3.2 BODE PLOT

The Bode plot or the Bode diagram consists of two plots:

- Magnitude plot
- Phase plot

In both the plots, x-axis represents angular frequency (logarithmic scale). Whereas, yaxis represents the magnitude (linear scale) of open loop transfer function in the magnitude plot and the phase angle (linear scale) of the open loop transfer function in the phase plot.

The **magnitude** of the open loop transfer function in dB is -

$$M=20 \log |G(j\omega)H(j\omega)|$$

The **phase angle** of the open loop transfer function in degrees is -

$$\phi=\angle G(j\omega)H(j\omega)$$

Note − The base of logarithm is 10.

Basic of Bode Plots

The following table shows the slope, magnitude and the phase angle values of the terms present in the open loop transfer function. This data is useful while drawing the Bode plots.

Type of term	G(jω)H(jω)	Slope(dB/dec)	Magnitude (dB)	Phase angle(degrees)
Constant	K	0	20 logK	0
Zero at origin	jω	20	20 logω	90
'n' zeros at origin	$(j\omega)^n$	20 n	20 n logω	90 n
Pole at origin	1/jω	−20	−20 logω	−90 or 270
'n' poles	$1 / (j\omega)^n$	−20 n	−20n logω	−90n or 270n

at origin				
Simple zero	$1+j\omega_r$	20	0 for $\omega<1/r$ 20 $\log\omega_r$ for $\omega>1/r$	0 for $\omega<1/r$ 90 for $\omega>1/r$
Simple pole	$1 / 1+j\omega r$	-20	0 for $\omega < 1/r$ $-20 \log\omega_r$ for $\omega>1/r$	0 for $\omega <1/r$ -90 or 270 for $\omega >1/r$
Second order derivative term	$\omega^2 n(1-\omega^2/\omega^2_n+2j\delta\omega / \omega_n)$	40	40 $\log\omega_n$ for $\omega<\omega_n$ 20 $\log(2\delta\omega^2_n)$ for $\omega=\omega_n$ 40 $\log\omega$ for $\omega>\omega_n$	0 for $\omega<\omega_n$ 90 for $\omega=\omega_n$ 180 for $\omega>\omega_n$
Second order integral term	$1 / \omega^2_n(1-\omega^2/\omega^2_n+2j\delta\omega/\omega_n)$	-40	$-40 \log\omega_n$ for $\omega<\omega_n$ $-20 \log(2\delta\omega^2_n)$ for $\omega=\omega_n$ $-40 \log\omega$ for $\omega>\omega_n$	-0 for $\omega<\omega_n$ -90 for $\omega=\omega_n$ -180 for $\omega>\omega_n$

Consider the open loop transfer function G(s) H(s)=K.

$$\text{Magnitude } M=20 \log K \text{ dB}$$

$$\text{Phase angle } \phi=0 \text{ degrees}$$

If K=1, then magnitude is 0 dB.

If K>1, then magnitude will be positive.

If K<1, then magnitude will be negative.

The following figure 3.2.1 & 3.2.2 shows the corresponding Bode plot.

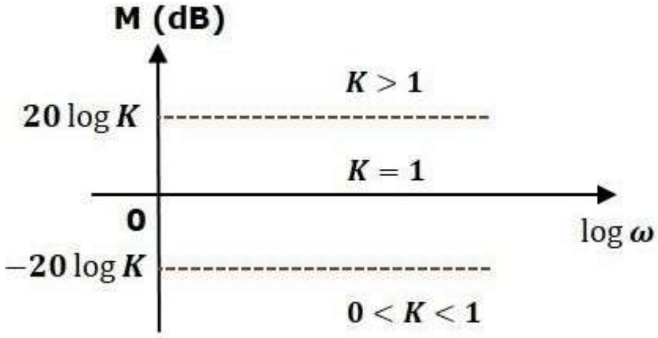

Figure 3.2.1: magnitude plot of open loop transfer function

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

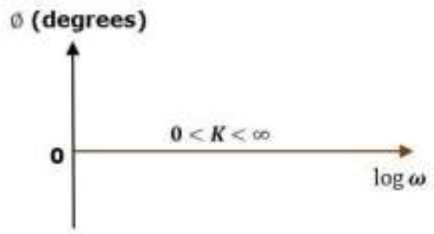

Figure 3.2.2: phase plot of open loop transfer function

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

The magnitude plot is a horizontal line, which is independent of frequency. The 0 dB line itself is the magnitude plot when the value of K is one. For the positive values of K, the horizontal line will shift 20 log K dB above the 0 dB line. For the negative values of K, the horizontal line will shift 20 log K dB below the 0 dB line. The Zero degrees line itself is the phase plot for all the positive values of K.

Consider the open loop transfer function G(s)H(s)=s.

$$\text{Magnitude } M=20 \log\omega \text{ dB}$$

$$\text{Phase angle } \phi=90^0$$

At ω=0.1 rad/sec, the magnitude is -20 dB.

At ω=1rad/sec, the magnitude is 0 dB.

At ω=10 rad/sec, the magnitude is 20 dB.

The following figure 3.2.3 & 3.2.4 shows the corresponding Bode plot.

