

(英文版)

# 控制系统基础

**Elements of Control Systems** 

(美) 苏希尔·古普塔 (Sudhir Gupta) 著





#### 时代教育・国外高校优秀教材精选

## 控制系统基础

(英文版)

## **Elements of Control Systems**

(美)苏希尔·古普塔(Sudhir Gupta) 著



机械工业出版社

English reprint copyright ©2004 by Pearson Education North Asia Limited and China Machine Press.

Original English Language title: Elements of Control Systems by Sudhir Gupta

ISBN 0-13-010310-1

Copyright ©2002 by Pearson Education, Inc.

All right reserved.

Published by arrangement with the original publisher, Pearson Education, Inc.

本书影印版由 Pearson Education(培生教育出版集团)授权给机械工业出版社出版发行。

For sale and distribution in the People's Republic of China exclusively (except Taiwan, Hong Kong SAR and Macao SAR)

仅限于中华人民共和国境内(不包括中国香港、澳门特别行政区和中国台湾地区)销售发行。

北京市版权局著作权合同登记号: 图字: 01-2004-1644

本书封面贴有 Pearson Education(培生教育出版集团)激光防伪标签。无标签者不得销售。

#### 图书在版编目 (CIP) 数据

控制系统基础: Elements of Control Systems/(美)古普塔(Sudhir,G.)著.一北京: 机械工业出版社, 2004.7 时代教育·国外高校优秀教材精选 ISBN 7-111-14768-5.

1. 控 **L∞**齿. **II** 控制系统理论—高等学校 一教材**→元文 IV** 0231

中国版本版 馆 CIP 数据核字(2004)第 060208 号

机械工业出版社 (北京市百万庄大街22号 邮政编码100037)

责任编辑, 苏颖太。

封面设计: 饶 薇 责任印制: 施 红

北京铭成印刷有限公司印刷・新华书店北京发行所发行

2004年7月第1版第1次印刷

787mm×1092mm 1/16・37.25 印张・916 千字

定价: 54.00 元

凡购本书,如有缺页、倒页、脱页,由本社发行部调换本社购书热线电话(010)68993821、88379646封面无防伪标均为盗版

## 国外高校优秀教材审定委员会

主任委员:

杨叔子

委员(按姓氏笔画为序):

丁丽娟	王先逵	王大康	白峰衫	石德珂
史荣昌	孙 洪 祥	朱孝禄	陆启韶	张润琦
张 策	张三慧	张福润	张延华	吴 宗 泽
吴 麒	宋心琦	李俊峰	佘 远 斌	陈文楷
陈立周	单辉祖	周双喜	范 瑜	俞正光
赵汝嘉	郭可谦	翁 贻 方	翁海珊	龚光鲁
音 栋 因	黄永畅	遭 泽 光	朝 油 志	

## 出版说明

随着我国加入 WTO, 国际间的竞争越来越激烈, 而国际间的竞争实际上也就是人才的竞争、教育的竞争。为了加快培养具有国际竞争力的高水平技术人才, 加快我国教育改革的步伐, 国家教育部近来出台了一系列倡导高校开展双语教学、引进原版教材的政策。以此为契机, 机械工业出版社陆续推出了一系列国外影印版教材, 其内容涉及高等学校公共基础课,以及机、电、信息领域的专业基础课和专业课。

引进国外优秀原版教材,在有条件的学校推动开展英语授课或双语教学,自然也引进了先进的教学思想和教学方法,这对提高我国自编教材的水平,加强学生的英语实际应用能力,使我国的高等教育尽快与国际接轨,必将起到积极的推动作用。

为了做好教材的引进工作,机械工业出版社特别成立了由著名专家组成的国外高校优秀教材审定委员会。这些专家对实施双语教学做了深入细致的调查研究,对引进原版教材提出了许多建设性意见,并慎重地对每一本将要引进的原版教材一审再审,精选再精选,确认教材本身的质量水平,以及权威性和先进性,以期所引进的原版教材能适应我国学生的外语水平和学习特点。在引进工作中,审定委员会还结合我国高校教学课程体系的设置和要求,对原版教材的教学思想和方法的先进性、科学性严格把关。同时尽量考虑原版教材的系统性和经济性。

这套教材出版后,我们将根据各高校的双语教学计划,举办原版教材的教师培训,及时地将其推荐给各高校选用。希望高校师生在使用教材后及时反馈意见和建议,使 我们更好地为教学改革服务。

机械工业出版社

Elements of Control Systems 由 Sudhir Gupta 编著,2002 年出版。本书的内容是经典控制理论的基本方法和自动控制的常用技术,主要包括线性连续控制系统的建模、瞬态响应分析、频率响应分析、稳定性分析、各种控制器的整定与系统设计等等。

