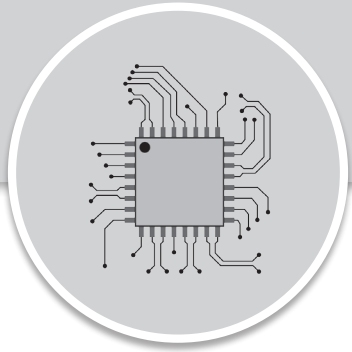
ELECTRONICS ENGINEERING

CONTROL SYSTEMS



Comprehensive Theory
with Solved Examples *and* Practice Questions

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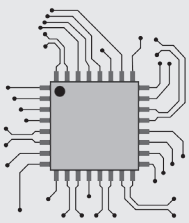
Control Systems



EDITIONS

First Edition : 2015
Second Edition : 2016
Third Edition : 2017
Fourth Edition : 2018
Fifth Edition : 2019
Sixth Edition : 2020
Seventh Edition : 2021
Eighth Edition : 2022
Ninth Edition : 2023

Tenth Edition : 2024

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2

Transfer Function

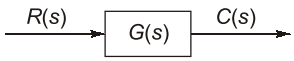
2.1 TRANSFER FUNCTION AND IMPULSE RESPONSE FUNCTION

In control theory, transfer functions are commonly used to characterise the input-output relationships of components or systems that can be described by linear, time-invariant differential equations.

Transfer Function

The transfer function of a linear, time-invariant, differential equation system is defined as the ratio of the Laplace transform of the output (response function) to the Laplace transform of the input (driving function) under the assumption that all initial conditions are zero.

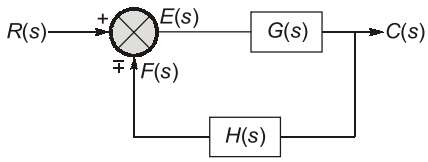
Transfer Function of Open Loop System :



$$G(s) = \frac{C(s)}{R(s)}$$

Transfer Function of Closed Loop System :

Transfer function of closed loop system



$$\frac{C(s)}{R(s)} = \frac{G(s)}{1 \pm G(s)H(s)}$$

$R(s)$ = Reference input

$C(s)$ = Controlled output

$E(s)$ = Actuating error signal

$G(s)$ = Forward path transfer function

$H(s)$ = Feedback path transfer function

$$C(s) = G(s)E(s)$$

$$= G(s)[R(s) \pm C(s)H(s)] = G(s)[R(s) \pm G(s)C(s)H(s)$$

$$C(s) \pm G(s)H(s)C(s) = G(s)R(s)$$

$$\frac{C(s)}{R(s)} = \frac{G(s)}{1 \pm G(s)H(s)}$$

Shortcut Method

1. To find close loop transfer function from open loop transfer function

   If $\text{O.L.T.F.} = \dfrac{\text{Numerator}}{\text{Denominator}}$

   Then, $\text{C.L.T.F.} = \dfrac{\text{Numerator}}{\text{Denominator} + \text{Numerator}}$

2. To find open loop transfer function from close loop transfer function

   If $\text{C.L.T.F.} = \dfrac{\text{Numerator}}{\text{Denominator}}$

   Then, $\text{O.L.T.F.} = \dfrac{\text{Numerator}}{\text{Denominator} - \text{Numerator}}$

Linear Systems

A system is called linear if the principle of superposition and principle of homogeneity apply. The principle of superposition states that the response produced by the simultaneous application of two different forcing functions is the sum of the two individual responses. Hence, for the linear system, the response to several inputs can be calculated by transferring one input at a time and adding the results. It is the principle that allows one to build up complicated solutions to the linear differential equations from simple solutions.

In an experimental investigation of a dynamic system, if cause and effect are proportional, thus implying that the principle of superposition holds, then the system can be considered as linear.

Linear Time-Invariant Systems and Linear-Time Varying Systems

A differential equation is linear if the coefficients are constants or functions only of the independent variable. Dynamic systems that are composed of linear time-invariant lumped-parameter components may be described by linear time-invariant differential equations i.e. constant-coefficient differential equations. Such systems are called linear time-invariant (or linear constant-coefficient) systems. Systems that are represented by differential equations whose coefficients are function of time are called linear time varying systems. An example of a time-varying control system is a space craft control system (the mass of a space craft changes due to fuel consumption).

