Course guides

230475 - TCTRL - Control Theory

Unit in charge: Barcelona School of Telecommunications Engineering
Teaching unit: 710 - EEL - Department of Electronic Engineering.

Degree: BACHELOR'S DEGREE IN ENGINEERING PHYSICS (Syllabus 2011). (Compulsory subject).

Academic year: 2020  ECTS Credits: 6.0  Languages: Catalan, Spanish

LECTURER

Coordinating lecturer: Doria Cerezo, Arnau

Others: Olm Miras, Josep Maria
        Biel Sole, Domingo

DEGREE COMPETENCES TO WHICH THE SUBJECT CONTRIBUTES

Specific:
1. Knowledge of control theory. Knowledge of feedback procedures. Ability to design a process control system.

General:
1. ABILITY TO IDENTIFY, FORMULATE, AND SOLVE PHYSICAL ENGINEERING PROBLEMS. Planning and solving physical engineering problems with initiative, making decisions and with creativity. Developing methods of analysis and problem solving in a systematic and creative way.

7. They will have acquired knowledge related to experiments and laboratory instruments and will be competent in a laboratory environment in the ICC field. They will know how to use the instruments and tools of telecommunications and electronic engineering and how to interpret manuals and specifications. They will be able to evaluate the errors and limitations associated with simulation measures and results.

Transversal:
2. THIRD LANGUAGE. Learning a third language, preferably English, to a degree of oral and written fluency that fits in with the future needs of the graduates of each course.
3. EFFICIENT ORAL AND WRITTEN COMMUNICATION - Level 3. Communicating clearly and efficiently in oral and written presentations. Adapting to audiences and communication aims by using suitable strategies and means.
4. TEAMWORK - Level 3. Managing and making work groups effective. Resolving possible conflicts, valuing working with others, assessing the effectiveness of a team and presenting the final results.
5. EFFECTIVE USE OF INFORMATION RESOURCES - Level 3. Planning and using the information necessary for an academic assignment (a final thesis, for example) based on a critical appraisal of the information resources used.
6. SELF-DIRECTED LEARNING - Level 3. Applying the knowledge gained in completing a task according to its relevance and importance. Deciding how to carry out a task, the amount of time to be devoted to it and the most suitable information sources.

TEACHING METHODOLOGY

There will be three theoretical and two practical weekly sessions. The theoretical lectures will be devoted to a careful presentation of the basic concepts and the main results which will be illustrated with some examples. The practical sessions will be devoted to the solution of a variety of exercises and problems.

LEARNING OBJECTIVES OF THE SUBJECT

* To understand the basic concepts related to feedback systems in both continuous-time and discrete-time
* To apply the root locus technique and the Routh and Jury stability criteria in the analysis of feedback control systems
* To design the proper controllers to verify specifications in both time domain and frequency domain
STUDY LOAD

<table>
<thead>
<tr>
<th>Type</th>
<th>Hours</th>
<th>Percentage</th>
</tr>
</thead>
<tbody>
<tr>
<td>Self study</td>
<td>85.0</td>
<td>56.67</td>
</tr>
<tr>
<td>Hours large group</td>
<td>65.0</td>
<td>43.33</td>
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</tbody>
</table>

Total learning time: 150 h

CONTENTS

1. Introduction

**Description:**
1.1. What is a control system? Basic components of a control system, reference, control, output and disturbance signals.
1.2. Control system goals.
1.3. Continuous-time control and discrete-time control. Examples.

**Full-or-part-time:** 5h
Theory classes: 2h
Self study: 3h

2. System modelling

**Description:**
2.1. Dynamic systems classification: linear and nonlinear systems, time-varying and time-invariant systems.
2.2. State space models.
2.3. SISO and MIMO Systems.
2.4. Nonlinear system linearization. Examples.

**Full-or-part-time:** 11h
Theory classes: 2h
Practical classes: 2h
Self study: 7h

3. Dynamic behaviour

**Description:**
3.1. Autonomous and non-autonomous systems.
3.2. Equilibrium points, invariant sets and limit cycles.

**Full-or-part-time:** 24h
Theory classes: 5h
Practical classes: 4h
Self study: 15h
4. Linear systems

Description:
4.1. Linear system state space representation.
4.3. Transfer function for SISO systems.
4.4. Transient response characterization: settling time, maximum overshoot, etc.

Full-or-part-time: 10h
Theory classes: 3h
Practical classes: 1h
Self study: 6h

5. State feedback

Description:
5.1. Reachability.
5.3. Integral action.

Full-or-part-time: 33h
Theory classes: 8h
Practical classes: 5h
Guided activities: 3h
Self study: 17h

6. Output feedback

Description:
6.1. Observability.
6.2. State observer design.
6.4. First and second-order controllers. PID controllers.
6.5. Implementation issues of PID controllers.

Full-or-part-time: 42h
Theory classes: 12h
Practical classes: 8h
Self study: 22h
7. Frequency-domain control design

Description:
7.2. Nyquist stability criterion.
7.3. Application of the Nyquist criterion to systems with non-linearities: the describing function.
7.4. Relative stability: gain margin and phase margin.
7.5. Frequency-domain specifications: relative stability margins and bandwidth of a control system. Frequency-domain control design. Lead-lag and phase-lag compensations.

Full-or-part-time: 25h
Theory classes: 7h
Practical classes: 4h
Self study: 14h

GRADING SYSTEM

There will be a final exam (EF) and a partial exam (EP).

The final score will be computed as max{EF, 0.65*EF+0.35*EP}

BIBLIOGRAPHY

Basic:

Complementary: