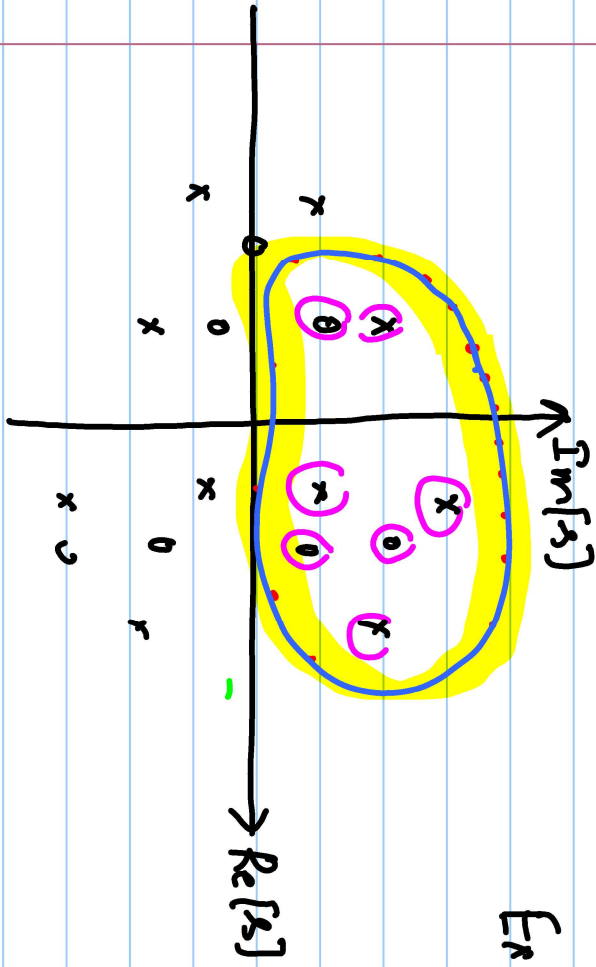


lecture # 16

Nyquist Stability Criterion.