The definition of transfer function is easily extended to a system with multiple inputs and outputs (i.e. a multivariable system). In a multivariable system, a linear differential equation may be used to describe the relationship between a pair of input and output variables, when all other inputs are set to zero. Since the principle of superposition is valid for linear systems, the total effect (on any output) due to all the inputs acting simultaneously is obtained by adding up the outputs due to each input acting alone.

EXAMPLE : 2.1

When deriving the transfer function of a linear element

(a) both initial conditions and loading are taken into account.

(b) initial conditions are taken into account but the element is assumed to be not loaded.

(c) initial conditions are assumed to be zero but loading is taken into account.

(d) initial conditions are assumed to be zero and the element is assumed to be not loaded.

Solution : (c)

While deriving the transfer function of a linear element only initial conditions are assumed to be zero, loading (or input) can't assume to be zero.

EXAMPLE : 2.2

If the initial conditions for a system are inherently zero, what does it physically mean?

(a) The system is at rest but stores energy

(b) The system is working but does not store energy

(c) The system is at rest or no energy is stored in any of its part

(d) The system is working with zero reference input

Solution : (c)

A system with zero initial conditions is said to be at rest since there is no stored energy.

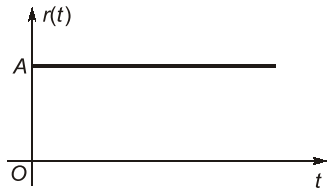
2.2 STANDARD TEST SIGNALS

1. Step Signal

$$r(t) = A\,u(t)$$

where, unit step signal $u(t) = \begin{cases} 1, & t \geq 0 \\ 0, & t < 0 \end{cases}$

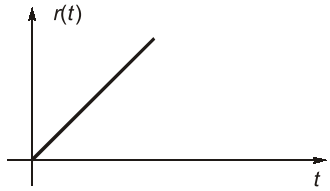
Laplace transform, $R(s) = A/s$



2. Ramp Signal

$$r(t) = \begin{cases} A\,t & t \geq 0 \\ 0 & t < 0 \end{cases}$$

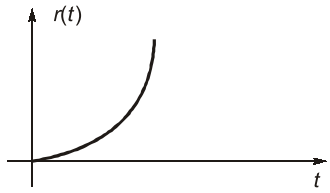
Laplace transform, $R(s) = A/s^2$



3. Parabolic Signal

$$r(t) = \begin{cases} A\,t^2/2 & , t \geq 0 \\ 0 & , t < 0 \end{cases}$$

Laplace transform, $R(s) = A/s^3$



4. Impulse Signal

$$r(t) = \begin{cases} \infty & , t = 0 \\ 0 & , t \neq 0 \end{cases} \quad ; \quad \int_{-\infty}^{+\infty} \delta(t)\,dt = 1$$

Laplace transform, $R(s) = 1$

Transfer function, $G(s) = \dfrac{C(s)}{R(s)}$

$$C(s) = F(s)\,R(s)$$

Let, $R(s) =$ Impulse signal $= 1$

$C(s) =$ Impulse response $= G(s) \times 1 =$ Transfer Function

$$\mathcal{L}\{\text{Impulse Response}\} = \text{Transfer function} = \left[\frac{C(s)}{R(s)}\right]$$

NOTE

- Td/dt (Parabolic Response) = Ramp Response
- d/dt (Ramp Response) = Step Response
- d/dt (Step Response) = Impulse Response

Consider, a linear time-invariant system has the input $u(t)$ and output $y(t)$. The system can be characterized by its impulse response $g(t)$, which is defined as the output when the input is a unit-impulse function $\delta(t)$. Once the impulse response of a linear system is known, the output of the system $y(t)$, with any input $u(t)$, can be found by using the transfer function.

