CONTENTS

Prefa Ackn	owledgments	xv xvii
1. B	ASICS OF CONTROL SYSTEMS	1
	Introduction 1	
1.1	System, Process, and Plant 1	
1.2	Control and Controller 2	
	1.2.1 Controller 3	
1.3	Control System 5	
1.4	Nature of Control Systems 5	
	1.4.1 Manual control systems 6	
	1.4.2 Semi-automatic control systems 6	
	1.4.3 Automatic control systems 6	
1.5	Classification of Control Systems 6	
	1.5.1 Based on configuration 6	
	1.5.2 Based on change of plant parameters δ	
	1.5.3 Based on behavior 9	
	1.5.4 Based on distribution of parameters over the structure of control system 9	
	1.5.5 Based on control learning capabilities 9	
	1.5.6 Based on the number of inputs and outputs 10	
	1.5.7 Based on the type of signal and signal conditioning requirements 11	
	1.5.8 Distributed control systems 13	
	1.5.9 Programmable logic controller 14	
	1.5.10 Supervisory control and data acquisition system 15	
	1.5.11 Microcontroller-based systems 16	
	1.5.12 Simple programmable logic devices 16	
	1.5.13 Complex programmable logic devices 16	
	1.5.14 Field programmable gate array (FPGA) based control systems 16	
1.6	Servo Control Systems 17	
1.7	Regulators or Automatic Regulating System 17	
1.8	Process Control Systems 17	
1.9	Some Examples of Control Systems 17	
	1.9.1 Steam turbine speed control system 18	
	1.9.2 Manual feedforward and feedback control of temperature 18	
	1.9.3 Speed control of a single-phase induction motor 18	
	1.9.4 Computer-based servo mechanism 19	

2.

3.

	1.9.5 Open-loop ceiling fan control system 19 1.9.6 Closed-loop ceiling fan control system 20 1.9.7 Open-loop traffic light system 20 1.9.8 Closed-loop traffic light control system 21 1.9.9 Closed-loop water heating control system 21 1.9.10 Closed-loop feedforward tank height/level control system 21 1.9.11 Closed-loop feedforward/feedback tank height/level control system 22 1.9.12 Production control system 23 1.9.13 Economic control system 23 1.9.14 Robot-arm control system 24 1.9.15 Quality control system 24 1.9.16 Closed-loop electrical drive position control system 25 Designing a Control System 25 Solved Problems 27 Exercises 29	
	APLACE TRANSFORM AND z-TRANSFORM	31
2.1	Introduction 31 Domain Analysis 31 2.1.1 Time-domain mathematical models and analysis 31 2.1.2 Frequency-domain mathematical models and analysis 33 Mathematical Analytical Tools 34 2.2.1 Laplace transform technique 34 2.2.2 Inverse Laplace transform 44 2.2.3 z-transform technique 54 2.2.4 Inverse z-transforms 62 2.2.5 Residue method for repeated poles 66 Solved Problems 67 Exercises 75	
3. TI	RANSFER FUNCTION AND GAIN	77
3.1 3.2 3.3	Introduction 77 Transfer Function 77 Gain 78 Transfer Functions of Standard Control Systems 89 3.3.1 Transfer function of a field-controlled DC motor (servo motor) 89 3.3.2 Transfer function of an armature-controlled DC motor (servo motor) 90 3.3.3 Transfer function of a two-phase AC servo motor 92 3.3.4 Transfer function of a separately excited DC generator 93 3.3.5 Transfer function of an amplidyne generator 95	