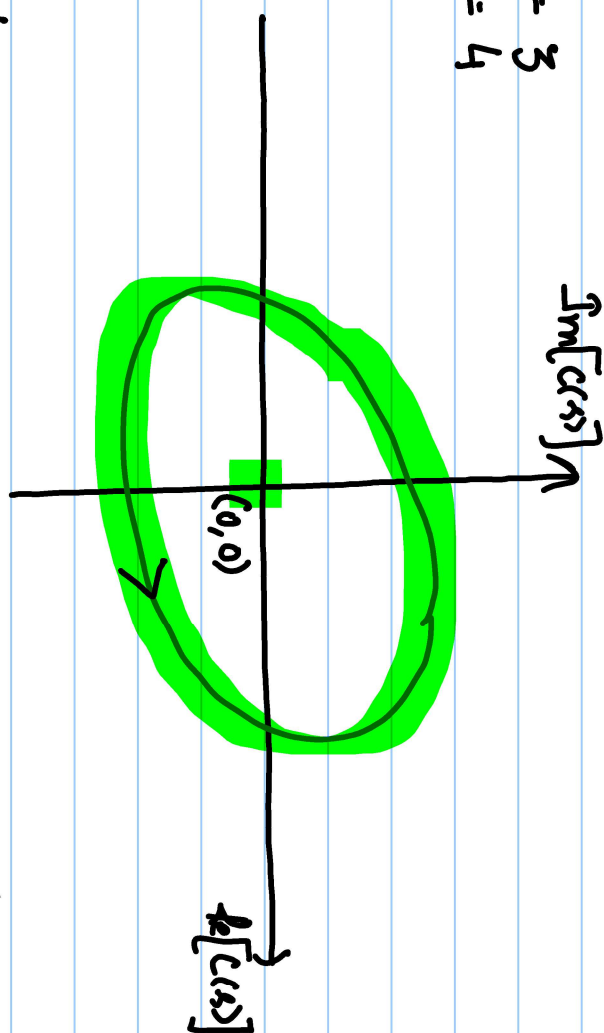


Ex: $N = 3$
 $M = 4$

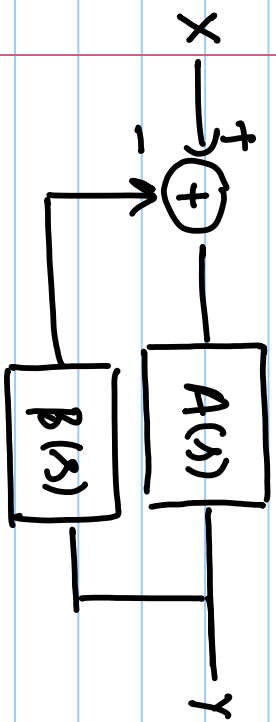
$$C(s) = \frac{(s-z_1)(s-z_2) \dots (s-z_k)}{(s-p_1)(s-p_2) \dots (s-p_L)}$$

K-zeros
L-poles

evaluate $C(s)$ at each point of the closed contour.



- if N zeros and M poles inside the closed contour in s -plane then closed contour in $C(s)$ -plane will encircle $(0,0)$ $N-M$ times.
- if $N > M$, it will encircle in clockwise else anticlockwise for $N < M$



$$LG(s) = A(s)B(s) = \frac{N(s)}{D(s)}$$

$$\frac{Y}{X} = \frac{A(s)}{1 + B(s)A(s)} \quad \text{shouldn't have R.H.P poles}$$

