

EE 482 LINEAR CONTROLS SYSTEMS Fall 2007 (Safonov)

Text:

Dorf, *Modern Control Systems*, 11th Edition. Upper Saddle River, NJ: Prentice-Hall. ISBN 0132270285

<http://vig.prenhall.com/catalog/academic/product/0,1144,0132270285,00.html>

Instructor:

Prof. Michael G. Safonov

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Office Hours: M 11:00AM-1:00PM, W 11:00AM-12:00PM

Prerequisite: EE301 Introduction to Linear Systems

Web: For course materials and grades, login to DEN at <http://den.usc.edu/>

Discussion Section: Friday 12:00-12:50, OHE 100C

TA:

Yun Wang <yunwang@usc.edu>

Office Hours: Tuesdays 2-5pm. EEB320, (213)740-6257

Grades:

10% homework, 40% Midterm Exam, 50% Final Exam

Computer:

The following software (freely available to use on PC's in USC's computer rooms) will be required for some of the homework exercises:

- MATLAB & Simulink Student Version Release 2007a. Natick, MA: MathWorks. ISBN 9780979223907 <http://www.mathworks.com/products/studentversion>
- MATLAB Control System Toolbox.

It is also possible to access MATLAB from off-campus using X-Windows as described in the documentation at <http://www.usc.edu/its/doc/math/matlab/>

New students visit <http://www.usc.edu/firstlogin> to setup your USC computer account.

Academic Integrity:

University policies regarding academic integrity are described in *SCampus* <http://www.usc.edu/dept/publications/SCAMPUS/> All violations will be reported to the Office of Student Conduct.

Students with Disabilities: Any student requesting academic accommodations based on a disability is required to register with Disability Services and Programs (DSP) each semester. A letter of verification for approved accommodations can be obtained from DSP. Please be sure the letter is delivered to me (or to TA) as early in the semester as possible. DSP is located in STU 301 and is open 8:30 a.m.5:00 p.m., Monday through Friday. The phone number for DSP is (213) 740-0776.

EE482 LECTURE TOPICS

Fall 2007 (Safonov)

1. (a) Introduction, perspective, examples of typical control problems. Homework: Modeling techniques; linear systems, principle of superposition, convolution integrals, Laplace transforms.
(b) Laplace transformation models: Partial fraction expansion and impulse response, pole-zero plot; signal flow diagram and direct solution of multi-input-output transfer function matrices from node equations.
2. (a) **USC Holiday**: Labor Day
(b) Feedback system characteristics: Sensitivity reduction, transient response control, noise attenuation, steady-state error improvement; definitions and formulas; examples.
3. (a) Feedback system performance specifications: Steady-state spec's, transient response spec's, parameter variation tolerance spec's, noise tolerance spec's; the concept of compromise design.
(b) Two-dominant-pole model: Damping ratio, natural frequency, relationships of pole locations to transient spec's; model order reduction by partial fraction expansion and justification of the two-dominant-pole assumption.
4. (a) Miscellaneous: Steady-state error, final-value theorem, performance indices, introduction to the concept of stability.
(b) Stability: Relation to pole location, Routh-Hurwitz stability criterion.
5. (a) Root locus: The concept of root-locus, relation to open-loop pole-zero plot; phase angle and magnitude conditions.
(b) Root locus behavior: Asymptotic behavior for large and small gains; behavior on real axis.
6. (a) Root locus behavior at break-away points.
(b) Root locus: Sketching examples.
7. (a) Root locus: Use for parameter variation analysis; root sensitivity.
(b) Frequency response model: Review of Fourier transform; Bode plot, polar plot, and log magnitude vs. phase angle plot.
8. (a) Frequency response model: Relation to open-loop pole-zero plot.
(b) Frequency response model: Procedures for sketching Bode plot given the pole-zero plot; determination of transfer function from Bode plot.
9. (a) Frequency response model: Concepts of minimum and non-minimum phase systems; two-dominant-pole system; resonant peak and resonant frequency, relation to damping ratio and natural frequency.
(b) **Midterm Exam**: 9:30–10:45 AM, Wednesday October 24, 2007.

10. (a) Performance spec's in the frequency domain: Determination of transient properties (rise-time, etc.) from a closed-loop frequency response; determination of steady-state error from open-loop frequency response.
(b) Nyquist stability criterion: Cauchy's "principle of the argument" and the proof of the Nyquist criterion.
11. (a) Nyquist stability criterion: Procedures for handling imaginary-axis poles.
(b) Gain and phase margin: Definition and interpretation; relation to damping ratio of dominant closed-loop poles.
12. (a) M-circles: Derivation, relation to damping ratio of dominant closed-loop poles; Nichols' chart.
(b) Compensation: Root-locus approach.
13. (a) Compensation: Frequency response approaches using Bode plot and Nichols' chart.
(b) Compensation: Examples
14. (a) Compensation: Examples
(b) Robust Control Systems: Uncertain models and parameter variation, QFT, small gain theorem.
15. (a) Robust Control Systems: H -infinity optimal loop-shaping.
(b) Review
16. **FINAL EXAM**: 11:00 AM –1:00 PM, Monday, December 17, 2007.