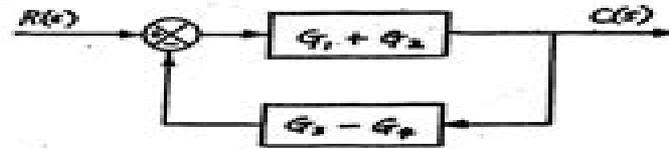


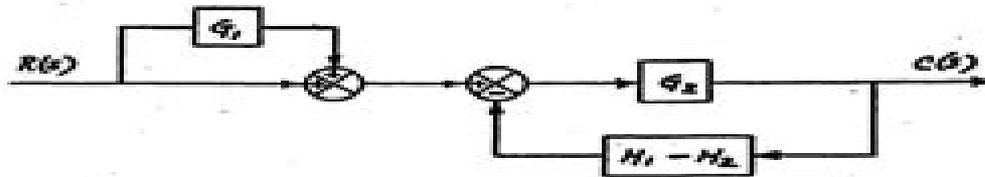
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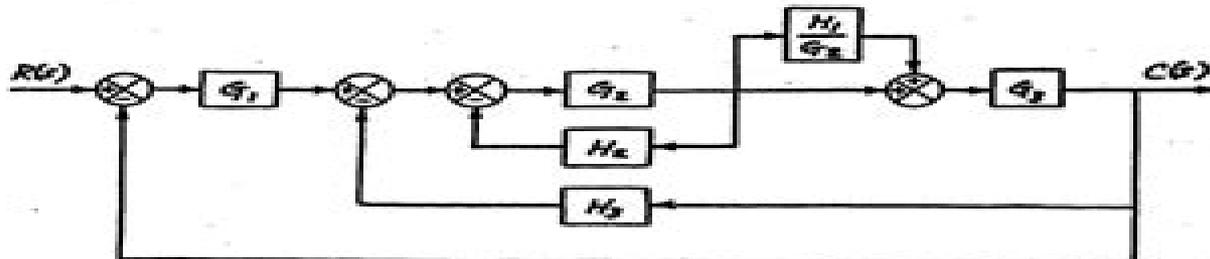
$$\frac{C(s)}{R(s)} = \frac{G_1 + G_2}{1 + (G_1 + G_2)(G_2 - G_p)}$$

B-3-2.



$$\frac{C(s)}{R(s)} = \frac{(1 + G_1)G_2}{1 + G_2(H_1 - H_2)}$$

B-3-3.



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Modern Control Engineering Katsuhiko Ogata, 1997 Comprehensive treatment of the analysis and design of continuous time control systems Partial contents The Laplace transform Mathematical modelling of dynamic system Transient response analysis Root locus analysis Frequency response analysis PID controls and introduction to robust control Control systems in state space Liapunov stability analysis and quadratic optimal control

Introduction to Digital Control Systems Hugh F. VanLandingham, 1985

Microcomputers and Modern Control Engineering Douglas A. Cassell, 1983 Good No Highlights No Markup all pages are intact Slight Shelfwear may have the corners slightly dented may have slight color changes slightly damaged spine

Modern Control Systems Theory Cornelius T. Leondes, 1965

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Advanced Modern Control System Theory and Design Stanley M. Shinnars, 1998-09-30 Linear Control System Compensation and Design Modern Control System Design Using State Space Pole Placement Ackermann's Formula Estimation Robust Control and H_∞ Techniques Digital Control System Analysis and Design Nonlinear Control System Design Introduction to Optimal Control Theory and Its Applications Control System Design Examples Complete Case Studies

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Solutions Manual, Modern Control Engineering, Fourth Edition Katsuhiko Ogata, 2002

Control Engineering, 1971 Instrumentation and automatic control systems

Applied Mechanics Reviews, 1982

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