Let $G(s)$ denotes the transfer function of a system with input $u(t)$, output $y(t)$, and impulse response $g(t)$. The transfer function $G(s)$ is defined as

$$G(s) = \mathcal{L}[g(t)] = \left.\frac{\mathcal{L}[y(t)]}{\mathcal{L}[u(t)]}\right|_{\text{initial conditions}\to 0} = \frac{Y(s)}{U(s)}$$

REMEMBER

Sometimes, students do a common mistake, they first find $y(t)/u(t)$ and then take its Laplace transform to determine the transfer function which is absolutely wrong. Because,

$$G(s) = \frac{Y(s)}{U(s)} = \frac{\mathcal{L}[y(t)]}{\mathcal{L}[u(t)]} \neq \mathcal{L}\left[\frac{y(t)}{u(t)}\right]$$

2.3 POLES AND ZEROS OF A TRANSFER FUNCTION

The transfer function of a linear control system can be expressed as

$$G(s) = \frac{A(s)}{B(s)} = \frac{K(s-s_1)(s-s_2)\ldots(s-s_n)}{(s-s_a)(s-s_b)\ldots(s-s_m)}$$

where K is known as gain factor of the transfer function $G(s)$.

In the transfer function expression, if s is put equal to s_a, s_b ... s_m then it is noted that the value of the transfer function is infinite. These s_a, s_b, ... s_m are called the poles of the transfer function.

In the transfer function expression, if s is put equal to s_1, s_2 ... s_n then it is noted that the value of the transfer function is zero. These s_1, s_2 ... s_n are called the zeros of the transfer function.

2.3.1 Multiple Poles and Multiple Zeros

The poles s_a, s_b ... s_m or the zeros s_1, s_2 ... s_n are either real or complex and the complex poles or zeros always appear in conjugate pairs.

It is possible that either poles or zeros may coincide; such poles or zeros are called multiple poles or multiple zeros.

2.3.2 Simple Poles and Simple Zeros

Non-coinciding poles or zeros are called simple poles or simple zeros. From the transfer function expression, it is observed that

- If $n > m$, then the value of transfer function is found to be infinity for $s = \infty$. Hence, it is concluded that there exists a pole of the transfer function at infinity (∞) and the multiplicity (order) of such a pole being $(n - m)$.

- If $n < m$, then the value of transfer function is found to be zero for $s = \infty$. Hence, it is concluded that there exists a zero of the transfer function at infinity (∞) and the multiplicity (order) of such a zero being $(m - n)$.

  Therefore, for a rational transfer function the total number of zeros is equal to the total number of poles. The transfer function of a system is completely specified in terms of its poles, zeros and the gain factor.

Consider the following transfer function:

$$G(s) = \frac{s+3}{(s+2)(s+1+3j)(s+1-3j)}$$

For the above transfer function, the poles are at :

(a) $s_a = -2$; (b) $s_b = -1 - 3j$; and (c) $s_c = -1 + 3j$

The zeros are at $s_1 = -3$.

As the number of zeros should be equal to number of poles, the remaining two zeros are located at $s = \infty$. The pole-zero plot is plotted as shown:

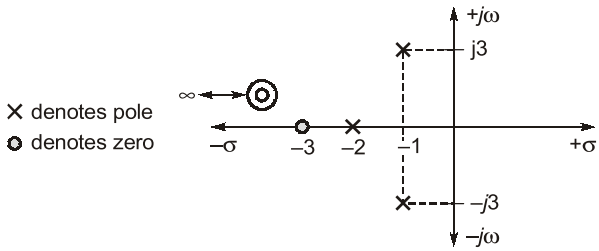


Fig. : *Pole-zero plot*

Note : Poles and zero are those complex/critical frequencies which make the transfer function infinity or zero.

2.3.3 Proper Transfer Functions

The transfer functions are said to be strictly proper if the order of the denominator polynomial is greater than that of the numerator polynomial (i.e. $m > n$). If $m = n$, the transfer function is called proper. The transfer function is improper if $n > m$.

In the transfer function expression of a control system, the highest power of s in the numerator is generally either equal to or less than that of the denominator.

EXAMPLE : 2.3

A transfer function has two zeros at infinity. Then the relation between the numerator degree (N) and the denominator degree (M) of the transfer function is

(a) $N = M + 2$ (b) $N = M - 2$

(c) $N = M + 1$ (d) $N = M - 1$

Solution : (b)

For a rational transfer function, the total number of zeros are equal to total number of poles.

