

# 自动控制原理试题解答

$$(1) \Phi(s) = \frac{E(s)}{R(s)} = \frac{1 + \frac{K_0 K_1 s}{s(s+1)} - \frac{K_0 G_c(s)}{s(s+1)}}{1 + \frac{K_0 K_1}{s+1} + \frac{K_0(s+2)}{s^2(s+1)}} = \frac{s[s(s+1) + K_0 K_1 s - K_0 G_c(s)]}{s^2(s+1) + K_0 K_1 s^2 + K_0(s+2)}$$

$$D(s) = s^3 + (1 + K_0 K_1)s^2 + K_0 s + 2K_0 = 0$$

劳斯阵列

$s^3$	1	$K_0$	
$s^2$	$1 + K_0 K_1$	$2K_0$	
$s^1$	$\frac{K_0[1 + K_0 K_1 - 2]}{1 + K_0 K_1}$		$\rightarrow K_0 K_1 > -1, K_1 > \frac{1}{K_0}$
$s^0$	$2K_0$		$K_0 > 0$

$$(2) e_{ss} = \lim_{s \rightarrow 0} s \Phi(s) = \lim_{s \rightarrow 0} \frac{s^2[s(s+1) + K_0 K_1 s - K_0 G_c(s)]}{s^2(s+1) + K_0 K_1 s^2 + K_0(s+2)} = \frac{1 + K_0 K_1 - \frac{K_0 G_c(s)}{s}}{2K_0} = 0$$

$$G_c(s) = \frac{(1 + K_0 K_1)s}{K_0}$$

故

如图 D.1.1 所示。

二、(1) 绘制根轨迹, 如图 D.1.2 所示。

$$G(s) = \frac{5K_0(s-1)}{(s^2+4s+4)(s+5)} \quad \begin{cases} K = \frac{K_0}{4} \\ \gamma = 0 \end{cases}$$

① 渐近线  $\begin{cases} \sigma_a = \frac{-2-2-5-1}{3-1} = -5 \\ \varphi_a = \frac{(2K+1)\pi}{3-1} = \pm 90^\circ \end{cases}$

② 分离点  $\frac{2}{d+2} + \frac{1}{d+5} = \frac{1}{d-1}$

整理有  $d^2 + d - 11 = 0$

解得  $\begin{cases} d_1 = -3.854 \\ d_2 = +2.854 \end{cases}$

③ 与虚轴交点

$$D(s) = (s^2+4s+4)(s+5) + 5K_0(s-1) = s^3 + 9s^2 + (24+5K_0)s + (20-5K_0) = 0$$

$$\begin{cases} \text{Im}[D(j\omega)] = -\omega^3 + (24+5K_0)\omega = 0 \\ \text{Re}[D(j\omega)] = -9\omega^2 + (20-5K_0) = 0 \end{cases}$$

$$\begin{cases} \omega = 0 \\ K_0 = \frac{20}{5} = 4 \end{cases}$$

$$0 < K_0 < 4, \quad 0 < K = \frac{K_0}{4} < 1$$

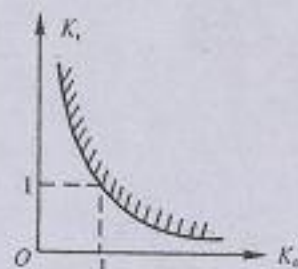


图 D.1.1

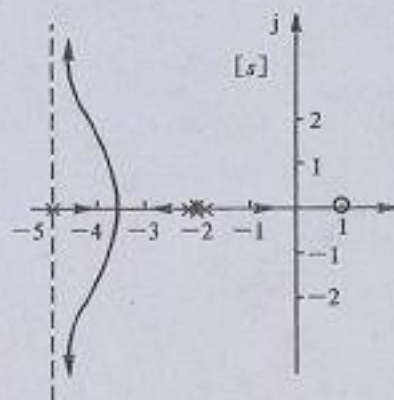


图 D.1.2

$$\frac{D(s)}{s+1} = s^2 + 8s + 18, \quad \Phi(s) = \frac{0.4(s-1)(s+5)}{(s+1)(s^2+8s+18)}$$

