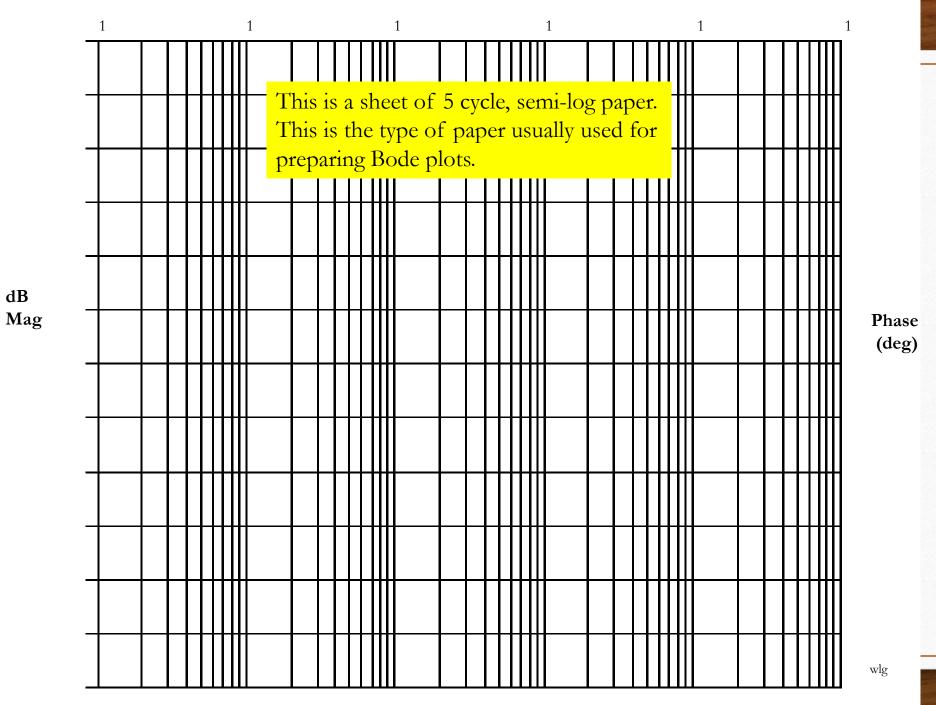
advantages

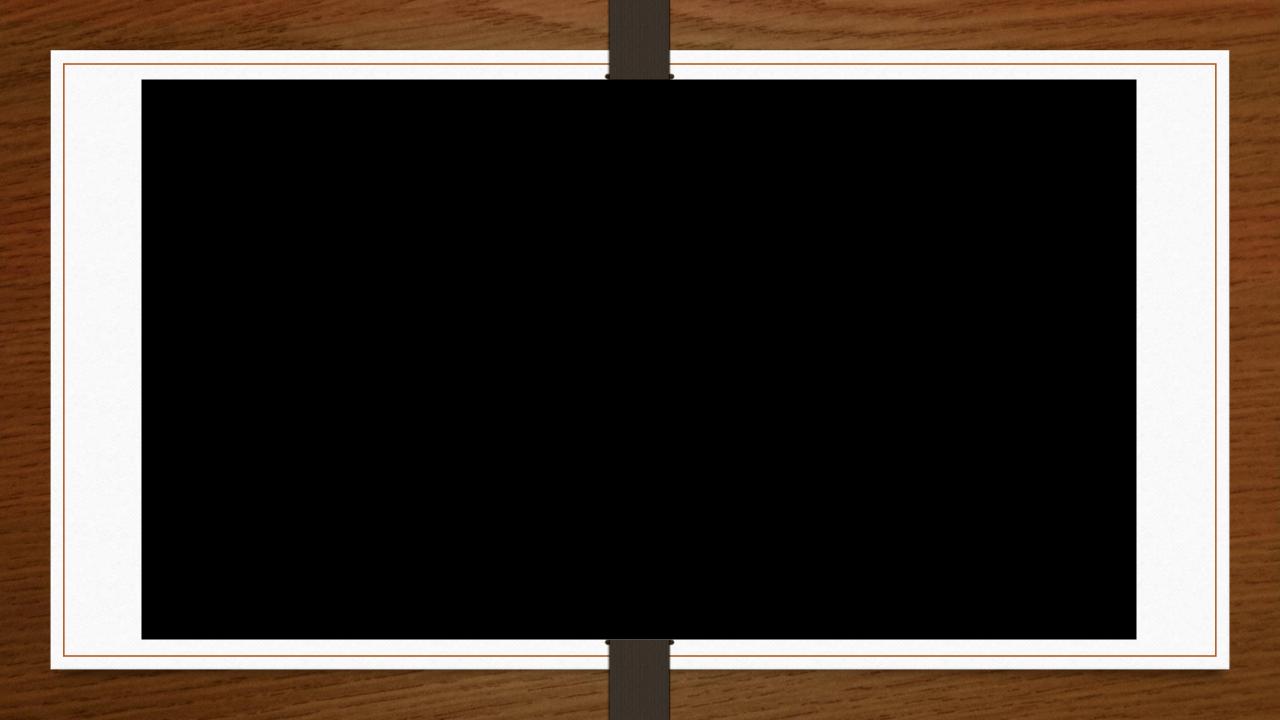
- \bullet quantities can vary in large range (both ω and magnitude)
- easy to build the magnitude plot in dB of a frequency response given in its Bode canonical form from the magnitudes of the single terms
- easy to represent series of systems
- same data different scales for abscissa and ordinates