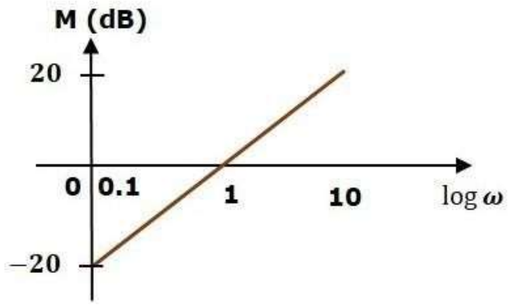

Figure 3.2.3: magnitude plot of open loop transfer function

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

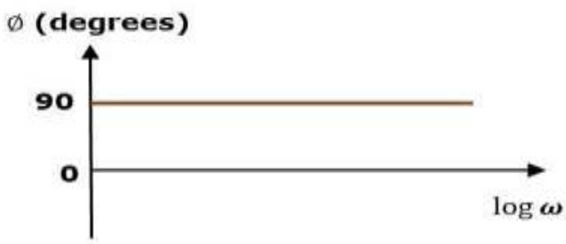

Figure 3.2.4: phase plot of open loop transfer function

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

The magnitude plot is a line, which is having a slope of 20 dB/dec. This line started at ω=0.1 rad/sec having a magnitude of -20 dB and it continues on the same slope. It is touching 0 dB line at ω=1 rad/sec. In this case, the phase plot is 90^0 line.

Consider the open loop transfer function G(s)H(s)=1+sτ.

Magnitude $\sqrt{\quad}$ dB Phase angle ϕ=tan−1ωτ degrees

For ω < 1τ , the magnitude is 0 dB and phase angle is 0 degrees.

For ω > 1τ , the magnitude is 20 logωτ dB and phase angle is 90^0.

The following figure shows the corresponding Bode plot.

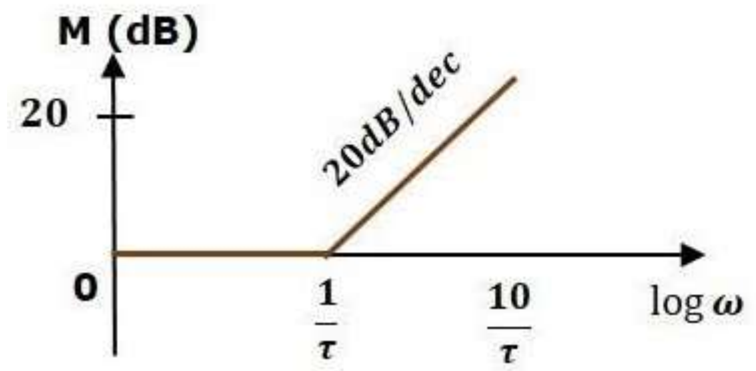

Figure 3.2.5: Magnitude plot of open loop transfer function for 1+sτ

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

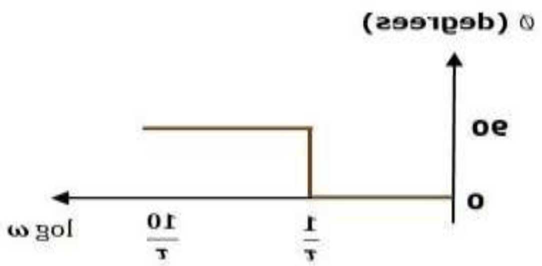

Figure 3.2.6: phase plot of open loop transfer function for 1+sτ

[Source: "Control System Engineering" by Nagoor Kani, page-3.11]

The magnitude plot is having magnitude of 0 dB upto ω=1 /τ rad/sec. From ω=1 /τ rad/sec, it is having a slope of 20 dB/dec. In this case, the phase plot is having phase angle of 0 degrees up to ω=1 /τ rad/sec and from here, it is having phase angle of 90^0. This Bode plot is called the **asymptotic Bode plot**.

As the magnitude and the phase plots are represented with straight lines, the Exact Bode plots resemble the asymptotic Bode plots. The only difference is that the Exact Bode plots will have simple curves instead of straight lines.

Similarly, you can draw the Bode plots for other terms of the open loop transfer function which are given in the table.

Rules for Construction of Bode Plots

Follow these rules while constructing a Bode plot.

- Represent the open loop transfer function in the standard time constant form.
- Substitute, s=jω in the above equation.

- Find the corner frequencies and arrange them in ascending order.
- Consider the starting frequency of the Bode plot as 1/10th of the minimum corner frequency or 0.1 rad/sec whichever is smaller value and draw the Bode plot upto 10 times maximum corner frequency.
- Draw the magnitude plots for each term and combine these plots properly.
- Draw the phase plots for each term and combine these plots properly.

Note − The corner frequency is the frequency at which there is a change in the slope of the magnitude plot.

Example

Consider the open loop transfer function of a closed loop control system

$$G(s)H(s) = \frac{10s}{(s+2)(s+5)}$$

Let us convert this open loop transfer function into standard time constant form.

$$G(s)H(s) = \frac{10s}{2\left(\frac{s}{2}+1\right)5\left(\frac{s}{5}+1\right)}$$

$$G(s)H(s) = \frac{s}{\left(\frac{s}{2}+1\right)\left(\frac{s}{5}+1\right)}$$

So, we can draw the Bode plot in semi log sheet using the rules mentioned earlier.

Stability Analysis using Bode Plots

From the Bode plots, we can say whether the control system is stable, marginally stable or unstable based on the values of these parameters.

- Gain cross over frequency and phase cross over frequency
- Gain margin and phase margin

Phase Cross over Frequency

The frequency at which the phase plot is having the phase of -180^0 is known as **phase cross over frequency**. It is denoted by ω_{pc}. The unit of phase cross over frequency is **rad/sec**.