3.4	Concept of Poles and Zeros 96 3.4.1 Gain factor 97	
3.5	Mapping of Poles and Zeros and Region of Stability 97	
3.6	Type, Order, and Dynamics of Control Systems 99 3.6.1 Type of a control system/process 99	
	3.6.2 Order of a control system/process 99	
	3.6.3 Static error constants and steady-state error 102	
	Solved Problems 105	
	Exercises 118	
4 N	NODELLING TECHNIQUES OF CONTROL SYSTEMS: BLOCK	
	IAGRAMS AND SIGNAL FLOW GRAPHS	121
4.1	Modeling: Introduction 121	
	4.1 1 Definition of a model 121	
4.2	Interconnects-based Modeling: Block Diagrams 121	
	4.2.1 Block diagram representation 121	
	4.2.2 Overall (total) transfer function of blocks in series (cascaded blocks) 123	
	4.2.3 Overall (total) transfer function of blocks in parallel 123	
	4.2.4 Generalized negative feedback control system block diagram 124	
	4.2.5 Block diagram representation of a positive feedback control system 125	
	4.2.6 Block diagram reduction 125	
	 4.2.7 Multiple input—multiple output control system block diagram 154 4.2.8 Concept of disturbance in control systems and its block diagram representation 	164
	4.2.9 Block diagram representation of some control systems 166	104
4.3	Signal Flow Graphs 170	
	4.3.1 Definition of a signal flow graph 170	
	4.3.2 Other definitions in signal flow graphs 171	
	4.3.3 Properties of signal flow graphs 171	
	4.3.4 Procedure for converting a block diagram into a signal flow graph 172	
	4.3.5 Mason's gain formula for signal flow graphs 173	
	Solved Problems 184	
	Exercises 191	
5. T	IME-DOMAIN MODELING: STATE-SPACE APPROACH	193
	Introduction 193	
5.1	State-Space Modeling or State-Variable Approach 193	
5.2	Definitions in State-Space Modeling Approach 194	
5.3	General State-Space Model of Multiple Input-Multiple Output Control System 196	
5.4	"State" of a Dynamic Control System 198	
5.5	State-Space Representation of a Transfer Function 204	
5.6	State-Space Representation of <i>n</i> th-order Differential Equation 206	
5.7	Non-uniqueness of State-Space Models 207	

5.8 5.9	State Variable Representation in Signal Flow Graphs 208 Transfer Function Decomposition 211 5.9.1 Direct decomposition 211 5.9.2 Cascade decomposition 213 5.9.3 Parallel decomposition 216	
	State-Space Model of a Multivariable Control System 219 Solution of State Equations 220 5.11.1 Homogeneous state equation 220 5.11.2 Non-homogeneous state equation 224	
	Transfer Function Determination from State-Space Model 229 Controllability and Observability 232 5.13.1 Controllability 232 5.13.2 Observability 234 Solved Problems 236 Exercises 242	
6. A	NALOGOUS SYSTEMS AND PHYSICAL SYSTEM MODELING	243
6.1	Introduction 243 Analogous Systems 244 6.1.1 Mechanical translational system 244 6.1.2 Mechanical rotational system 248 Physical System Modeling 278 6.2.1 Electrical system modeling 278	
	6.2.2 Mechanical system modeling 279 6.2.3 Pneumatic system modeling 279 6.2.4 Hydraulic system modeling 284 6.2.5 Chemical system modeling 292 6.2.6 Thermal system modeling 293 Solved Problems 297 Exercises 307	
7. C	ONTROL SYSTEM COMPONENTS	311
7.1 7.2 7.3	Introduction 311 Concept of Controller and Actuator and Their Placement in a Control Loop 311 Potentiometric Error Detector 313 Linear Variable Differential Transformer 316 7.3.1 LVDT specifications 320 7.3.2 Applications of LVDTs 320	
7.4	7.3.3 Advantages and disadvantages of LVDTs 320 Rotary Variable Differential Transformers 321 7.4.1 RVDT specifications 322 7.4.2 Advantages and disadvantages of RVDTs 322	