从本书的体系结构和内容取舍可见,作为自动控制理论课程的教材,本书具有如下特点:

- 1. 书中对概念的定义严格,讲述详细,深入浅出,较少从纯数学角度的推导,侧重从物理意义直观地解释问题,为说明概念的举例,浅显易懂。
- 2. 全书的工程实践背景强,例题量大,且结合工程实际。如在开关控制(第9章)一章中,给出了温度开关控制、步进电动机开关控制的实际电路图等,并进行分析,这对于未接触过实际控制系统的在校学生,是很有启发和帮助的。
- 3. 全书的章节安排和内容与国内目前使用的大多数教材不同,如不包括稳态误差分析、非线性系统分析等内容,根轨迹的内容也缩减为稳定性分析(第8章)—章中的一节。在 MATLAB 控制系统工具箱普遍应用的今天,对根轨迹内容的缩减,可使学生把注意力集中在用根轨迹方法分析系统上,而不是如何绘制根轨迹上。
- 4. 书中用大量篇幅(第9~13章)讲述各种实用的控制器,包括开关控制器、模拟控制器、数字控制器、模糊控制器。对这部分内容的侧重,有利于工程实践观念的培养。
- 5. 书中将自动控制理论和自动控制系统紧密结合起来,通过控制系统的实例分析,不仅帮助理解控制理论,而且有助于掌握常见控制系统的工作原理。
- 6. 在语言方面,全书文字流畅、易读。本科生在学完大学英语,并掌握一定的专业词汇后,较易阅读本书。

本书可作为高等院校本科电子信息类专业自动控制理论课程教材或教学参考书, 也可供相关专业研究生参考或从事自动化技术的工程技术人员作为自学读物。

> 北京工商大学 翁贻方 2004 年1月

## PREFACE ...

There are a number of excellent textbooks covering the subject of control engineering at the engineering level. These books are typically written for a two-semester course in control engineering or for an intense one-semester course in the senior year. As is typical of engineering textbooks, these treat control theory from a mathematical point of view.

Elements of Control Systems does not do that. This book is suitable for

- Two- or four-year college programs requiring an in-depth understanding of control systems
- A one-semester university course at the freshman level
- Industry personnel interested in developing a greater understanding of control principles

It has been very difficult to decide on the precise content of such a textbook. It is not a handbook, so it cannot contain every single aspect of it, and it is not a "how-to" recipe book focusing on very specific topics. An attempt has been made to cover the major topics in control system technology. It should permit the reader to develop sufficient understanding to operate, maintain, and regulate control systems. At the same time, it should permit the reader to design and develop basic control systems.

No attempt has been made to cover PLCs or their operation or programming. This topic is a field in itself, and a chapter in this text could not have done justice to it.

#### viii Preface

Even though a number of PLCs have begun to offer continuous control modules, their primary application is in digital I/O and not in process control.

Sensors, transducers, and actuators form an important segment of control technology, but so do microcontrollers, data converters, and instrumentation interface circuits. These again have not been covered in lieu of more relevant subject matter.

Where possible, an attempt has been made to point out the issues with circuit components and their impact on system operations. A chapter has been dedicated to digital control, still treating it from the classical control point of view. A chapter on fuzzy logic control provides a solid introduction to the topic. An attempt has been made to avoid excessive use of some of the cryptic terms commonly used with fuzzy control.

#### How to Use the Book

The book consists of two major sections: the first part covers control system theory and the second part covers controllers and their applications.

It is important that the first part be studied with some diligence. The reader should be fully comfortable with the notions of time and frequency response before tackling controllers and their applications. The first chapter introduces the concept of a control system. The second chapter covers block diagrams, followed by a chapter on Laplace transformation. Laplace transformation is covered with an application-oriented approach. It is not intended to provide a solid foundation in operational calculus but apply it to determine system transfer functions in the following chapter on mathematical modeling. Having an understanding of the origin of transfer functions, time and frequency response techniques are covered. The discussion on stability is the coverage on controllers. It is intended to develop awareness for the consequences of improper controller selection and adjustment.

The second part of the book deals with controllers, their operation, adjustment, and analog and digital implementation. Some of these topics can actually be studied independently of the first, but it is not recommended. The section on digital controllers requires some understanding of microcontrollers and their programming. Annotated software listings have been provided in each case.

I would like to thank a number of people who have provided valuable support for this book project: Charles Stewart, publisher at Prentice Hall for his acceptance of the initial manuscript and his encouraging words; my copyeditor, Linda Thompson and project editor, Lisa Garboski, for their skills and painstaking effort; Eric Sells and Al Lovrich of Microchip Technology; Mark Siegesmund of CCS, Inc.; and Naomi Fernandes of The MathWorks Inc.