Therefore, Number of poles $= M$; Number of zeros $= N + 2$

For a rational transfer function : $M = N + 2$ or $N = M - 2$

2.4 PROPERTIES OF TRANSFER FUNCTION

The properties of the transfer function are summarized as follows:

1. The transfer function is defined only for a linear time-invariant system. It is not defined for non-linear or time variant systems.
2. The transfer function between an input variable and an output variable of a system is defined as the Laplace transform of the impulse response. Alternately, the transfer function between a pair of input and output variables is the ratio of the Laplace transform of the output to the Laplace transform of the input.
3. All initial conditions of the system are set to zero.
4. Transfer function is independent of the input of the system.
5. The transfer function of a continuous-data system is expressed only as a function of the complex variables. It is not a function of the real variable, time, or any other variable that is used as the independent variable or discrete-data system modelled by difference equations, the transfer function is a function of Z, when the Z-transform is used.
6. If the system transfer function has no poles or zeros with positive real parts, the system is a **minimum phase system.**

   Non-minimum phase functions are the functions which have poles or zeros on right hand side of s-plane.
7. The stability of a time-invariant linear system can be determined from its characteristic equation.

   Characteristic equation: The characteristic equation of a linear system is defined as the equation obtained by setting the denominator polynomial of the closed loop transfer function to zero.

EXAMPLE : 2.4

State and explain minimum phase and non-minimum phase transfer functions with examples.

Solution :

Minimum phase transfer function:

⇒ Transfer functions which have all poles and zeros in the left half of the s-plane, i.e., system having no poles and zeros in the RHS of the s-plane are minimum phase transfer functions.

⇒ On the other hand, a transfer function which has one or more zeros in the right half of s-plane is known as "**non-minimum phase transfer function**".

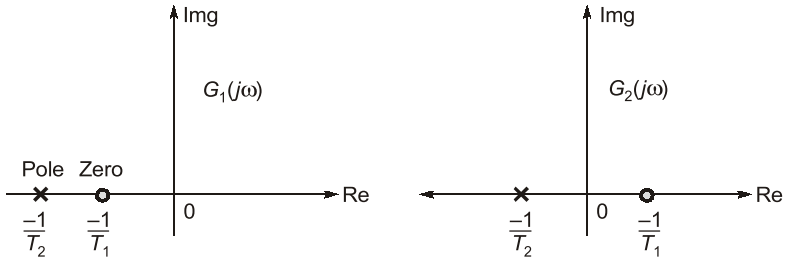
Let $$G_1(s) = \frac{1+sT_1}{1+sT_2}$$

⇒ $$G_1(j\omega) = \frac{1+j\omega T_1}{1+j\omega T_2} \quad \text{...(i)}$$

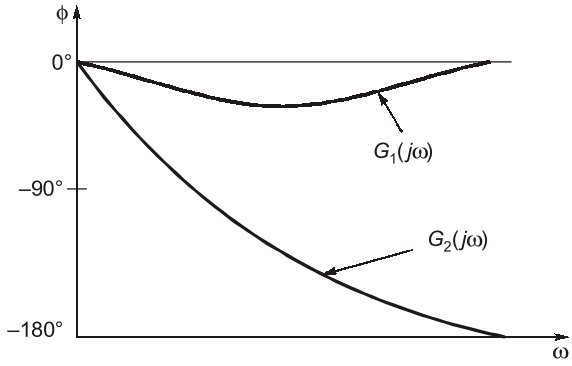
and $$G_2(j\omega) = \frac{1-j\omega T_1}{1+j\omega T_2} \quad \text{...(ii)}$$

The transfer function given by equation (i) represents the minimum-phase transfer function and equation (ii) represents the non-minimum phase transfer function.

⇒ The pole-zero configuration of above transfer function as given by equation (i) and (ii) may be drawn as:



⇒ The ***minimum phase function*** has unique relationship between its phase and magnitude curves. Typical phase angle characteristics are shown below:



⇒ It will be seen that larger the phase lags present in a system, the more complex are its stabilization problems. Therefore, in control systems, elements with non minimum phase transfer function are avoided as far as possible.

