

Computer Exercise 2

EL2520 Control Theory and Practice

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Minimum phase case

The controller is given by

$$F(s) = \dots$$

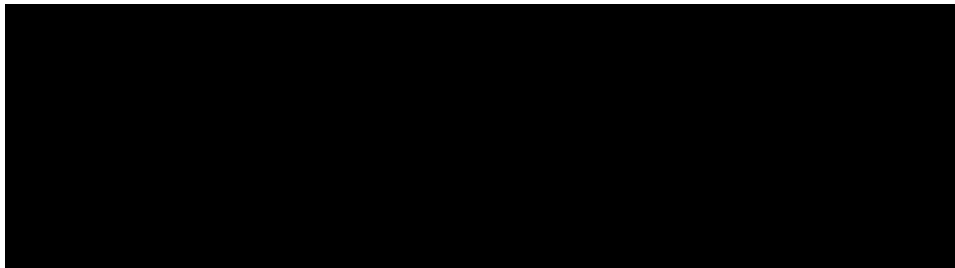


Figure 1: Simulink plots from exercise 3.2.3

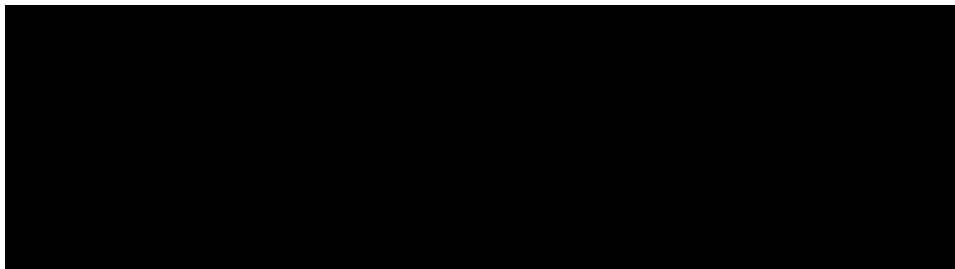


Figure 2: Bode diagram of the loop gain $L(s)$ from exercise 3.2.1

Is the controller good?

.....
.....

Are the output signals coupled?

.....
.....

Non-minimum phase case

The controller is given by

$$F(s) = \dots$$

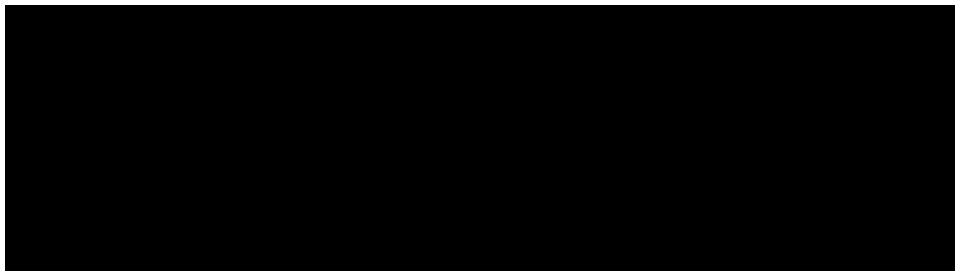


Figure 3: Simulink plots from exercise 3.2.3

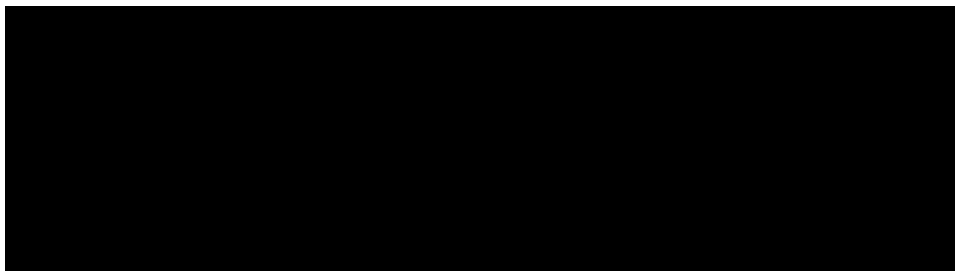


Figure 4: Bode diagram of the loop gain $L(s)$ from exercise 3.2.1

Is the controller good?

.....
.....

Are the output signals coupled?

.....
.....