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First find the mechanical constants.

$$J_m = J_a + J_L \left( \frac{1}{5} * \frac{1}{4} \right)^2 = 1 + 400 \left( \frac{1}{400} \right) = 2$$

$$D_m = D_a + D_L \left( \frac{1}{5} * \frac{1}{4} \right)^2 = 5 + 800 \left( \frac{1}{400} \right) = 7.6$$

Solutions to Skill-Assessment Exercises. Now find the electrical constants. From the torque-speed equation, set  $\omega_m = 0$  to find stall torque and set  $T_m = 0$  to find no-load speed.

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further illustrates the steady state and transient analysis of control systems. The book covers the fundamental knowledge of controllers used in practice to optimize the performance of the systems. The book emphasizes the detailed analysis of second order systems as these systems are common in practice and higher order systems can be approximated as second order systems. The book teaches the concept of stability and time domain stability analysis using Routh-Hurwitz method and root locus method. It further explains the fundamentals of frequency domain analysis of the systems

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including co-relation between time domain and frequency domain. The book gives very simple techniques for stability analysis of the systems in the frequency domain, using Bode plot, Polar plot and Nyquist plot methods. It also explores the concepts of compensation and design of the control systems in time domain and frequency domain. The classical approach loses the importance of initial conditions in the systems. Thus, the book provides the detailed explanation of modern approach of analysis which is the state variable analysis of the systems including methods of finding the state transition

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matrix, solution of state equation and the concepts of controllability and observability. The variety of solved examples is the feature of this book which helps to inculcate the knowledge of the design and analysis of the control systems in the students. The book explains the philosophy of the subject which makes the understanding of the concepts very clear and makes the subject more interesting.

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be equally useful for all engineering disciplines, this text is organized around the concept of control systems theory as it has been developed in the frequency and time domains. It provides coverage of classical control, employing root locus design, frequency and response design using Bode and Nyquist plots. It also covers modern control methods based on state variable models including pole placement design techniques with full-state feedback controllers and full-state observers. Many examples throughout give students ample opportunity to apply the theory to the design and analysis of control

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