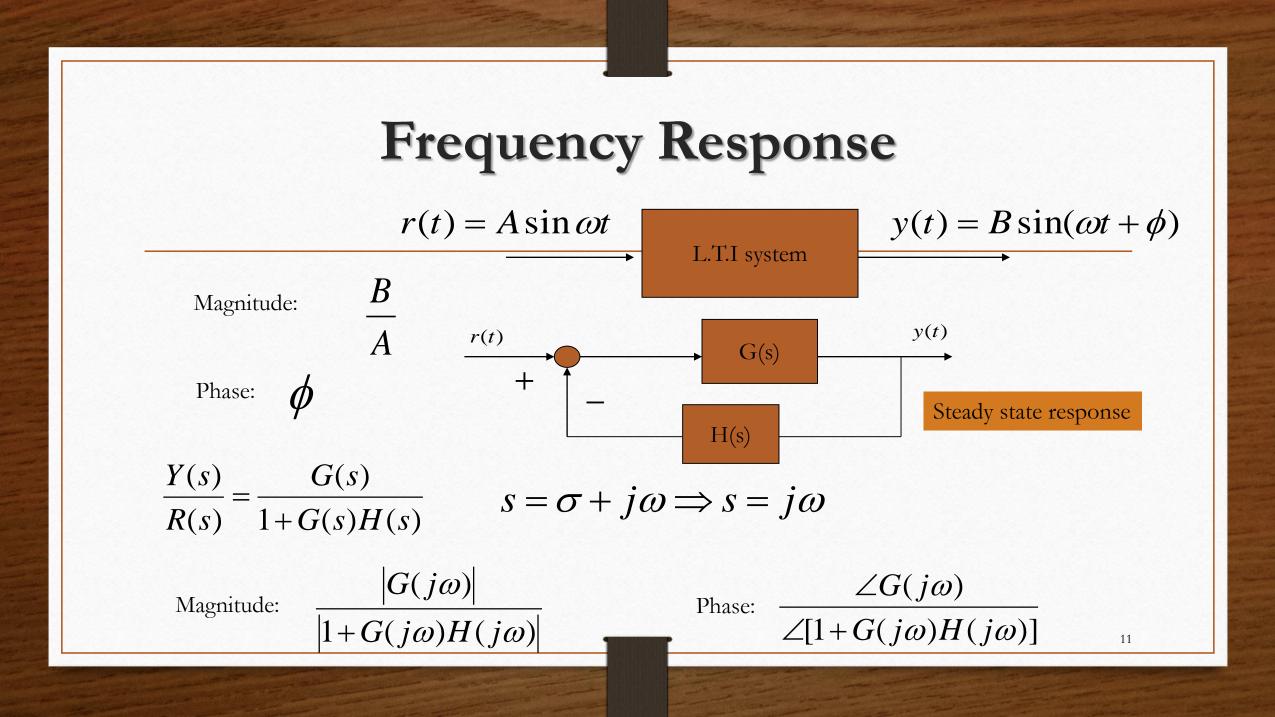


Logarithmic coordinate









Bode Plots

Characterization:

Considering the transfer function of the previous slide. We note that we have 4 different types of terms in the previous general form: These are: $K_{_B}, \frac{1}{s}, \frac{1}{(s/p + 1)}, (s/z + 1)$

 $G(jw) = \frac{K_B(jw/z+1)}{(jw)(jw/p+1)}$

wlg

Expressing in dB: Given the transfer function:

 $20\log |G(jw|=20\log K_{B}+20\log |(jw/z+1)|-20\log |jw|-20\log |jw/p+1|$

Bode Plots

- A **Bode plot** is a (semilog) plot of the transfer function **magnitude** and **phase** angle as a function of frequency
- The gain magnitude is many times expressed in terms of decibels (dB)

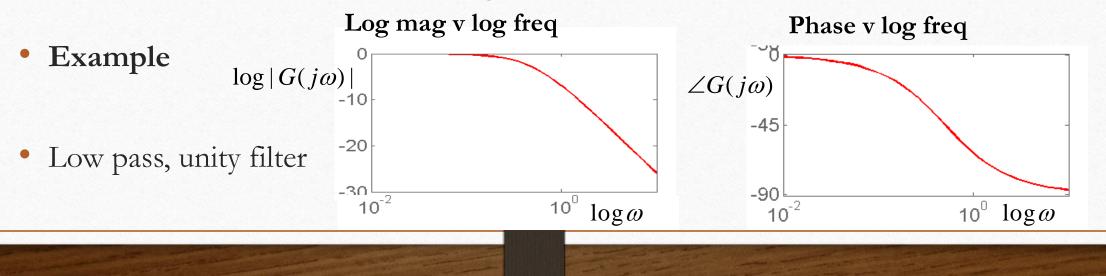
 $dB = 20 \log_{10} A$

where A is the amplitude or gain

- a *decade* is defined as any 10-to-1 frequency range
- an *octave* is any 2-to-1 frequency range

20 dB/decade = 6 dB/octave

- A **Bode Plot** for a system is simply plots of log magnitude and phase against log frequency
- Both the log magnitude and phase effects are now additive
- Widely used for analysis and design of filters and controllers





magnitude in dB of the frequency response as a function of the angular frequency ω with logarithmic scale for ω $20\log K_{\rm B}$ angle or phase of the frequency response as a function of the angular $\angle F(j\omega)$ $20\log |(jw/z + 1)|$ frequency ω with logarithmic scale for ω we need to find the magnitude (in dB) and phase for the 4 elementary factors $-20\log|jw|$ 1. Constant K (generalized gain) 2. Monomial j ω (zero or pole in s = 0) $-20\log|(jw/p + 1)|$ 3. Binomial 1 + $j\omega\tau$ (non-zero real zero or pole) 4. Trinomial $1 + 2\zeta(j\omega) / \omega_n + (j\omega)^2 / \omega_n^2$ (complex conjugate pairs of zeros or poles)