⇒ A common example of a non-minimum phase system is "***transportation lag***" which has the transfer function,

$$G(j\omega) = e^{-j\omega T} = 1\angle -\omega T \text{ Radian}$$
$$= 1\angle -57.3\,\omega T \text{ degree}$$

2.5 METHODS OF ANALYSIS

Methods of analysis of a system involves:

(a) Transfer function approach

(b) State variable approach

Many a times in interviews the relative comparison of these two approaches has been asked, which we will understand during the study of state variable analysis.

2.5.1 Advantages of Transfer Function Approach

1. It gives simple mathematical algebraic equation.
2. It gives poles and zeros of the system directly.
3. Stability of the system can be determined easily.
4. The output of the system for any input can be determined easily.

Using equation (i) when input is $u(t)$, output is

$$\frac{H(s+c)}{s(s+a)(s+b)} = \frac{K_1}{s} + \frac{D}{s+a} + \frac{E}{s+b}$$

Taking inverse Laplace transform,

$$\text{Output} = 2 + De^{-t} + Ee^{-3t}$$

So, $a = 1$ and $b = 3$

Using final value theorem

$$\Rightarrow \lim_{s\to 0} \frac{s\cdot H(s+c)}{s(s+a)(s+b)} = \lim_{t\to\infty} 2 + De^{-t} + Ee^{-3t}$$

$$\frac{Hc}{ab} = 2 \quad \text{and} \quad Hc = 6$$

Using equation (i) when input is $e^{-2t}u(t)$, output is $\dfrac{H(s+c)}{(s+2)(s+a)(s+b)}$

Only two terms are present in the response.

Hence $s + c = s + 2$

$\Rightarrow$ $c = 2$

$H = 3$ $(\because HC = 6)$

OBJECTIVE BRAIN TEASERS

Q.1 A control system with certain excitation is governed by the following mathematical equation $\dfrac{d^2x}{dt^2} + \dfrac{1}{2}\dfrac{dx}{dt} + \dfrac{1}{18}x = 10 + 15e^{-4t} + 2e^{-5t}$. The natural time constants of the response of the system are

(a) $2s$ and $5s$ (b) $3s$ and $6s$

(c) $4s$ and $5s$ (d) $\dfrac{1}{3}s$ and $\dfrac{1}{6}s$

Q.2 The response $g(t)$ of a linear time invariant system to an impulse $\delta(t)$, under initially relaxed condition is $g(t) = e^{-t} + e^{-2t}$. The response of this system for a unit step input $u(t)$ is

(a) $(1 + e^{-t} + e^{-2t})u(t)$

(b) $(e^{-t} + e^{-2t})u(t)$

(c) $(1.5 - e^{-t} - 0.5e^{-2t})u(t)$

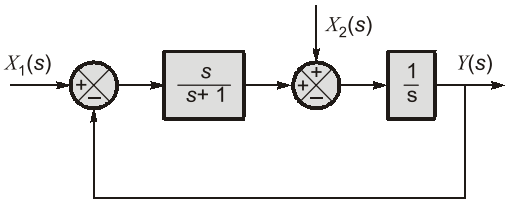
(d) $e^{-t}\delta(t) + e^{-2t}u(t)$

Q.3 The frequency response of a linear time-invariant system is given by $H(f) = \dfrac{5}{1 + j10\pi f}$. The step response of the system is

(a) $5(1 - e^{-5t})u(t)$ (b) $5\left(1 - e^{-t/5}\right)u(t)$

(c) $\dfrac{1}{5}\left(1 - e^{-5t}\right)u(t)$ (d) $\dfrac{1}{(s+5)(s+1)}$

Q.4 For the following system :



when $X_1(s) = 0$, the transfer function $\dfrac{Y(s)}{X_2(s)}$ is

(a) $\dfrac{s+1}{s^2}$ (b) $\dfrac{1}{s+1}$

(c) $\dfrac{s+2}{s(s+1)}$ (d) $\dfrac{s+1}{s(s+2)}$

Q.5 Ramp response of the transfer function $F(s) = \frac{s+1}{s+2}$ is

(a) $\frac{1}{4} - \frac{1}{4}e^{-2t} + \frac{1}{2}t$ (b) $\frac{1}{4}e^{-2t} + \frac{1}{4} + \frac{1}{2}t$

(c) $\frac{1}{2} - \frac{1}{2}e^{-2t} + t$ (d) $\frac{1}{2}e^{-2t} + \frac{1}{2} - t$

Q.6 Which of the following statements are correct?