$$= \frac{1}{B(s)} \frac{B(s)A(s)}{1 + B(s)A(s)}$$

$$= \frac{1}{B(s)} \frac{K_c}{1 + L_c}$$

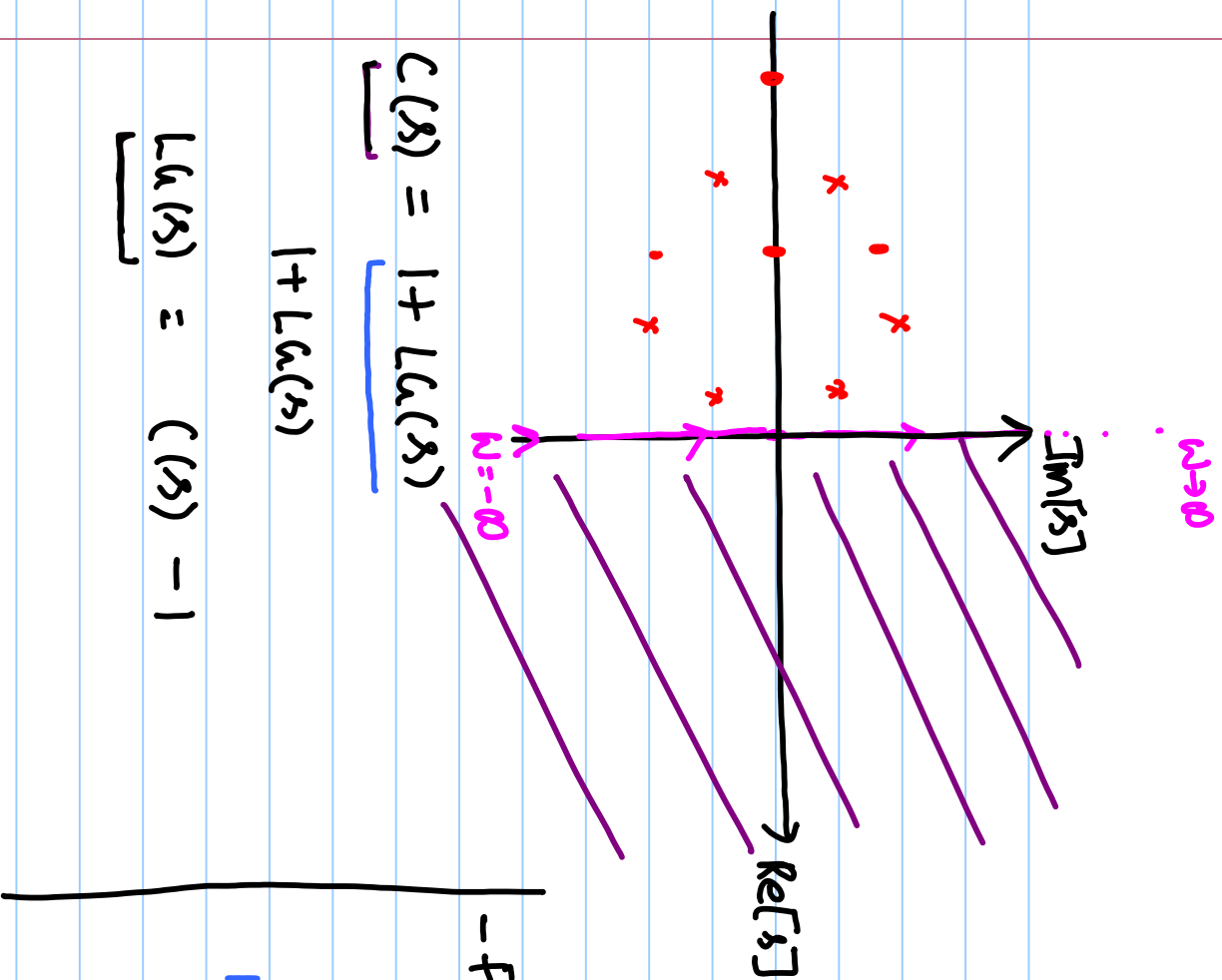
$$1 + L_c = 0 \quad \checkmark$$

$$\Rightarrow 1 + \frac{N(s)}{D(s)} = 0 \Rightarrow \underline{D(s) + N(s)} = 0$$

- if $\frac{Y}{X}$ has R.H.P poles then

$N(s) + D(s)$ must have R.H.P zeros.

