1. Record Nr. UNINA9910461801703321 Autore Ellis George (George H.) Titolo Control system design guide [[electronic resource]]: using your computer to understand and diagnose feedback controllers / / George Ellis Amsterdam;; Boston,: Elsevier/BH, 2012 Pubbl/distr/stampa **ISBN** 1-283-73501-6 0-12-385921-2 Edizione [4th ed.] Descrizione fisica 1 online resource (521 p.) Disciplina 629.8 629.8/3 629.83 Soggetti Feedback control systems - Design and construction System design Electronic books. Lingua di pubblicazione Inglese **Formato** Materiale a stampa Monografia Livello bibliografico Note generali Description based upon print version of record. Nota di bibliografia Includes bibliographical references and index. Nota di contenuto Front Cover; Control System Design Guide: Using Your Computer to Understand and Diagnose Feedback Controllers; Copyright; Dedication; Contents: Praise for the new edition: Preface: What's New in this Edition?; Organization of the Book; Reader Feedback; Acknowledgments; Section I - Applied Principles of Controls; Chapter 1 - Introduction to Controls: 1.1Visual ModelQ Simulation Environment: 1.2The Control System: 1.3The Controls Engineer: Chapter 2 - The Frequency Domain; 2.1The Laplace Transform; 2.2Transfer Functions; 2.3Examples of Transfer Functions; 2.4Block Diagrams; 2.5Phase and Gain 2.6Measuring Performance2.7 Questions; Chapter 3 - Tuning a Control System; 3.1 Closing Loops; 3.2 A Detailed Review of the Model; 3.3 The Open-Loop Method: 3.4 Margins of Stability: 3.5 A Zone-Based Tuning

Procedure; 3.6 Variation in Plant Gain; 3.7 Multiple (Cascaded) Loops; 3.8 Power Converter Saturation and Synchronization; 3.9 Phase vs. Gain Plots; 3.10 Questions; Chapter 4 - Delay in Digital Controllers; 4.1How Sampling Works; 4.2Sources of Delay in Digital Systems; 4.3Experiment

4A: Understanding Delay in Digital Control; 4.4Selecting the Sample Time; 4.5 Questions

Chapter 5 - The z-Domain5.1Introduction to the z-Domain: 5.2z Phasors; 5.3Aliasing; 5.4Experiment 5A: Aliasing; 5.5From Transfer Function to Algorithm; 5.6Functions for Digital Systems; 5.7Reducing the Calculation Delay; 5.8Quantization; 5.9. Questions; Chapter 6 -Four Types of Controllers; 6.1Tuning in this Chapter; 6.2Using the Proportional Gain: 6.3Using the Integral Gain: 6.4Using the Differential Gain; 6.5PD Control; 6.6Choosing the Controller; 6.7Experiments 6A-6D; 6.8 Questions; Chapter 7 - Disturbance Response; 7.1 Disturbances; 7.2Disturbance Response of a Velocity Controller 7.3Disturbance Decoupling 7.4 Questions; Chapter 8 - Feed-Forward; 8.1Plant-Based Feed-Forward; 8.2Feed-Forward and the Power Converter: 8.3Delaying the Command Signal: 8.4Variation in Plant and Power Converter Operation: 8.5Feed-Forward for the Double-Integrating Plant: 8.6 Questions: Chapter 9 - Filters in Control Systems: 9.1Filters in Control Systems; 9.2Filter Passband; 9.3Implementation of Filters: 9.4 Questions: Chapter 10 - Introduction to Observers in Control Systems; 10.1Overview of Observers; 10.2Experiments 10A-10C: Enhancing Stability with an Observer 10.3Filter Form of the Luenberger Observer10.4Designing a Luenberger Observer: 10.5Introduction to Tuning an Observer Compensator: 10.6 Questions; Section II - Modeling; Chapter 11 - Introduction to Modeling: 11.1What is a Model?: 11.2Frequency-Domain Modeling: 11.3Time-Domain Modeling; 11.4Questions; Chapter 12 - Nonlinear Behavior and Time Variation; 12.1LTI Versus Non-LTI; 12.2Non-LTI Behavior: 12.3Dealing with Nonlinear Behavior: 12.4Ten Examples of Nonlinear Behavior; 12.5 Questions; Chapter 13 - Model Development and Verification; 13.1Seven-Step Process to Develop a Model 13.2From Simulation to Deployment: RCP and HIL

Sommario/riassunto

Control Systems Design Guide has helped thousands of engineers to improve machine performance. This fourth edition of the practical guide has been updated with cutting-edge control design scenarios, models and simulations enabling apps from battlebots to solar collectors. This useful reference enhances coverage of practical applications via the inclusion of new control system models, troubleshooting tips, and expanded coverage of complex systems requirements, such as increased speed, precision and remote capabilities, bridging the gap between the complex, math-heavy control theory ta