1. Transfer function can be obtained from the signal flow graph of the system.
2. Transfer function typically characterizes to linear time invariant systems.
3. Transfer function gives the ratio of output to input in frequency domain of the system.

(a) 1 and 2 (b) 2 and 3

(c) 1 and 3 (d) 1, 2 and 3

Q.7 Which of the following is not a desirable feature of a modern control system?

(a) Quick response

(b) Accuracy

(c) Correct power level

(d) Oscillations

Q.8 In regenerating feedback, the transfer function is given by

(a) $\frac{C(s)}{R(s)} = \frac{G(s)}{1+G(s)H(s)}$

(b) $\frac{C(s)}{R(s)} = \frac{G(s)H(s)}{1-G(s)H(s)}$

(c) $\frac{C(s)}{R(s)} = \frac{G(s)H(s)}{1+G(s)H(s)}$

(d) $\frac{C(s)}{R(s)} = \frac{G(s)}{1-G(s)H(s)}$

Q.9 The principle of homogeneity and superposition are applied to

(a) linear time variant systems

(b) non-linear time variant systems

(c) linear time invariant systems

(d) non-linear time invariant systems

Q.10 If a system is represented by the differential equation, is of the form $\frac{d^2y}{dt^2} + 6\frac{dy}{dt} + 9y = r(t)$

(a) $k_1e^{-t} + k_2e^{-9t}$ (b) $(k_1 + k_2)e^{-3t}$

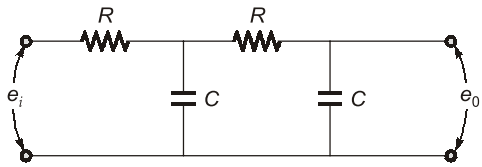
(c) $ke^{-3t}\sin(t+\phi)$ (d) $te^{-3t}u(t)$

Q.11 A linear system initially at rest, is subject to an input signal $r(t) = 1 - e^{-t}$ $(t \geq 0)$. The response of the system for $t > 0$ is given by $c(t) = 1 - e^{-2t}$. The transfer function of the system is

(a) $\frac{(s+2)}{(s+1)}$ (b) $\frac{(s+1)}{(s+2)}$

(c) $\frac{2(s+1)}{(s+2)}$ (d) $\frac{(s+1)}{2(s+2)}$

Q.12 Consider the RC circuit shown in figure below:

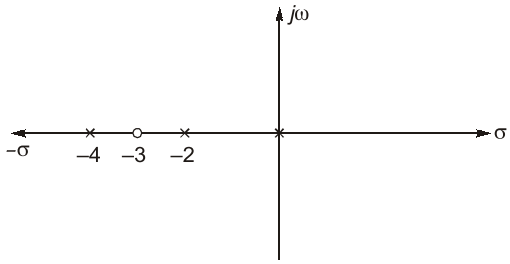


The transfer function $\frac{E_0(s)}{E_i(s)}$ will be ($\tau = RC$)

(a) $\frac{1}{\tau^2s^2 + 2\tau s + 1}$ (b) $\frac{1}{\tau^2s^2 + 3\tau s + 1}$

(c) $\frac{\tau_s}{\tau^2s^2 + 2\tau s + 1}$ (d) $\frac{\tau_s}{\tau^2s^2 + 3\tau s + 1}$

Q.13 The pole-zero configuration of a transfer function is shown in figure. The value of transfer function at $s = 1$ is found to be 4. Then the transfer function of system is