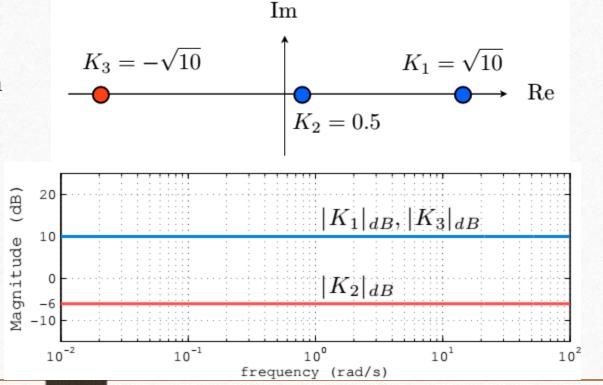
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1. Constant K (generalized gain)

 The gain term, 20logK_B is just so many dB and this is a straight line on Bode paper, independent of omega (radian frequency).

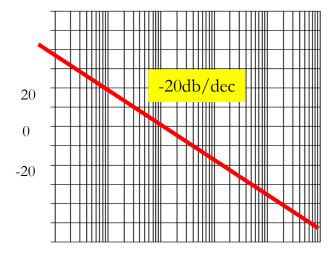
magnitude

 $20 \log_{10} |K|$



2. Monomial $j\omega$ (poles)

The term, $-20\log|jw| = -20\log w$, when plotted on semi-log paper is a straight line sloping at 20dB/decade. It has a magnitude of 0 at w = 1.



ω=1

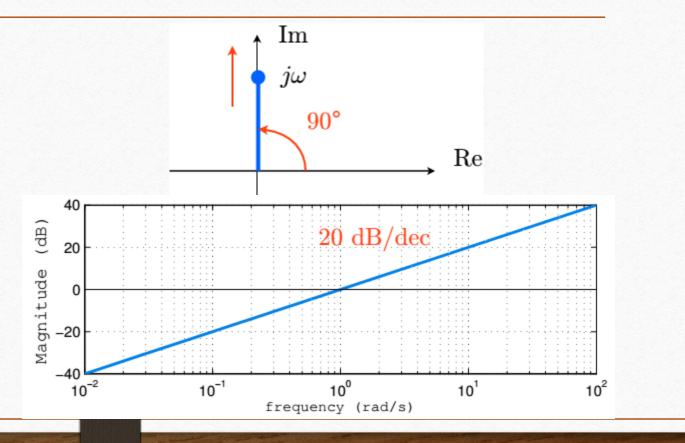
2. Monomial j
$$\omega$$
 (Zeros) S^{μ}

Magnitude:

$$\left|(j\omega)^p\right|_{dB} = 20p\log\omega(dB)$$

Phase:

$$\angle (j\omega)^p = (90^o) \times p$$



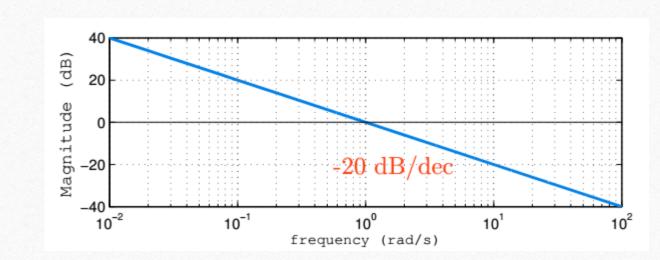
Magnitude:

$$\left|\frac{1}{(j\omega)^p}\right|_{dB} = -20p\log\omega(dB)$$

 s^{p}

Phase:

$$\angle \frac{1}{(j\omega)^p} = (-90^o) \times p$$



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3. Binomial $1 + j\omega\tau$ (non-zero real zero or pole)

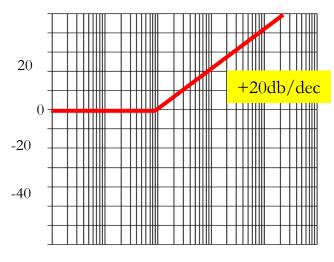
Magnitude approximation wrt the cutoff frequency $1/|\tau|$ (corner frequency)