Gain Cross over Frequency

The frequency at which the magnitude plot is having the magnitude of zero dB is known as **gain cross over frequency**. It is denoted by ω_{gc}. The unit of gain cross over frequency is **rad/sec**.

The stability of the control system based on the relation between the phase cross over frequency and the gain cross over frequency is listed below.

- If the phase cross over frequency ω_{pc} is greater than the gain cross over frequency ω_{gc}, then the control system is **stable**.
- If the phase cross over frequency ω_{pc} is equal to the gain cross over frequency ω_{gc}, then the control system is **marginally stable**.
- If the phase cross over frequency ω_{pc} is less than the gain cross over frequency ω_{gc}, then the control system is **unstable**.

Gain Margin

Gain margin GM is equal to negative of the magnitude in dB at phase cross over frequency.

$$GM = 20\log\left(\frac{1}{M_{pc}}\right)$$

Where, M_{pc} is the magnitude at phase cross over frequency. The unit of gain margin (GM) is **dB**.

Phase Margin

The formula for phase margin PM is

$$PM=180^0+\phi_{gc}$$

Where, ϕ_{gc} is the phase angle at gain cross over frequency. The unit of phase margin is **degrees**.

The stability of the control system based on the relation between gain margin and phase margin is listed below.

- If both the gain margin GM and the phase margin PM are positive, then the control system is **stable**.
- If both the gain margin GM and the phase margin PM are equal to zero, then the control system is **marginally stable**.
- If the gain margin GM and / or the phase margin PM are/is negative, then the control system is **unstable**

3.1 CLOSED LOOP FREQUENCY RESPONSE-PERFORMANCE SPECIFICATION IN FREQUENCY-FREQUENCY RESPONSE OF STANDARD SECOND ORDER SYSTEM

The response of a system can be partitioned into both the transient response and the steady state response. We can find the transient response by using Fourier integrals. The steady state response of a system for an input sinusoidal signal is known as the **frequency response**. In this chapter, we will focus only on the steady state response.

If a sinusoidal signal is applied as an input to a Linear Time-Invariant (LTI) system, then it produces the steady state output, which is also a sinusoidal signal. The input and output sinusoidal signals have the same frequency, but different amplitudes and phase angles.

Let the input signal be −

$$r(t)=A\sin(\omega_0 t)$$

The open loop transfer function will be −

$$G(s)=G(j\omega)$$

We can represent G(jω) in terms of magnitude and phase as shown below.

$$G(j\omega)=|G(j\omega)|\angle G(j\omega)$$ Substitute,

$\omega=\omega_0$ in the above equation.

$$G(j\omega_0)=|G(j\omega_0)|\angle G(j\omega_0)$$

The output signal is

$$c(t)=A|G(j\omega_0)|\sin(\omega_0 t+\angle G(j\omega_0))$$

- The **amplitude** of the output sinusoidal signal is obtained by multiplying the amplitude of the input sinusoidal signal and the magnitude of G(jω) at $\omega=\omega_0$.
- The **phase** of the output sinusoidal signal is obtained by adding the phase of the input sinusoidal signal and the phase of G(jω)G(jω) at $\omega=\omega_0$.

Where,

- **A** is the amplitude of the input sinusoidal signal.
- $\boldsymbol{\omega_0}$ is angular frequency of the input sinusoidal signal.

We can write angular frequency ω_0 as shown below.

$$\omega_0=2\pi f_0$$

Here, f_0 is the frequency of the input sinusoidal signal. Similarly, you can follow the same procedure for closed loop control system.

Performance Specification in Frequency and Frequency Response of Standard Second Order System:

The frequency domain specifications are **resonant peak, resonant frequency and bandwidth**, **cut-off rate, gain marginKg, phase margin(γ)**

Consider the transfer function of the second order closed loop control system as,

$$T(s)=\frac{C(s)}{R(s)}=\frac{\omega_n^2}{s^2+2\delta\omega_n s+\omega_n^2}$$

Substitute, s=jω in the above equation.

$$T(j\omega)=\frac{\omega_n^2}{(j\omega)^2+2\delta\omega_n(j\omega)+\omega_n^2}$$

$$T(j\omega)=\frac{\omega_n^2}{-\omega^2+2j\delta\omega_n\omega+\omega_n^2}$$

$$T(j\omega)=\frac{1}{\left(1-\frac{\omega^2}{\omega_n^2}\right)+j\left(\frac{2\delta\omega}{\omega_n}\right)}$$

Let, $\omega / \omega_n = u$ Substitute this value in the above equation.

$$T(j\omega)=\frac{1}{(1-u^2)+j(2\delta u)}$$

Magnitude of T(jω) is -

$$M=|T(j\omega)|=\frac{1}{\sqrt{(1-u^2)^2+(2\delta u)^2}}$$

Phase of T(jω) is -

$$\angle T(j\omega)=-\tan^{-1}\left(\frac{2\delta u}{1-u^2}\right)$$

Resonant Frequency:

It is the frequency at which the magnitude of the frequency response has peak value for the first time. It is denoted by ω_r. At $\omega=\omega_r$, the first derivate of the magnitude of T(jω) is zero.

Differentiate M with respect to u.