(a) $\frac{12(s+3)}{s(s+2)(s+4)}$ (b) $\frac{15(s+3)}{s(s+2)(s+4)}$

(c) $\frac{4(s+3)}{s(s+2)(s+4)}$ (d) $\frac{10(s+2)}{s(s+3)(s+4)}$

Q.14 The transfer function of a system is given by $\frac{C(s)}{R(s)} = \frac{100}{(s+10)(s^2+2s+1)}$, using the concept of dominant pole, the 2nd order approximation of above transfer function is

(a) $\frac{100}{s^2+2s+1}$ (b) $\frac{10}{s^2+2s+1}$

(c) $\frac{10}{s+10}$ (d) $\frac{100}{(s+10)}$

Q.15 A differentiator has a transfer function whose

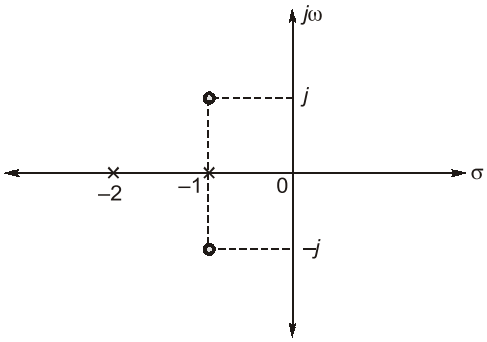
(a) Magnitude decreases linearly with frequency

(b) Magnitude increases linearly with frequency

(c) Phase increases linearly with frequency

(d) Phase is constant

Q.16 The pole-zero plot of a system is given below. If $G(s) = 15$ for $s = 2$, then the transfer function of the system is



(a) $\frac{12(s^2+2s+5)}{(s+1)(s+2)}$ (b) $\frac{18(s^2+2s+2)}{(s+1)(s+2)}$

(c) $\frac{12(s^2+2s+3)}{(s+1)(s+2)}$ (d) $\frac{6(s^2+2s+3)}{(s+1)(s+2)}$

Q.17 A linear time invariant system initially at rest, when subjected to unit step input gives a response of $2te^{-5t}$, $t > 0$, the corresponding transfer function is

(a) $\frac{2}{s(s+5)^2}$ (b) $\frac{2s}{(s+5)}$

(c) $\frac{2s}{(s+5)^2}$ (d) $\frac{2s}{(s-5)^2}$

ANSWER KEY

1. (b)	**2.** (c)	**3.** (b)	**4.** (d)	**5.** (a)
6. (d)	**7.** (d)	**8.** (d)	**9.** (c)	**10.** (d)
11. (c)	**12.** (b)	**13.** (b)	**14.** (b)	**15.** (b, d)
16. (b)	**17.** (c)			

HINTS & EXPLANATIONS

1. (b)

Natural time constants of the response depend only on poles of the system.

$$T(s) = \frac{C(s)}{R(s)}$$

$$= \frac{1}{s^2 + s/2 + 1/18}$$

$$= \frac{18}{18s^2 + 9s + 1}$$

$$= \frac{1}{(6s+1)(3s+1)}$$

This is in the form $\frac{1}{(1+sT_1)(1+sT_2)}$

$\therefore$ $T_1, T_2 = 6$ sec, 3 sec.

2. (c)

Transfer function of system is impulse response of the system with zero initial conditions.

Transfer function = $G(s) = \mathcal{L}\left(e^{-t} + e^{-2t}\right)$

$$= \frac{1}{s+1} + \frac{1}{s+2}$$

$$G(s) = \frac{C(s)}{R(s)} = \left(\frac{1}{s+1} + \frac{1}{s+2}\right)$$

For step input, $R(s) = \frac{1}{s}$

$$C(s) = R(s) \cdot G(s) = \frac{1}{s}\left(\frac{1}{s+1} + \frac{1}{s+2}\right)$$

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

$$H(s) = \frac{Y(s)}{X(s)} = s$$

Put $s = j\omega$,

$$H(j\omega) = j\omega$$

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

$$\angle H(j\omega) = 90° \text{ (always)}$$

So, it is constant with w.r.t. frequency.

