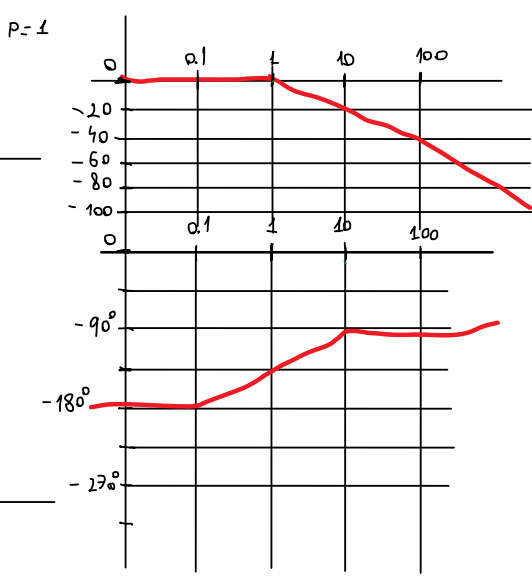
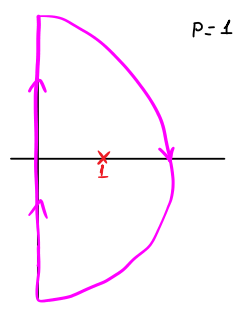
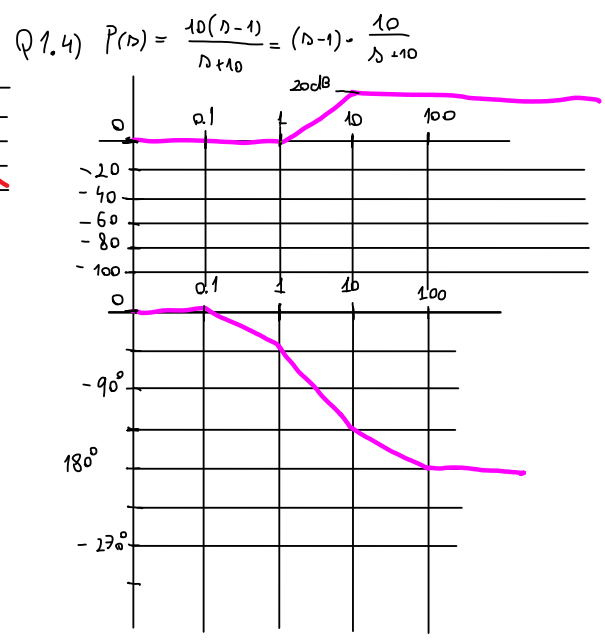
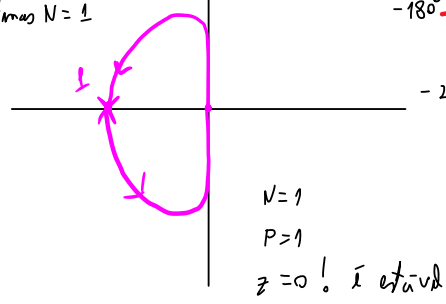