Differentiate M with respect to u.

$$\frac{dM}{du} = -\frac{1}{2}[(1-u^2)^2 + (2\delta u)^2]^{\frac{-3}{2}}[4u(u^2 - 1 + 2\delta^2)]$$

Substitute, $u=u_r$ and dM / du==0 in the above equation.

$$0 = -\frac{1}{2}[(1-u^2)^2 + (2\delta u)^2]^{\frac{-3}{2}}[4u(u^2 - 1 + 2\delta^2)]$$

$$u_r = \sqrt{1-2\delta^2}$$

Substitute, $u_r=\omega_r / \omega_n$ in the above equation.

$$\frac{\omega_r}{\omega_n} = \sqrt{1-2\delta^2}$$

$$\omega_r = \omega_n\sqrt{1-2\delta^2}$$

Resonant Peak:

It is the peak (maximum) value of the magnitude of T(jω). It is denoted by M_r.

At $u=u_r$, the Magnitude of T(jω) is –

$$M = |T(j\omega)| = \frac{1}{\sqrt{(1-u_r^2)^2 + (2\delta u_r)^2}}$$

Substitute, $u_r = \sqrt{1-2\delta^2}$ and $1 - u_r^2 = 2\delta^2$ in the above equation.

$$M_r = \frac{1}{2\delta\sqrt{1-\delta^2}}$$

Resonant peak in frequency response corresponds to the peak overshoot in the time domain transient response for certain values of damping ratio δδ. So, the resonant peak and peak overshoot are correlated to each other.

Bandwidth:

It is the range of frequencies over which, the magnitude of T(jω) drops to 70.7% from its zero frequency value.

At ω=0 , the value of u will be zero.

Substitute, u=0 in M.

M=1

Therefore, the magnitude of T(jω) is one at ω=0.

At 3-dB frequency, the magnitude of T(jω) will be 70.7% of magnitude of T(jω) at ω=0.

i.e., at $\omega=\omega_B$, $M=0.707(1)=\frac{1}{\sqrt{2}}$

$$M=\frac{1}{\sqrt{2}}=\frac{1}{\sqrt{(1-u_b^2)^2+(2\delta u_b)^2}}$$

$$\Rightarrow 2=(1-u_b^2)^2+(2\delta)^2 u_b{}^2$$

Let, $u_b^2=x$

$$x=\frac{-(4\delta^2-2)\pm\sqrt{(4\delta^2-2)^2+4}}{2}$$

Consider only the positive value of x.

$$x=1-2\delta^2+\sqrt{(2-4\delta^2+4\delta^4}$$

Substitute, $x=u_b^2=\omega_b^2/\omega_n^2$

$$\frac{\omega_b^2}{\omega_n^2}=1-2\delta^2+\sqrt{(2-4\delta^2+4\delta^4}$$

$$\omega_b=\omega_n\sqrt{1-2\delta^2+\sqrt{(2-4\delta^2+4\delta^4}}$$

Bandwidth ω_b in the frequency response is inversely proportional to the rise time t_r in the time domain transient response.

Cut-off rate:

The slope of the log-magnitude curve near the cutoff frequency is called cut-off rate

Gain Margin, K_g:

Gain margin is defined as the value of gain to be added to system in order to bring the system to the verge of instability.

$$Gain\ Margin, K_g = \frac{1}{|G(j\omega_{pc})|}$$

$|G(j\omega_{pc})|$ is the magnitude of $G(j\omega)$ at $\omega = \omega_{pc}$

Phase Margin (γ):

The phase margin is obtained by adding 180^0 to the phase angle φ of the open loop transfer function at the gain cross over frequency

$$\text{Phase margin } \gamma = 180^0 + \varphi_{gc}$$

3.5 COMPENSATORS

The control systems are designed to perform specific tasks. The requirements of a control system are usually specified as performance specification. These specifications are generally related to accuracy relative stability and speed of response.

When a set of specifications are given for a system, then a suitable compensator should be designed so that the overall system will meet the given specification.

The compensator may be electrical, mechanical, hydraulic, pneumatic or other type of device or network.

In Control system, compensation is required in the following situations,

1. When the system is absolutely unstable, then compensation is required to stabilize the system and also to meet the desired performance.
2. When the system is stable, compensation is provided to obtain the desired performance.

There are three types of compensators — lag, lead and lag-lead compensators. These are most commonly used.

Lag Compensator

The Lag Compensator is an electrical network which produces a sinusoidal output having the phase lag when a sinusoidal input is applied. The lag compensator circuit in the 's' domain is shown in the following figure 3.5.1.

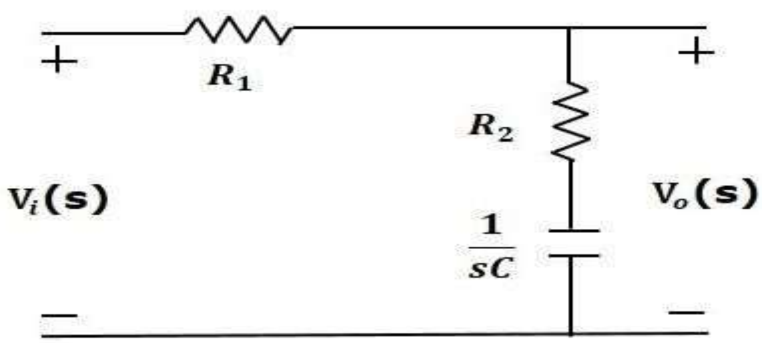

Figure 3.5.1: lag compensator

[Source: "Control System Engineering" by Nagoor Kani, page-5.4]

Here, the capacitor is in series with the resistor R_2 and the output is measured across this combination.