16. (b)

Poles : –1, –2

Zeros : $-1 + j, -1 - j$

∴ Transfer function is given by,

$$G(s) = \frac{K((s+1)^2 + 1)}{(s+1)(s+2)},$$

where gain is assumed to be K

$$G(s) = \frac{K(s^2 + 2s + 2)}{(s+1)(s+2)}$$

at $s = 2$, $G(s) = 15$

$$G(s) = 15 = \frac{K(2^2 + 2(2) + 2)}{(2+1)(2+2)}$$

$$\therefore \quad K = \frac{15 \times 3 \times 4}{10} = 18$$

Therefore, transfer function of the system is given as,

$$G(s) = \frac{18(s^2 + 2s + 2)}{(s+1)(s+2)}$$

17. (c)

Given : $y(t) = 2te^{-5t}$

$x(t) = u(t)$

Taking Laplace transform, we get,

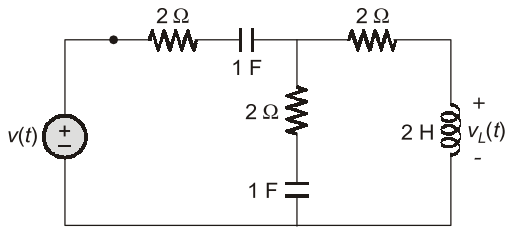
$$Y(s) = \frac{2}{(s+5)^2} \quad \text{and} \quad X(s) = \frac{1}{s}$$

∴ Overall transfer function,

$$\frac{Y(s)}{X(s)} = \frac{2s}{(s+5)^2}$$

CONVENTIONAL BRAIN TEASERS

Q.1 Determine the transfer function, $G(s) = \frac{V_L(s)}{V(s)}$ for the network shown below using mesh analysis.



1. (Sol.)

For the given network assuming loop current as shown in figure.

Writing mesh equation using KVL,

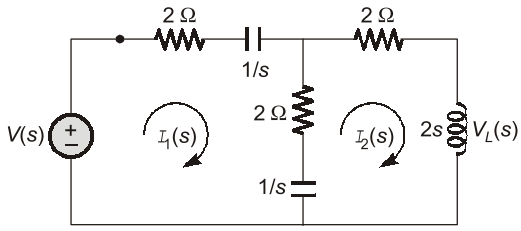
$$-V(s) + 2I_1(s) + \frac{I_1(s)}{s} + (I_1(s) - I_2(s))\left(2 + \frac{1}{s}\right) = 0$$

$$V(s) = \left(4 + \frac{2}{s}\right) I_1(s) - \left(2 + \frac{1}{s}\right) I_2(s) \qquad \ldots(1)$$

Similarly, $(2+2s)I_2(s)+\left(2+\frac{1}{s}\right)(I_2(s)-I_1(s)) = 0$

$$\left(4+2s+\frac{1}{s}\right)I_2(s)-\left(2+\frac{1}{s}\right)I_1(s) = 0$$

$$-\left(2+\frac{1}{s}\right)I_1(s)+\left(4+2s+\frac{1}{s}\right)I_2(s) = 0 \qquad ...(2)$$



Eliminating $I_1(s)$ using equation (2),

$$I_1(s) = \frac{\left(4+2s+\frac{1}{s}\right)I_2(s)}{\left(2+\frac{1}{s}\right)} = \left(\frac{4s+2s^2+1}{2s+1}\right)\cdot I_2(s)$$

Substituting equation (1),

$$V(s) = \left(4+\frac{2}{s}\right)\left(\frac{4s+2s^2+1}{2s+1}\right)I_2(s)-\left(2+\frac{1}{s}\right)I_2(s)$$

$$V(s) = \frac{4s+2}{s}\left(\frac{4s+2s^2+1}{2s+1}\right)I_2(s)-\left(\frac{2s+1}{s}\right)I_2(s)$$

$$V(s) = \frac{2}{s}(4s+2s^2+1)I_2(s)-\frac{(2s+1)}{s}I_2(s)$$

$$V(s) = \frac{(8s+4s^2+2-2s-1)}{s}I_2(s) = \frac{4s^2+6s+1}{s}I_2(s)$$

$$\frac{I_2(s)}{V(s)} = \frac{s}{4s^2+6s+1}$$

$$2s\frac{I_2(s)}{V(s)} = \frac{2s^2}{4s^2+6s+1} = \frac{V_L(s)}{V(s)}$$

■■■■