Q 1.1)
 $P(s) = \frac{1}{s-1}$

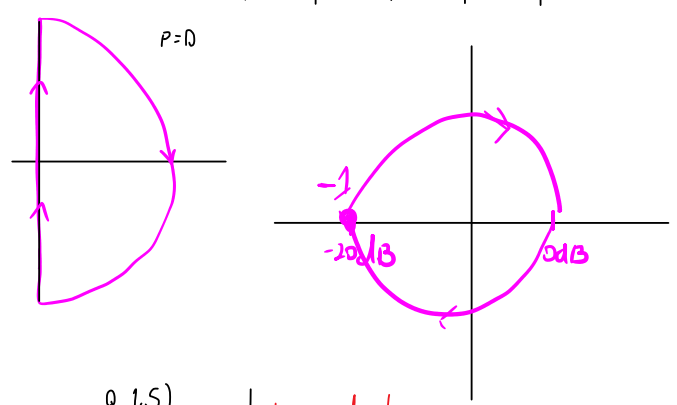


$k=1$
 Logo para $k>1$
 temos $N=1$



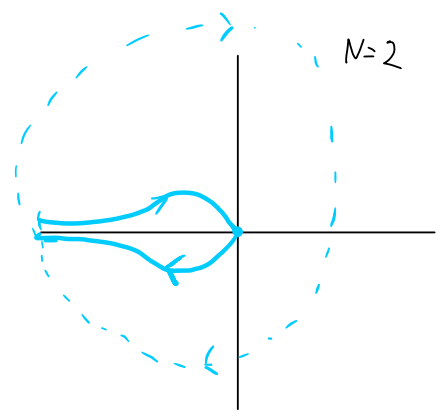
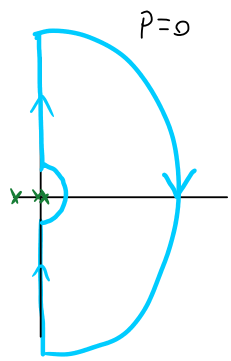
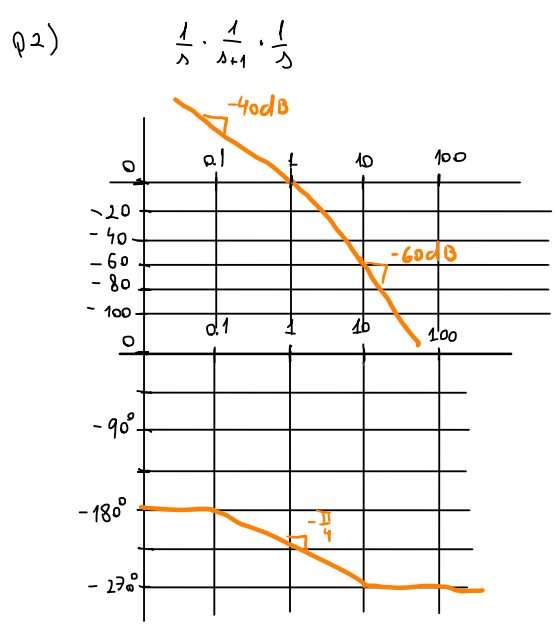
Q 1.2) $K=100 \Rightarrow$ "substitua" 40dB
 $G M^+ = +\infty$ dada que a fase para $\omega \rightarrow \infty$ é 180°
 $G M^- = -40dB$ que faz o que queremos

$E(s) = X(s) - Y(s)$ $\lim_{t \rightarrow \infty} e(t) = \lim_{s \rightarrow 0} s E(s)$
 $Y(s) = C(s) \cdot C(s)$
 $E(s) = \frac{1}{s} \cdot \frac{1}{1 + \frac{100}{s-1}}$ $\lim_{s \rightarrow 0} s \cdot \frac{1}{s} \cdot \frac{1}{1 + \frac{100}{s-1}} = \frac{1}{1-100} = \left[\frac{1}{99} \right] \rightarrow < 1\% \checkmark$



Q 1.5)
 K grande!
 é instável

Q 1.3)
 K pequena!
 é instável



$\frac{1}{s^2(s+1)}$ $\Rightarrow \frac{1}{s^2} e^{-2j\theta}$
 $s \rightarrow \epsilon e^{j\theta}$
 $P=0$
 $N=2 \Rightarrow z \neq 0$ é instável

Q 2.2)

R1) $\Rightarrow$ 1 integrador ($\frac{1}{s}$) ✓

R2) $\Rightarrow$ + 1 integrador ($\frac{1}{s}$) ✓

R3) $\Rightarrow$ $[0; 0.01] > 60dB$ ✓

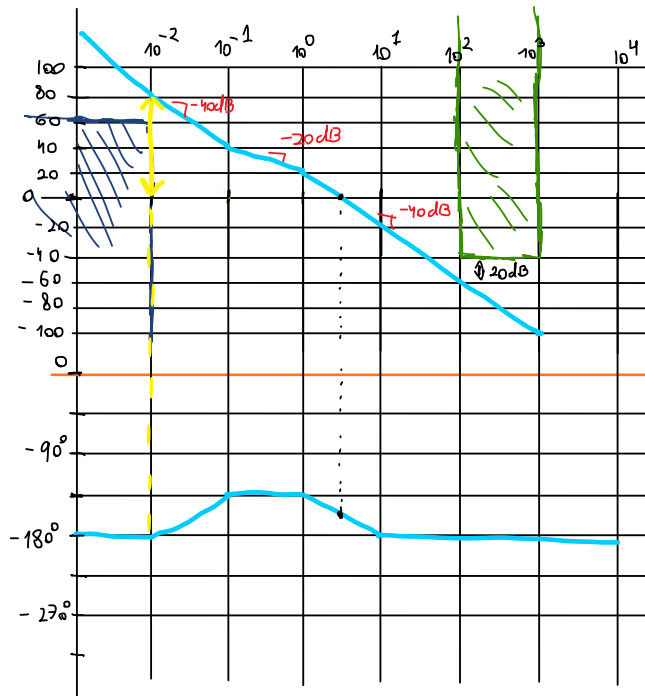
R4) $\Rightarrow$ $[10^2, 10^3] < -40dB$ ✓

R5) $\Rightarrow$ $P_M > 20^\circ$ ✓

R6) $\Rightarrow$ $G_M > 20dB$ ✓

$$K(s) = K \frac{s+a}{s\alpha} \quad \begin{matrix} R1) \\ R2) \end{matrix} \quad \checkmark$$

$$K = \frac{s+a}{\alpha} \cdot \frac{1}{s} \cdot \frac{1}{s} \cdot \frac{1}{(s+1)}$$



$\alpha = 0.1 \quad G_M = \infty$ (na entrada a respeito das perturbações é apenas 20dB)
 $K = 1 \quad P_M \approx 45^\circ //$

Q.2.2) Precisão do sistema 80dB

Q 2.3) $\tau = 1$

fase de $e^{-s\tau} = -\omega\tau$

$\omega = 3.16$ (na saída)
 -3.16

Atenuação
Entre valores
não amortecidos

$$\underbrace{PM_Z}_{0} = -\omega\tau + PM$$

$$0 < -\omega\tau + PM \approx -3.16 + \frac{\pi}{4} \quad PF \rightarrow \text{fica instável}$$