The transfer function of this lag compensator is -

$$\frac{V_o(s)}{V_i(s)} = \frac{1}{\alpha}\left(\frac{s+\frac{1}{\tau}}{s+\frac{1}{\alpha\tau}}\right)$$

Where,

$$\tau = R_2C$$

$$\alpha = (R_1+R_2)/R_2$$

From the above equation, α is always greater than one.

From the transfer function, we can conclude that the lag compensator has one pole at $s=-1/\alpha\tau$ and one zero at $s=-1/\tau$. This means, the pole will be nearer to origin in the pole-zero configuration of the lag compensator.

Substitute, $s=j\omega$ in the transfer function.

$$\frac{V_o(j\omega)}{V_i(j\omega)} = \frac{1}{\alpha}\left(\frac{j\omega+\frac{1}{\tau}}{j\omega+\frac{1}{\alpha\tau}}\right)$$

Phase angle $\phi=\tan^{-1}\omega\tau-\tan^{-1}\alpha\omega\tau$

We know that, the phase of the output sinusoidal signal is equal to the sum of the phase angles of input sinusoidal signal and the transfer function.

So, in order to produce the phase lag at the output of this compensator, the phase angle of the transfer function should be negative. This will happen when $\alpha>1$.

Lead Compensator

The lead compensator is an electrical network which produces a sinusoidal output having phase lead when a sinusoidal input is applied. The lead compensator circuit in the 's' domain is shown in the following figure 3.5.2.

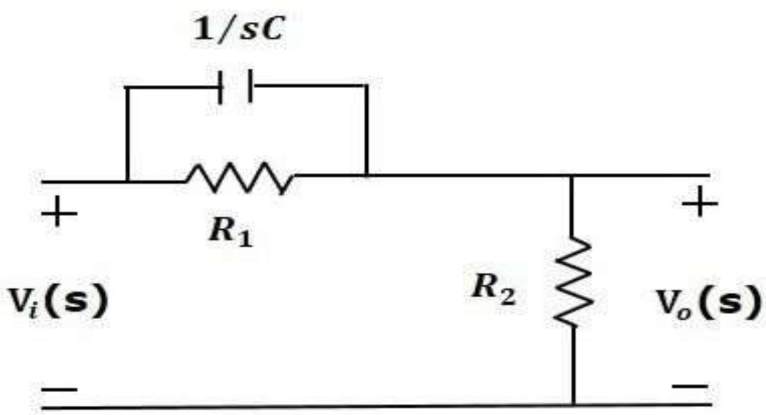

Figure 3.5.2: lead compensator

[Source: "Control System Engineering" by Nagoor Kani, page-5.26]

Here, the capacitor is parallel to the resistor R_1 and the output is measured across resistor R_2.

The transfer function of this lead compensator is -

$$\frac{V_o(s)}{V_i(s)} = \beta(\frac{s\tau + 1}{\beta s\tau + 1})$$

Where, $\tau = R_1C$

$$\beta = R_2 / R_1 + R_2$$

From the transfer function, we can conclude that the lead compensator has pole at s=−1 /β and zero at s=−1/βτ.

Substitute, s=jω in the transfer function.

$$\frac{V_o(j\omega)}{V_i(j\omega)} = \beta(\frac{j\omega\tau + 1}{\beta j\omega\tau + 1})$$

ngle $\phi = \tan^{-1}\omega\tau - \tan^{-1}\beta\omega\tau$

We know that, the phase of the output sinusoidal signal is equal to the sum of the phase angles of input sinusoidal signal and the transfer function.

So, in order to produce the phase lead at the output of this compensator, the phase angle of the transfer function should be positive. This will happen when $0<\beta<1$. Therefore, zero will be nearer to origin in pole-zero configuration of the lead compensator.

Lag-Lead Compensator

Lag-Lead compensator is an electrical network which produces phase lag at one frequency region and phase lead at other frequency region. It is a combination of both the lag and the lead compensators. The lag-lead compensator circuit in the 's' domain is shown in the following figure 3.5.3.

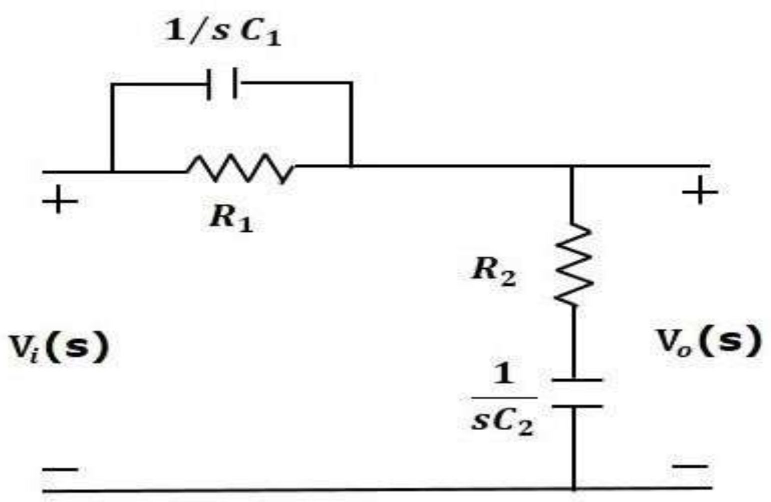

Figure 3.5.3: lag-lead compensator

[Source: "Control System Engineering" by Nagoor Kani, page-5.49]