7.5	Tachogenerator 323 7.5.1 DC tachogenerator 323 7.5.2 AC tachogenerator 324
76	7.5.2 AC tachogenerator 324 Synchro 325
7.6	7.6.1 Differential synchro sets 332
7.7	Servo Motors 334
,	7.7.1 DC servo motors 335
	7.7.2 AC servo motors 337
7.8	Servomechanism 343
	7.8.1 Velocity servomechanism or rate servomechanism 346
7.9	Modulator 348
	7.9.1 Synchronous vibrator 348
	7.9.2 Diode modulator 350
	7.9.3 Diode bridge modulator 351
7.10	Demodulator 351
	7.10.1 Synchronous vibrator as a demodulator 352
	7.10.2 Diode demodulator 352
7.11	Stepper Motor 353
	7.11.1 Permanent magnet stepper motors 356
	7.11.2 Variable reluctance stepper motor 358
	7.11.3 Hybrid stepper motor 360
7.12	7.11.4 Step operations of a stepper motor 361
	Gear Trains 362
	Amplidyne 366 Resolvers 368
	Gyroscopes 370
	Accelerometers 377
	Magnetic Amplifiers 379
/.1/	Solved Problems 382
	Exercises 384
	LACTURES 507
8. TI	ME RESPONSE ANALYSIS OF CONTROL SYSTEMS
Δ	ND ERROR CRITERION 385
	Introduction 385
8.1	<u> </u>
8.2	Steady-State Response 385
8.3	Performance Indices of Control Systems 386
	8.3.1 Speed of response 387
	8.3.2 Accuracy of output: Steady-state error 388
	8.3.3 Disturbance and sensitivity analysis of control systems 396
_	8.3.4 Sensitivity analysis of control systems 399
8.4	Time Response Analysis of First-Order Control System 408
	8.4.1 Unit impulse input response and analysis 408

8.4.2 Unit step input response and analysis 410

8.5 8.6 8.7 8.8	 8.4.3 Unit ramp input response and analysis 413 Time Response Analysis of a Second-Order Control System 415 8.5.1 Unit impulse input response and analysis 416 8.5.2 Unit step response, various performance indices (transient responsedy-state specification) and analysis 419 Time Response Analysis of Third- and Higher Order Control Systems Effect of Feedback on the Time Response of a Control System 434 Error Criteria 435 Solved Problems 437 	onse specification and
	Exercises 447	
9. S	TABILITY ANALYSIS	449
	Introduction 449	
9.1	Hurwitz Criterion 450	
9.2	Routh Stability Criterion 452	
	9.2.1 Special cases for resolving Routh stability criterion 4539.2.2 Relative stability analysis 455	
9.3	Bode Plots 456	
	9.3.1 Asymptotic plots 456	
	9.3.2 Gain and phase crossover 467	
9.4	Root Locus Method 470	
	9.4.1 Rules for the construction of a root locus 471	
9.5	Polar Plots 476	
9.6	Nyquist Stability Criterion 476 9.6.1 Nyquist plots and relative stability assessment 477	
	9.6.1 Nyquist plots and relative stability assessment 4779.6.2 Rules for construction of Nyquist plots 477	
	9.6.3 Nyquist contour and Nyquist stability criterion 479	
	Solved Problems 479	
	Exercises 488	
10.	CONTROLLERS	489
10.1	Introduction 489	
10.1	Controller and Its Issues 489 10.1.1 Controller placement in a control loop 490	
	10.1.1 Controller placement in a control loop 490	
	10.1.3 Disturbance placement in a control system 491	
	•	491
10.2	Conventional Controllers 495	
	10.2.1 ON–OFF controllers (relay-based controllers) 496	
	10.2.2 Time proportioning controllers 497	
	10.2.3 Proportional controllers 498	
	10.2.4 Proportional-derivative controllers 499	