 $|1 + j\omega\tau|_{dB} = 20\log_{10}\sqrt{1 + \omega^2\tau^2}$

$ 1+j\omega\tau _{dB}$	\approx	ſ	0dB	if	$\omega \ll 1/ \tau $
		201	$\operatorname{og}_{10}\omega + 20\log_{10} \tau $	if	$\omega \gg 1/ \tau $

two half-lines approximation: 0 dB until the cutoff frequency, + 20dB/decade after

When we have a term of $20\log|(jw/z + 1)|$ we approximate it be a straight line of slop 0 dB/dec when w < z. We approximate it as $20\log(w/z)$ when w > z, which is a straight line on Bode paper with a slope of + 20dB/dec.

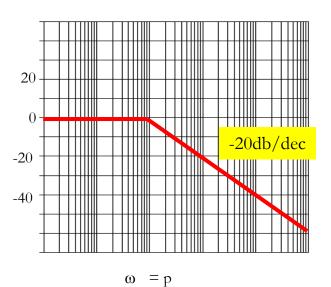


 $\omega = z$

The term, - $20\log|(jw/p + 1)$, is drawn with the following approximation:

If $\mathbf{w} < \mathbf{p}$ we use the approximation that $-20\log|(jw/p + 1)| = 0$ dB, a flat line on the Bode.

If $\mathbf{w} > \mathbf{p}$ we use the approximation of $-20\log(w/p)$, which slopes at -20dB/dec starting at w = p. It is easy to show that the plot has an error of -3dB at w = p and -1 dB at w = p/2 and w = 2p. One can easily make these corrections if it is appropriate.



4. Trinomial 1 + $2\zeta(j\omega) / \omega_n + (j\omega)^2 / \omega_n^2$ Magnitude

$$\left|1 + 2\frac{\zeta}{\omega_n}(j\omega) + \frac{(j\omega)^2}{\omega_n^2}\right| = \left|1 - \frac{\omega^2}{\omega_n^2} + j2\zeta\frac{\omega}{\omega_n}\right| = \sqrt{\left(1 - \frac{\omega^2}{\omega_n^2}\right)^2 + \left(4\zeta^2\frac{\omega^2}{\omega_n^2}\right)^2}$$

 $|\text{TRINOMIAL}|_{dB} \approx \begin{cases} 0 \, dB & \text{if } \omega \ll \omega_n \\ \\ 40 \log_{10} \omega - 20 \log_{10} \omega_n^2 & \text{if } \omega \gg \omega_n \end{cases}$

4. Trinomial 1 + $2\zeta(j\omega) / \omega_n + (j\omega)^2 / \omega_n^2$

Phase

$$T(j\omega) = \frac{\omega_n^2}{(\omega_n^2 - \omega^2) + 2j\xi\omega_n\omega} \qquad \angle T(j\omega) = -\tan^{-1}\frac{2\xi\omega\omega_n}{(\omega_n^2 - \omega^2)}$$
$$T(j\omega) = \frac{1}{(1 - (\frac{\omega}{\omega_n})^2) + j2\xi\frac{\omega}{\omega_n}} \qquad \angle T(j\omega) = -\tan^{-1}\frac{2\xi\frac{\omega}{\omega_n}}{1 - (\frac{\omega}{\omega_n})^2}$$

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Credits

This video was made for the ECE 220 course at George Mason University during the spring 2014 semester.

For more information check out these websites:

- Mason: http://www.gmu.edu
- Volgenau School of Engineering: http://vse.gmu.edu
- ECE Department: http://ece.gmu.edu
- Kathleen Wage:

http://ece.gmu.edu/~kwage/kew.html

Video produced using Doodlecast Pro software for the iPad



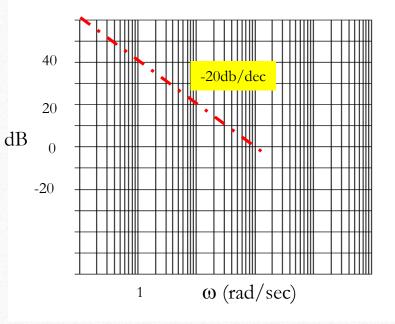
Bode Plots

 $G(s) = \frac{100(1 + s/10)}{s(1 + s/100)^2}$ $\frac{100}{jw}$ Example : Given the transfer function. Plot the Bode magnitude.

