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continuous to  
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*Discrete Time  
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*State Space Model*

*for Discrete time*

*Control System*

*(Part 1) Discrete*

*Time Control*

*System: Design*

*methods based on*

*Frequency*

*Response Digital*

*control 8: Stability*

*of discrete-time*

*systems Digital*

*control 1: Overview*

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*Dynamical Systems*

ENGR487 Lecture 5

Closed-Loop Pulse

Transfer Function

and Discrete

Equivalent

Sampling Theorem

Why Z transforms?

For discrete time

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DCS unit 2 LEC 1

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#5: The bilinear

transform *Digital*

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*Control 10:*

*Continuous-time  
models of discrete-  
time systems*

~~Discrete Time  
Systems – Pulse  
Transfer Functions  
(Lecture 6 – Part I)  
Hardware Demo of  
a Digital PID  
Controller Control  
Systems || Lecture  
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**Derivation of the  
Transfer  
Function of the  
Zero Order Hold  
Block, 7/8/2016**

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~~Discrete Time~~

~~Systems - Inverse z-~~

~~Transforms Digital~~

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explanation of the  
Z transform part 1

**Pulse Transfer  
Function** ECE320

Lecture 10-1c:

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Systems Transfer  
Function Control

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9-1a: Discrete Time

System Design

State Equations

*Example TF to OCF*

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~~writing: Basics of  
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(chapter 4 - 4.3.3)

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*Designing for the  
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State Variable  
Analysis in Discrete  
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State Space*

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in this thesis.

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Concerning optimal time, it is shown that using discrete control system will take at most one

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avoiding highly mathematical arguments. The book features comprehensive treatment of pole placement, state observer design, and quadratic optimal control.

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Discrete control systems, as considered here, refer to the control theory of discrete-time Lagrangian or Hamiltonian systems.

Thesediscrete-time models are based on a discrete variational principle , and are

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part of the broader field of geometric integration .

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Such a discrete-time control

system consists of four major parts: 1

The Plant which is a continuous-time

dynamic system. 2

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The Analog-to-Digital Converter (ADC). 3 The Controller ( $\mu P$ ), a microprocessor with a “real-time” OS. 4 The Digital-to-Analog Converter (DAC). 3 + -  $r(t)$   
 $e(t)$  ADC  $\mu P$  DAC  
 $u(t)$  Plant ? ?  $y(t)$  4

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Notes for Discrete-Time Control Systems (ECE-520) Fall 2010 by R.

Throne The major sources for these notes are † Modern Control Systems, by Brogan, Prentice-Hall, 1991. † Discrete-Time Control Systems, by Ogata. Prentice-Hall, 1995. †



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Edition, by  
Åström and  
Wittenmark.

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First, digital  
computers are, by  
design, discrete-

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time devices, so discrete-time signals and systems includes digital computers. Second, almost all the important ideas in discrete-time systems apply equally to continuous-time systems. Alas, even discrete-time systems are too

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Katsuhiko Ogata.

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The time interval  
between two  
discrete instants is  
taken to be

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sufficiently short that the data for the time between them can be approximated by simple interpolation.

Discrete-time control systems differ from continuous-time control systems in that signals for a discrete-time



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Control system are  
in sampled-data  
form or in digital  
form.

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A comprehensive  
treatment of the  
analysis and design  
of discrete-time  
control systems  
which provides a

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gradual development of the theory by emphasizing basic concepts and avoiding highly mathematical arguments. The text features comprehensive treatment of pole placement, state observer design, and quadratic

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(available) at all times. A typical continuous time control system is shown in Figure below. (Closed loop continuous-time

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(control system)

Discrete time  
Control System:  
Discrete time

control systems are  
control systems in  
which one or more  
variables can  
change only at  
discrete instants of  
time. These  
instants, which  
may be denoted by  
 $kT(k=0,1,2,\dots)$

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