	10.2.5 Proportional integral controllers 508	
	10.2.6 Proportional integral derivative controllers 512	
	10.2.7 PID tuning 515	
10.3	Inference-based Controllers 518	
	10.3.1 Artificial intelligence-based controllers 518	
10.4	Fuzzy Logic Controllers 519	
	10.4.1 Fuzzification 523	
	10.4.2 Inference 523	
	10.4.3 Defuzzification 524	
	10.4.4 Hardware/software for fuzzy logic systems 525	
10.5	Artificial Neural Network-based Control Systems 526	
	10.5.1 Classification 529	
	10.5.2 Learning rules <i>532</i>	
	10.5.3 Neuro-Fuzzy controllers 533	
10.6	Expert Systems 534	
	10.6.1 Characteristics of an expert system 535	
	10.6.2 Building and searching 535	
10.7	Genetic Algorithms and Its Applications in Control Systems 537	
	10.7.1 Encoding methods in genetic algorithms 538	
	10.7.2 Selection methods in genetic algorithms 539	
	10.7.3 Genetic operators in genetic algorithms 540	
	10.7.4 Genetic algorithms: Issues and recommendations 543	
	10.7.5 Modifications in basic genetic algorithms 544	
	10.7.6 Difference between genetic algorithms and conventional optimization techniques	544
	10.7.7 Applications of genetic algorithms 545	
10.8	Other Model-based Algorithms 546	
	10.8.1 Static control law 546	
	10.8.2 Dynamic control law 548	
10.9	Comparison of Mathematical Model-based Controllers and Data-based Controllers 549	
	Solved Problems 550	
	Exercises 550	
	COMPANY AND	
11.	COMPENSATION IN CONTROL SYSTEMS	555
	Introduction 555	
11.1	Phase-lead Compensation 555	
11.2	Phase-lag Compensation 559	
11.3	Lag-lead Compensation 560	
11.4	Selection of a Phase Compensator 561	
11.5	Designing a Phase-lead Compensator 562	
11.6	Designing a Phase-lag Compensator 563	
11.7	Designing a Lag-Lead Compensator 564	
11.7	Frequency Domain Design of Phase Compensation Networks/Circuits 564	
11.0	Solved Problems 565	
	Exercises 568	

	EIGENVALUES AND EIGENVECTORS	5 <i>7</i> 1
	Introduction 571 Eigen Plane 571 Definitions 572 12.2.1 Eigenvector 572 12.2.2 Eigenvalue 572 12.2.3 Eigen space 572 12.2.4 Geometric multiplicity 572	
12.3	12.2.5 Spectrum 572 Eigenvalue Equation 572	
	Spectral Theorem 573	
	Computation of Eigenvalues 574	
	Properties of Eigenvalues 576	
	Identifying Eigenvectors 576	
	Algebraic Multiplicity of Eigenvalues 578	
	Decomposition Theorem 578 0 Eigenvalues of a Graph 579	
	1 Conjugate Eigenvector 580	
	2 Generalized Eigenvalues 580	
	Solved Problems 580	
	Exercises 589	
12	INDUSTRIAL CONTROL SYSTEMS	591
13.		371
13.		371
	Introduction 591	371
13.1	Introduction 591	341
13.1	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594	371
13.1	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595	371
13.1	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598	371
13.1 13.2	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598 13.3.5 Programming languages of a PLC 599	371
13.1 13.2 13.3	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598 13.3.5 Programming languages of a PLC 599 13.3.6 PLC instructions 600	371
13.1 13.2 13.3	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598 13.3.5 Programming languages of a PLC 599 13.3.6 PLC instructions 600 Distributed Control Systems 608	371
13.1 13.2 13.3	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598 13.3.5 Programming languages of a PLC 599 13.3.6 PLC instructions 600 Distributed Control Systems 608 13.4.1 DCS architecture 608	371
13.1 13.2 13.3	Introduction 591 Processor/PC-based Control Systems 592 Microcontrollers 593 13.2.1 Digital and analog input/output 594 13.2.2 Timers 595 13.2.3 Oscillators and analog output 595 13.2.4 Data logging 595 Programmable Logic Controllers 595 13.3.1 PLC structure 595 13.3.2 Advantages and disadvantages of a PLC 597 13.3.3 Types of PLC 598 13.3.4 PLC operation 598 13.3.5 Programming languages of a PLC 599 13.3.6 PLC instructions 600 Distributed Control Systems 608 13.4.1 DCS architecture 608	371

	13.4.5 Disadvantages of a DCS 616
12.5	Supervisory Control and Data Acquisition 617
13.5	
	13.5.1 SCADA structure and components 617
	13.5.2 SCADA architecture 620
	13.5.3 Security concerns of SCADA 621
	13.5.4 Potential benefits of a SCADA 621
13.6	Programmable Interface Controllers 621
	13.6.1 Features of a PIC 622
	13.6.2 Limitations of a PIC 622
13.7	Embedded Controllers 623
	13.7.1 Embedded Controller Architecture 623
13.8	3 Automatic Direct Memory Access Controllers 624
	13.8.1 Modes of operation 625
	Solved Problems 625
	Exercises 634

Index 635