Many thanks also should go to the reviewers: Jeff Slutsky, Rochester Institute of Technology; Richard L. Windley, ECPI College of Technology; C. Richard G. Helps, Brigham Young University; John Glozy, DeVry Institute of Technology; and Dr. Nebojsa Jaksic, DeVry Institute of Technology.

I would also like to thank my family: my wife Nita for putting up with my spending countless hours working on the manuscript, my son Sachin for very valuable help with computer work, and my daughter Avina for help in transforming the handwritten notes into a printed document. Above all I would like to thank them for their constant encouragement.

#### **Feedback**

This being the first edition, it is possible that mistakes may have been made, in spite of the best efforts of the author and the publisher. It would be greatly appreciated if you can point these out. Any kind of constructive criticism is welcome.

Sudhir K. Gupta sgupta@mcjournal.com

## CONTENTS

v
vii
1
13

#### **xii** Contents

	Comparison of Positive-Feedback and	
	Negative-Feedback Systems 22 Unity Feedback Systems 28	
	Conversion to a Unity Feedback System 28	
	Block Diagram Simplification 29	
	Op-Amp Simulation of a Block Diagram 34	
	Summing Point 35	
	Summing Point with Adjustable SP Input 36	
	Gain Block 38	
	Constant-Gain (Noninverting) Block 38	
	Constant-Gain (Inverting) Block 41	
	Takeoff Point 41	
	Summing Point with Multiple Inputs 42	
	Problems 50	
^		
J	LAPLACE TRANSFORMS	54
	Introduction 54	
	Transformations 54	
	Laplace Transform Integral 55	
	Transform Notation 56	
	Rules of Transformation 56	
	Forward Transformation Procedure 61	
	Inverse Transformation Procedure 67 Partial-Fraction Expansion 79	
	Distinct Roots 80	
	Repeated Roots 81	
	Applications of Laplace Transforms:	
	Differential Equations 88	
	Problems 93	•
4	MATHEMATICAL MODELING	97
	Introduction 97	
	Mathematical Model 98	
	Nonlinear Behavior 98	
	Transfer Functions 99	
	Electrical Networks 100	
	Resistor 101	
	Capacitor 101	

Series RC Circuit 103 Series RL Circuit 105 Series *RLC* Circuit 107 Mechanical Systems 112 Mass 112 Spring 113 113 Damper Spring Mass Damper System 114 Analogy Between Physical Systems 116 Fluid Systems 117 Single-Tank Fluid-Level System 117 Two-Tank Fluid-Level System 119 Thermal Systems 122 **Heating Systems** 123 **Problems** 124

102

#### **5 TRANSIENT RESPONSE**

Inductor

127

Introduction 127 Time Response 127 **Input Functions** 129 Step Function 129 Pulse Function 131 Impulse Function 132 Delayed Impulse Function 133 Ramp Function 134 Sinusoidal Function Types of Transient Responses 135 Overdamped Response 135 Critically Damped Response 136 136 Underdamped Response Constant Oscillations 137 **Increasing Oscillations** 137 **Exponential Rise** 138 Transient Response Through Laplace Transformation 138 Impulse Function Response 144 Characteristic Equation 148 Poles and Zeros of the Transfer Function

151

•	_
XIV	Contents

 $s ext{-Plane}$  and Pole-Zero Map

	Pole Location and Transient Response 155 Problems 160	
6	FREQUENCY RESPONSE	162
	Introduction 162 Methods Used for Frequency Response Representation 164 Frequency Response Determination 166	
	Problems 186	
7	COMMON TRANSFER FUNCTIONS	189
	Introduction 189 Common Blocks (Transfer Functions) 191 Constant Block 192 Time Response of a Constant TF 195 Frequency Response of a Constant Block 195 Integral Block 198 Time Response of an Integral Block 198 Frequency Response of an Integral Block 200 Derivative Block 203 Time Response of a Derivative Block 204 Frequency Response of a Derivative Block 204 The Relationship Between Integral and Derivative Blocks 208 First-Order Lag Block 208 First-Order Lag Block 208 Time Response to a Unit Step Input 209 Frequency Response of a First-Order Lag Block 213 First-Order Lead Block 219 Time Response to a Unit Step Input 220 Frequency Response of a First-Order Lead Block 220 Second-Order Lag Block 224 Time Response to a Unit Step Input 225 Characteristics of Underdamped Response 231	
	Frequency Response of a Second-Order  Lag Block 234  Second-Order Lead Block 238	