This circuit looks like both the compensators are cascaded. So, the transfer function of this circuit will be the product of transfer functions of the lead and the lag compensators.

$$\frac{V_o(s)}{V_i(s)} = \beta\left(\frac{s\tau_1 + 1}{\beta s\tau_1 + 1}\right)\frac{1}{\alpha}\left(\frac{s + \frac{1}{\tau_2}}{s + \frac{1}{\alpha\tau_2}}\right)$$

We know $\alpha\beta=1$.

$$\frac{V_o(s)}{V_i(s)} = \left(\frac{s + \frac{1}{\tau_1}}{s + \frac{1}{\beta\tau_1}}\right)\left(\frac{s + \frac{1}{\tau_2}}{s + \frac{1}{\alpha\tau_2}}\right)$$

Where,

$$\tau_1=R_1C_1$$

$$\tau_2=R_2C_2$$

3.6 DEIGN OF COMPENSATOR USING BODE PLOT

Procedure for the design of LAG Compensator:

The following steps may be followed to design a lag compensator

1. Choose the value of K in uncompensated system to meet the steady state error requirement
2. sketch the bode plot of uncompensated system
3. Determine the phase margin of the uncompensated system from the bode plot. If the phase margin does not satisfy the requirement then the lag compensation is required
4. Choose suitable vale for the phase margin of the compensated system.

   Let γ_d=desired phase margin as given in specification.

   γ_n=phase margin of compensated system.

   now $\gamma_n = \gamma_d + \epsilon$

   where ϵ-additional phase lag to compensate for shift in gain crossover frequency. Choose an initial value of $\epsilon = 5^0$

5. Determine the new gain crossover frequency ω_{gcn}. the new ω_{gcn} is the frequency corresponding to a phase margin of γ_n on the bode plot of uncompensated system.

   Let φ_{gcn}=phase of G(jω) at new gain crossover frequency ω_{gcn}

   The new gain crossover frequency is given by the frequency ω_{gcn} at which the phase of G(jω) is φ_{gcn}
6. Determine the parameter β of the compensator. the value of β is given by the magnitude of G(jω) at ne gain crossover frequency ω_{gcn}. find the db gain (A_{gcn}) at ne gain crossover frequency ω_{gcn}

$$A_{gcn} = 20 log \beta$$

$$\beta = 10^{Agcn/10}$$

7. Determine the transfer function of lag Compensator

   Place the zero of the compensator arbitrarily at 1/10th of the new gain crossover frequency ω_{gcn}

   Now T=10/ ω_{gcn}

   Pole of the lag compensator p_c=1 /βT

Transfer function of the lag compensator $G_c(s) = \frac{s+\frac{1}{T}}{S+\frac{1}{\beta T}}$

8. Determine the open loop transfer function of compensated system. The lag compensator is connected in series with plant

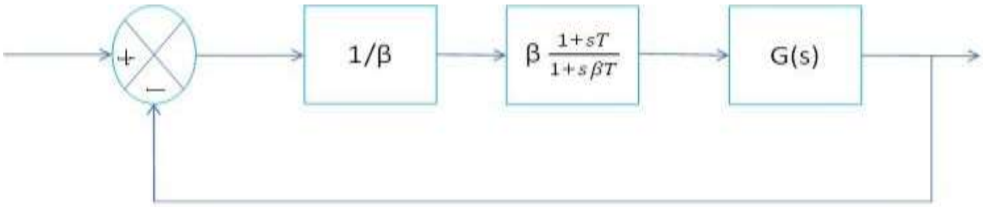

Figure 3.6.1: block diagram of lag compensated system

[Source: "Control System Engineering" by Nagoor Kani, page-5.30]

$$G_o(s) = \frac{(1 + sT)}{(1 + s\beta T)} G(s)$$

9. Determine the actual phase margin of compensated system. Calculate the actual phase angle of the Compensated system using the compensated transfer function at ne gain crossover frequency ω_{gcn} actual phase margin of the compensated system $\gamma_n=180^0+\varphi_{gco}$.

   If the actual phase margin satisfies the given specification then the design is accepted. Otherwise repeat the procedure from step 4 to 9 by taking ϵ as 5^0 more than previous design.

Procedure for the design of LEAD Compensator:

The following steps may be followed to design a lead compensator

1. The open loop gain K of the given system is determined to satisfy the requirement of the error constant
2. sketch the bode plot of uncompensated system
3. Determine the phase margin of the uncompensated system from the bode plot.
4. Determine the amount of phase angle to be contributed by the lead network by using the formula given.

$$\Phi_m = \gamma_d - \gamma + \epsilon$$

Let γ_d=desired phase margin as given in specification.