- $C(s) = 1 + LG(s) \checkmark$



$$\underline{C(s)} = \underline{1 + L_G(s)}$$

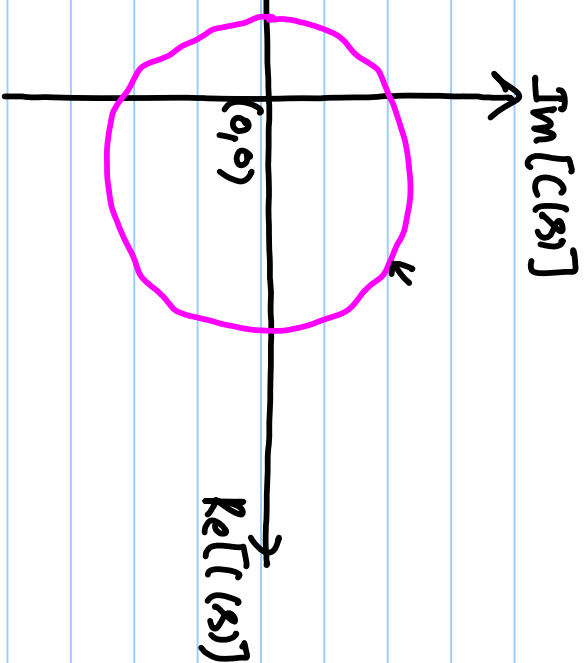
$$1 + L_G(s)$$

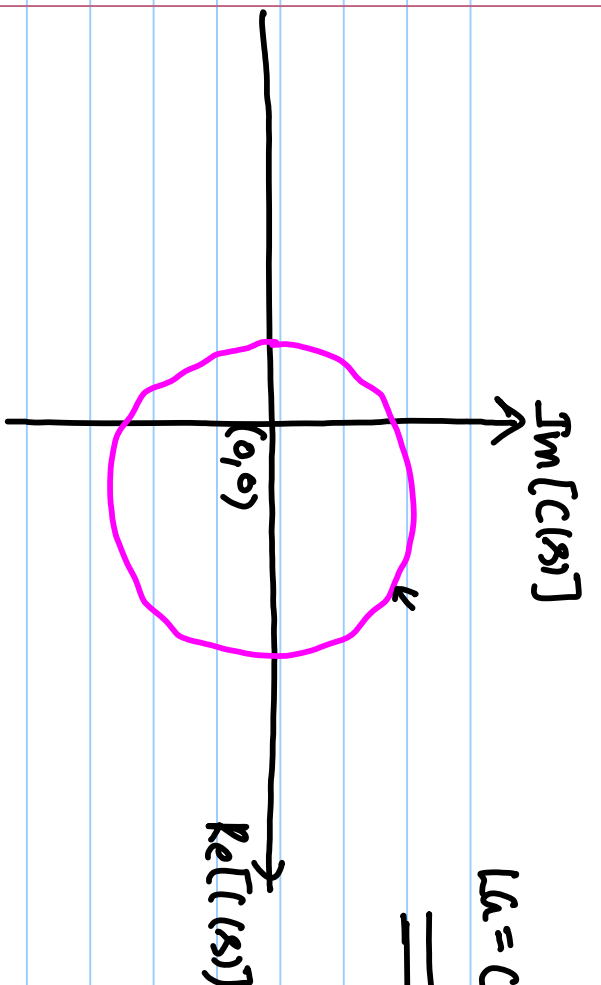
$$\underline{L_G(s)} = C(s) - 1$$

- First Order System

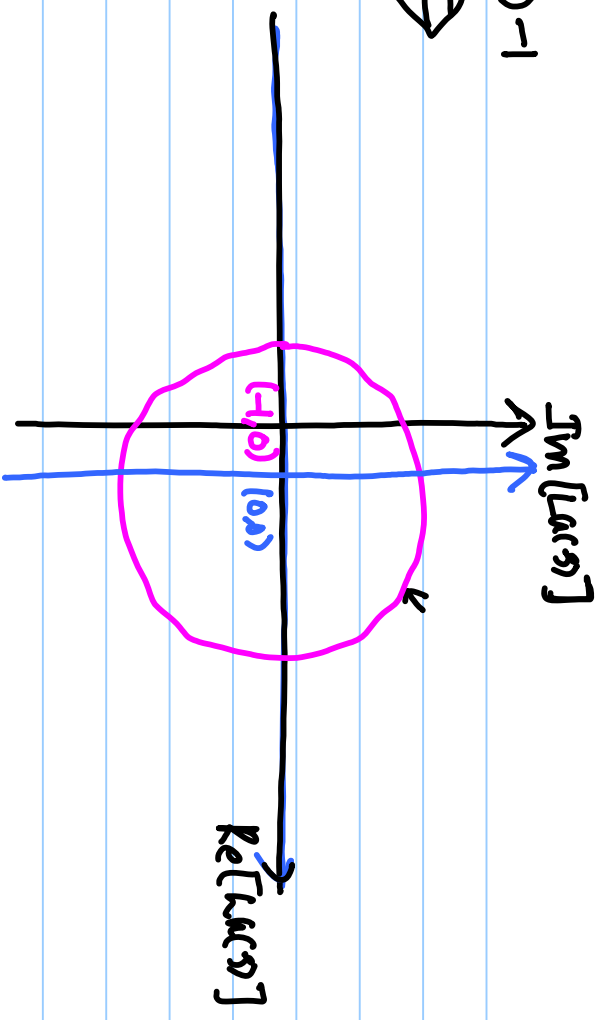
$$C(s) = 1 + \frac{A(s)}{K} = 1 + \frac{A_0/k}{1 + s/\omega_p} \quad \checkmark$$

$$L_G(s) = \frac{A_0/k}{1 + s/\omega_p}$$





$$L_u = C(s) - 1$$



$$L_u = \frac{A_0/k}{1 + s/\omega_p}$$

II

I

$$|L_u| = \frac{A_0/k}{\sqrt{1 + \omega^2/\omega_p^2}}$$

$$\phi_{L_u} = -\tan^{-1}\left(\frac{\omega}{\omega_p}\right)$$

III