Consider first only the two terms of

Which, when expressed in dB, are; $20\log 100 - 20 \log w$. This is plotted below.

> The is a tentative line we use until we encounter the first pole(s) or zero(s) not at the origin.



Bode Plots

Example :

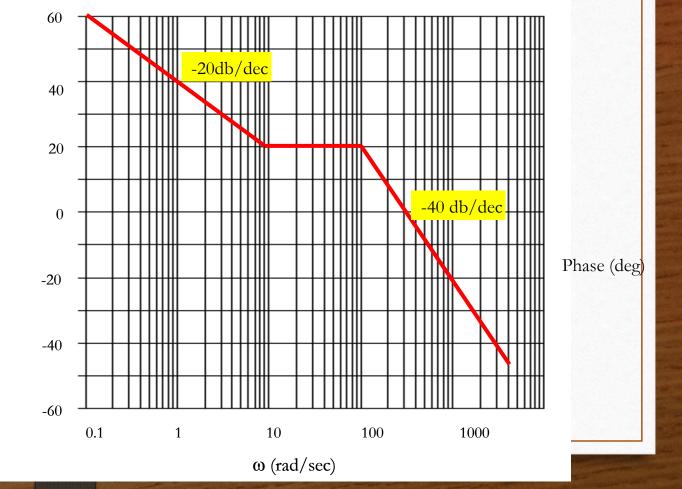
The completed plot is shown below.

 $G(s) = \frac{100(1+s/10)}{s(1+s/100)^2}$

dB Mag

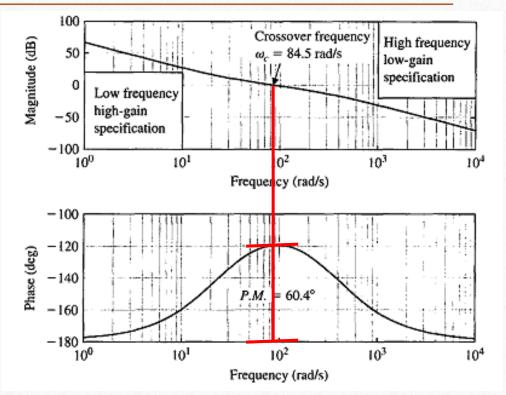
Phase

 $\angle G(jw) = \tan^{-1}(w/10) - \tan^{-1}(\infty) - \tan^{-1}(w/100)$



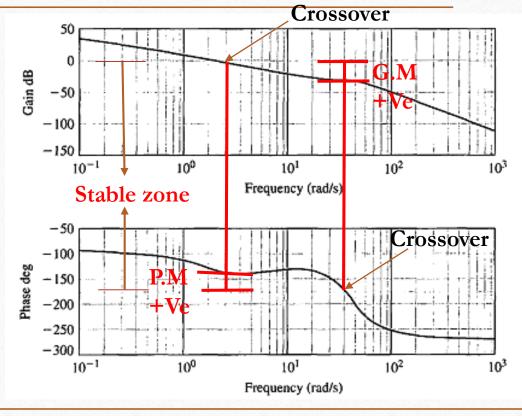
Stability in Frequency Response

- G.M = +Ve if belwo zero of magnitude
- P.M = +Ve if above -180 of phase
- Stable if G.M & P.M are +ve
- Unstable if G.M & P.M are -ve
- Critical stability if G.M & P.M are in opposite signs



Stability in Frequency Response

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Model Examples

• Pulse Width Modulation (PWM)