γ=phase margin of uncompensated system.

where ϵ-additional phase lag to compensate for shift in gain crossover frequency. Choose an initial value of ϵ=5^0

5. Determine the transfer function of lead Compensator

   Calculate α using the equation $\alpha = \frac{1-sin\varphi m}{1+sin\varphi m}$

   Calculate T from the relation $T = \frac{1}{\omega m}$

   Transfer function of the lead compensator

   $G_c(s) = \frac{s+\frac{1}{T}}{S+\frac{1}{\beta T}}$

6. Determine the open loop transfer function of compensated system. The lead compensator is connected in series with plant

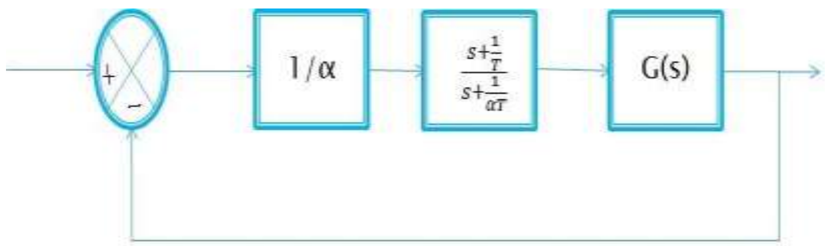

Figure 3.6.2: block diagram of lead compensated system

[Source: "Control System Engineering" by Nagoor Kani, page-5.53]

$$G_o(s) = \frac{(1+sT)}{(1+saT)}G(s)$$

7. Verify the design. Finally the bode plot of the compensated system is drawn and verify whether it satisfy the given specifications. If the phase margin of the compensated system is less than the required phase margin repeat the procedure from step 4 to 9 by taking ϵ as 5^0 more than previous design.

3.4 NYQUIST PLOT

Nyquist plots are the continuation of polar plots for finding the stability of the closed loop control systems by varying ω from $-\infty$ to ∞. That means, Nyquist plots are used to draw the complete frequency response of the open loop transfer function.

Nyquist Stability Criterion

The Nyquist stability criterion works on the **principle of argument**. It states that if there are P poles and Z zeros are enclosed by the 's' plane closed path, then the corresponding G(s)H(s) plane must encircle the origin P−Z times. So, we can write the number of encirclements N as,

$$N=P-Z$$

- If the enclosed 's' plane closed path contains only poles, then the direction of the encirclement in the G(s)H(s) plane will be opposite to the direction of the enclosed closed path in the 's' plane.
- If the enclosed 's' plane closed path contains only zeros, then the direction of the encirclement in the G(s)H(s) plane will be in the same direction as that of the enclosed closed path in the 's' plane.

Let us now apply the principle of argument to the entire right half of the 's' plane by selecting it as a closed path. This selected path is called the **Nyquist** contour.

We know that the closed loop control system is stable if all the poles of the closed loop transfer function are in the left half of the 's' plane. So, the poles of the closed loop transfer function are nothing but the roots of the characteristic equation. As the order of the characteristic equation increases, it is difficult to find the roots. So, let us correlate these roots of the characteristic equation as follows.

- The Poles of the characteristic equation are same as that of the poles of the open loop transfer function.
- The zeros of the characteristic equation are same as that of the poles of the closed loop transfer function.

We know that the open loop control system is stable if there is no open loop pole in the right half of the 's' plane.

$$\text{i.e.,} P=0 \Rightarrow N=-Z$$

We know that the closed loop control system is stable if there is no closed loop pole in the right half of the ‘s’ plane.

$$i.e., Z=0 \Rightarrow N=P$$

Nyquist stability criterion states the number of encirclements about the critical point (1+j0) must be equal to the poles of characteristic equation, which is nothing but the poles of the open loop transfer function in the right half of the ‘s’ plane. The shift in origin to (1+j0) gives the characteristic equation plane.

Rules for Drawing Nyquist Plots

Follow these rules for plotting the Nyquist plots.

- Locate the poles and zeros of open loop transfer function G(s)H(s) in ‘s’ plane.
- Draw the polar plot by varying ω from zero to infinity. If pole or zero present at s = 0, then varying ωω from 0+ to infinity for drawing polar plot.
- Draw the mirror image of above polar plot for values of ω ranging from − to zero (0^- if any pole or zero present at s=0).
- The number of infinite radius half circles will be equal to the number of poles or zeros at origin. The infinite radius half circle will start at the point where the mirror image of the polar plot ends. And this infinite radius half circle will end at the point where the polar plot starts.

After drawing the Nyquist plot, we can find the stability of the closed loop control system using the Nyquist stability criterion. If the critical point (-1+j0) lies outside the encirclement, then the closed loop control system is absolutely stable.

Stability Analysis using Nyquist Plots

From the Nyquist plots, we can identify whether the control system is stable, marginally stable or unstable based on the values of these parameters.

- Gain cross over frequency and phase cross over frequency
- Gain margin and phase margin

Phase Cross over Frequency

The frequency at which the Nyquist plot intersects the negative real axis (phase angle is 180^0) is known as the **phase cross over frequency**. It is denoted by ω_{pc}.

Gain Cross over Frequency

The frequency at which the Nyquist plot is having the magnitude of one is known as the **gain cross over frequency**. It is denoted by ω_{gc}.

The stability of the control system based on the relation between phase cross over frequency and gain cross over frequency is listed below.

- If the phase cross over frequency ω_{pc} is greater than the gain cross over frequency ω_{gc}, then the control system is **stable**.
- If the phase cross over frequency ω_{pc} is equal to the gain cross over frequency ω_{gc}, then the control system is **marginally stable**.
- If phase cross over frequency ω_{pc} is less than gain cross over frequency ω_{gc}, then the control system is **unstable**.

Gain Margin

The gain margin GM is equal to the reciprocal of the magnitude of the Nyquist plot at the phase cross over frequency.

$$GM = 1 / M_{pc}$$

Where, M_{pc} is the magnitude in normal scale at the phase cross over frequency.

