

Problem 1 (30 % , 計算題)

Consider the following equation:

$$s^2(s+10) + K(s+1) = 0.$$

Draw the root locus of the above equation for the different values of K, from K=0 to K=∞.

Problem 2 (30 % , 計算題)

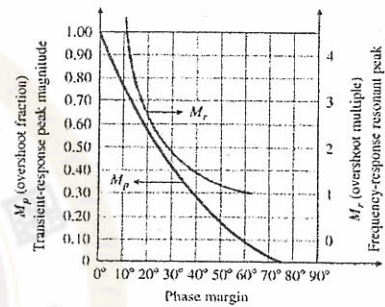
Consider the transfer function of a satellite tracking antenna as follows:

$$G(s) = \frac{1}{s(s+1)},$$

and the design specifications in time domain as follows:

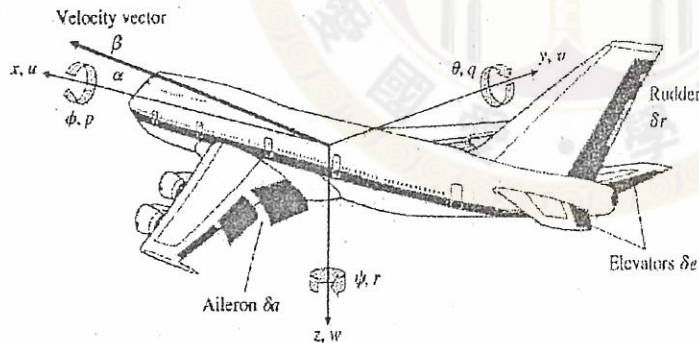
- (a) The steady-state error is less than 0.1 for a unit ramp input;
- (b) An overshoot < 25%.

Please use frequency-response approach, that is, in terms of Bode plot, to design a lead compensator satisfying the above specifications. For your reference, the relationship between the overshoot and the phase margin is shown in the right-hand-side figure.



Problem 3 (20 % , 申論題)

Consider the schematic picture of the Boeing 747 shown in the following figure.



- x, y, z = position coordinates
- u, v, w = velocity coordinates
- p = roll rate
- q = pitch rate
- r = yaw rate
- ϕ = roll angle
- θ = pitch angle
- ψ = yaw angle
- β = side-slip angle
- α = angle of attack

Assume that the nonlinear rigid body equations of motion in body-axis coordinates are derived as follows:

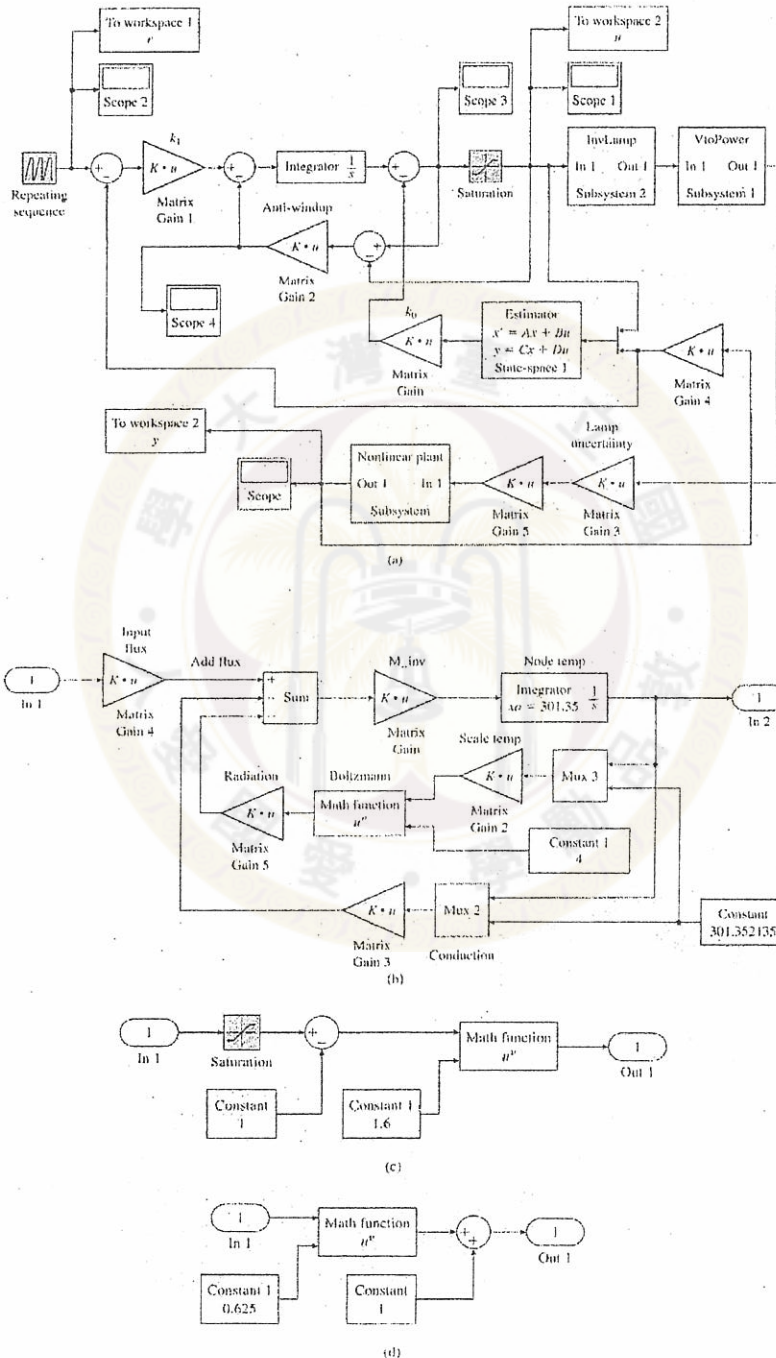
$$\begin{aligned} m(\dot{U} + qW - rV) &= X - mg \sin \theta + \kappa T \cos \theta \\ m(\dot{V} + rU - pW) &= Y + mg \cos \theta \sin \phi \\ m(\dot{W} + pV - qU) &= Z + mg \cos \theta \cos \phi - \kappa T \sin \theta \\ I_x \dot{p} + I_{xz} \dot{r} + (I_z - I_y)qr + I_{xz}qp &= L \\ I_y \dot{q} + (I_x - I_z)pr + I_{xz}(r^2 - p^2) &= M \\ I_z \dot{r} + I_{xz} \dot{p} + (I_y - I_x)qp - I_{xz}qr &= N \end{aligned}$$

where m is the mass, I_i 's are the inertia, $[U V W]$ are linear velocity, $[p q r]$ are angular velocity, $[X Y Z]$ are aerodynamic forces, and $[L M N]$ are aerodynamic torques. If you are the control engineer to design proper lateral and longitudinal controllers for the airplane, please discuss the procedures and/or methodologies in detail.

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Problem 4 (20 % , 申論題)

Consider the following Simulink diagram for one closed-loop system:



where (a) denotes the closed-loop system; (b) is the detail of the subsystem: nonlinear plant in (a); (c) is the detail of the subsystem: VtoPower in (a); and (d) is the detail of the subsystem: InvLamp in (a). If you are a control engineer and your task is to analyze the above Simulink diagram and diagnose the closed-loop system. Please discuss your analysis in detail.

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