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The fantail operates on the error signal  $w - T$ , and as the fantail

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turns, it drives the turret to turn.  $x$   $y$  Wind \* \*  $q_W$   $q_T$   $q_F$  Fantail  
Turret = Wind angle = Fantail angle = Turret angle  $q_W$   $q_T$   $q_F$  Torque  
 $q_T q_W$  Error - ProcessController Gears & turret Fantail © 2011 Pearson  
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12. CHAPTER 1. P1.19. Introduction to Control Systems. A control  
system to keep a car at a given relative position offset from a lead  
car: Throttle. Position of follower

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E1.4 An autofocus camera control system: One-way trip time for the  
beam Distance to subject Lens focusing motor  $K$   $l$  Lens Conversion  
factor (speed of light or sound) Emitter/ Receiver Beam Beam return  
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24. CHAPTER 2. E2.4. Mathematical Models of Systems. Since  $R(s) = 1/s$ , we have  $Y(s) = 6(s + 50) / s(s + 30)(s + 10)$ . The partial fraction expansion of  $Y(s)$  is given by  $A_1/A_2/A_3$   $Y(s) = \dots$

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~~Consider the system in Figure 2.79 where  $G_c(s) = 10$ ,  $H(s) \dots$~~

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Manual control system is the active control of the suspension system. One feedback control system uses a shock absorber consisting of a cylinder filled with a compressible fluid that provides both spring and Modern Control Systems, 12th Edition Page 11/27

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