153

Time Response to a Unit Step Input 240 Frequency Response of a Second-Order Lead Block 240 Dead Time: Transportation Lag Block 241 Time Response to a Unit Step Input 243 Frequency Response of a Dead-Time Block 243 Problems 244	
8 STABILITY	248
Introduction 248 Concept of Stability 248 Stability and the Open-Loop Transfer Function 252 Open-Loop Gain and Operating Frequency 255 Stability from a Bode Plot 259 Gain and Phase Margins 261 Gain and Phase Crossover Frequencies 261 Gain Margin (GM) 261 Phase Margin (PM) 263 Desired Gain and Phase Margins 264 Stability from the Characteristic Equation 269 Routh Criterion for Stability 271 Root Locus Analysis 278 Root Locus Through MATLAB 281 Problems 288	
9 CONTROLLERS: THE ON-OFF CONTROLLER  Introduction 291 Role of a Controller 291 Types of Controllers 292 Use of a Percent as Input and Output 293 Measured Value as a Percentage Value 295 Set Point as a Percentage Value 296 Error as a Percentage Value 296 On-Off Control 298 Types of On-Off Control 298 Electronic Implementation (Analog) 299 Two-Position Control 303 Neutral Zone 304 Controller Action 306	291

<b>XVi</b> Contents	
Applications 308	
Electronic Implementation 309	
Multiposition (Floating) Control 315	
Problems 315	
10 ANALOG CONTROLLER I	318
Introduction 318	
Proportional Controller (P) 318	
Transfer Characteristic 319	
Proportional Band 321	
Relationship Between Percent Output	
and Physical Controller Output 322	
Electronic Implementation 326	
Frequency Response of	
a Proportional Controller 332	
Proportional Control of a Closed Loop 334	
Steady-State Operation with Zero Error 339	
Proportional Controller with Offset 346 Offset Voltage Adjustment 346	
Integral Controller (I) 346	
Electronic Implementation 353	
Limiting DC Gain 354	
Frequency Response of an Ideal	
Integral Controller 355	
Frequency Response of a DC Gain-Limited	
Integral Controller 356	
Derivative Controller (D) 359	
Electronic Implementation 365	
Frequency Response of a Derivative	
Controller 366	
Limiting High-Frequency Gain 367	
Problems 375	
11 ANALOG CONTROLLER II	378
Introduction 378	

378

379

383

379

Electronic Implementation of a PI Controller

Frequency Response of a PI Controller

Composite Controller Modes

PI Controller

Serial Implementation

Parallel Implementation

PD Controller 391 Electronic Implementation of a PD Controller 393 Frequency Response of a PD Controller 395 PID Controller 400 Electronic Implementation 410 Changing the Operating Mode 412 Frequency Response of a PID Controller 412 Problems 417	
12 DIGITAL CONTROLLER	420
Introduction 420 Digital Controller 421 Controller Sequence of Operation 422 Considerations for Digital Control 424 Digital Two-Position Control 426 Sequence of Operation 426 Microcontroller Implementation of a Two-Position Controller 427 Digital PID Controller 433 Analog PID Algorithm 433 Digital PID Algorithm 433 Zero-Order Hold (ZOH) 435 Ideal Digital PID Algorithm 440 Discrete PID Algorithm—BASIC Language 440 Manual Control Mode 442 Velocity Algorithm 443 Improved Derivative Term 444 Microcontroller Implementation of a PID Controller 445 DC Motor Control 445 Control Software Description 448 Problems 453	
13 FUZZY CONTROLLER	455
Introduction 455 Continuum World 455 Conventional Logic 457 Fuzzy Logic and Fuzzy Logic Terminology 457 Fuzzy Control System 475 Problem Identification 476 Conceptual Design 476 Problems 487	

#### xviii Contents

14 CONTROLLER TUNING AND SYSTEM DESIGN	N 491
Introduction 491 Performance Criteria 492 Controller Tuning 492 Controller Tuning: Known Plant Model 493	•
Plant Model from Experimental Response Testing Step Response Test 504 Graphical Analysis 505 Computational Method 508 Frequency Response Test 511	504
Experimental Determination of Controller Setting Continuous Cycling Method 518 Reaction Curve Method 519	518
Case Study: Machine Positional Control System Drive Mechanism 522 Position Transducer 522 Problems 530	521
15 ADDITIONAL CONTROL TECHNIQUES	533
Introduction 533 Feedforward Control 533 Disturbance Signal 534 Ratio Control 537 Cascade Control 537 Autotuning Controller 539 State-Space Techniques 540 State Variables 540 State Equations 540 Transfer Function to State-Space Representation 543 Problems 545	
BIBLIOGRAPHY	547
APPENDIX A MATLAB	549
GLOSSARY	559
INDEX 教辅材料申请表	565