Phase Margin

The phase margin PM is equal to the sum of 180^0 and the phase angle at the gain cross over frequency.

$$PM = 180^0 + \phi_{gc}$$

Where, ϕ_{gc} is the phase angle at the gain cross over frequency.

The stability of the control system based on the relation between the gain margin and the phase margin is listed below.

- If the gain margin GM is greater than one and the phase margin PM is positive, then the control system is **stable**.
- If the gain margin GM is equal to one and the phase margin PM is zero degrees, then the control system is **marginally stable**.
- If the gain margin GM is less than one and / or the phase margin PM is negative, then the control system is **unstable**.

3.3 POLAR PLOT

In Bode plot we have two separate plots for both magnitude and phase as the function of frequency. Let us now discuss about polar plots. Polar plot is a plot which can be drawn between magnitude and phase. Here, the magnitudes are represented by normal values only.

The polar form of G(jω) H(jω) is

$$G(j\omega)H(j\omega)=|G(j\omega)H(j\omega)|\ \angle G(j\omega)H(j\omega)$$

The **Polar plot** is a plot, which can be drawn between the magnitude and the phase angle of G(jω)H(jω) by varying ω from zero to . The polar graph sheet is shown in the following figure 3.3.1.

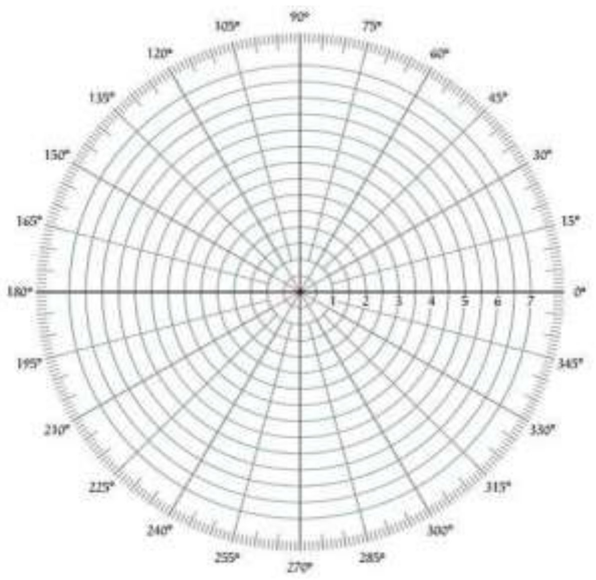

Figure 3.3.1: polar graph

[Source: "Control System Engineering" by Nagoor Kani, page-3.37]

This graph sheet consists of concentric circles and radial lines. The **concentric circles** and the **radial lines** represent the magnitudes and phase angles respectively. These angles are represented by positive values in anti-clock wise direction. Similarly, we can represent angles with negative values in clockwise direction. For example, the angle 270^0 in anti-clock wise direction is equal to the angle -90^0 in clockwise direction.

Rules for Drawing Polar Plots

Follow these rules for plotting the polar plots.

- Substitute, s=jω in the open loop transfer function.
- Write the expressions for magnitude and the phase of G(jω)H(jω).
- Find the starting magnitude and the phase of G(jω)H(jω) by substituting ω=0. So, the polar plot starts with this magnitude and the phase angle.
- Find the ending magnitude and the phase of G(jω)H(jω) by substituting ω= . So, the polar plot ends with this magnitude and the phase angle.
- Check whether the polar plot intersects the real axis, by making the imaginary term of G(jω)H(jω) equal to zero and find the value(s) of ω.
- Check whether the polar plot intersects the imaginary axis, by making real term of G(jω)H(jω) equal to zero and find the value(s) of ω.
- For drawing polar plot more clearly, find the magnitude and phase of G(jω)H(jω) by considering the other value(s) of ω.

Example

Consider the open loop transfer function of a closed loop control system.

$$G(s)H(s) = \frac{5}{s(s+1)(s+2)}$$

Let us draw the polar plot for this control system using the above rules.

Step 1 – Substitute, s=jω in the open loop transfer function.

$$G(j\omega)H(j\omega) = \frac{5}{j\omega(j\omega+1)(j\omega+2)}$$

The magnitude of the open loop transfer function is

$$M = \frac{5}{\omega(\sqrt{\omega^2+1})(\sqrt{\omega^2+4})}$$

The phase angle of the open loop transfer function is

$$\phi = -90^0 - \tan^{-1}\omega - \tan^{-1}\omega/2$$

Step 2 − The following table shows the magnitude and the phase angle of the open loop transfer function at ω=0 rad/sec and ω= rad/sec.

Frequency (rad/sec)	Magnitude	Phase angle(degrees)
0	∞	-90 or 270
∞	0	-270 or 90

So, the polar plot starts at (,-90^0) and ends at (0,-270^0). The first and the second terms within the brackets indicate the magnitude and phase angle respectively.

Step 3 − Based on the starting and the ending polar co-ordinates, this polar plot will intersect the negative real axis. The phase angle corresponding to the negative real axis is -180^0 or 180^0. So, by equating the phase angle of the open loop transfer function to either -180^0 or 180^0, we will get the ω value as $\sqrt{2}$.

By substituting $\omega=\sqrt{2}$ in the magnitude of the open loop transfer function, we will get M=0.83. Therefore, the polar plot intersects the negative real axis when ω=√ and the polar coordinate is (0.83,-180^0).

So, we can draw the polar plot with the above information on the polar graph sheet