三、(1) 依题意有

$$G(s) = \frac{K(\frac{s}{0.2} + 1)}{s(s^2 + 2s + 1)(\frac{s}{20} + 1)}$$

$$K = 2, \quad 20 \lg M_r = 2.7 \text{ dB}$$

$$M_r = 10^{\frac{2.7}{20}} = 1.3646 = \frac{1}{2\xi\sqrt{1-\xi^2}}$$

$$\xi^2 - \xi + 0.1342 = 0, \quad \xi^2 = \frac{1 \pm \sqrt{1-4 \times 0.1342}}{2} = 0.16, \quad \xi = 0.4$$

故

$$G(s) = \frac{2(\frac{s}{0.2} + 1)}{s(s^2 + 0.8s + 1)(\frac{s}{20} + 1)}$$

(2) 依题意有

$$1 < \omega_c < 20$$

$$G(j\omega_c) = \frac{2 \times \frac{\omega_c}{0.2}}{\omega_c \times \omega_c^2 \times 1} = \frac{10}{\omega_c^2} = 1$$

$$\omega_c = \sqrt{10} = 3.16$$

$$\gamma = 180^\circ + \arctan \frac{3.16}{0.2} - 90^\circ - \arctan \frac{0.8 \times 3.16}{1 - 3.16^2} - \arctan \frac{3.66}{20} = 180^\circ + 86.38^\circ - 90^\circ - (180^\circ - 15.7^\circ) - 8.98^\circ = 3.1^\circ$$

$$四、G_0(s) = \frac{K}{s(\frac{s}{10} + 1)(\frac{s}{100} + 1)}$$

当  $K = K_c = 100$  时, 作  $L_0(\omega)$  如图 D.1.3 所示。

$$\omega_{cs} = \omega_{cp} = \sqrt{10 \times 100} = 31.6$$

系统临界稳定, 故  $K$  的稳定范围为

$$0 < K < 100$$

$$(2) G(s) = G_c(s)G_0(s) = \frac{100(\frac{s}{20} + 1)}{s(\frac{s}{10} + 1)(\frac{s}{100} + 1)(\frac{s}{200} + 1)}$$

此时

$$\omega_c^* = \frac{\omega_{cs}}{20} = \frac{31.6}{20} = 1.58$$

图 D.1.3

$$\gamma^* = 180^\circ + \arctan \frac{50}{20} - 90^\circ - \arctan \frac{50}{10} - \arctan \frac{50}{100} - \arctan \frac{50}{200} = 180^\circ - 68.2^\circ - 90^\circ - 76.7^\circ - 26.6^\circ - 14.38^\circ > 30^\circ$$

五、

$$G_0(z) = (1 - z^{-1})Kz^{-1} \mathcal{Z}\left[\frac{1/T_0}{s(s + \frac{1}{T_0})}\right] = \frac{z-1}{z^2} K \mathcal{Z}\left[\frac{1}{s} - \frac{1}{s + \frac{1}{T_0}}\right] =$$

$$\frac{z-1}{z^2} K \left[ \frac{z}{z-1} - \frac{z}{z - e^{-T/T_0}} \right] = \frac{K}{z} \left[ 1 - \frac{z-1}{z - e^{-T/T_0}} \right] =$$

$$\frac{K(1 - e^{-T/T_0})}{z(z - e^{-T/T_0})} = \frac{0.2}{z(z - 0.2)}$$

(1)

$$D_0(z) = z(z - 0.2) + 0.8K = z^2 - 0.2z + 0.8K = 0$$

$$D_0(1) = 1 - 0.2 + 0.8K > 0 \rightarrow K > -1$$

$$D_0(-1) = 1 + 0.2 + 0.8K > 0 \rightarrow K > -1.5$$

$$0.8K < 1 \rightarrow K < \frac{1}{0.8} = 1.25$$

考虑题中条件,  $K > 0$ , 有

$$0 < K < 1.25$$



