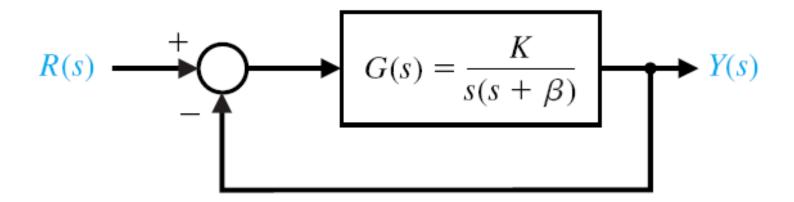
# Sensitivity and the Root Locus

 $S_k^{r_i} = \frac{\partial r_i}{\partial \ln k} = \frac{\partial r_i}{\partial k/k}$  $S_k^T = \frac{d \ln T}{d \ln k} = \frac{\partial T/T}{\partial k/k},$ 

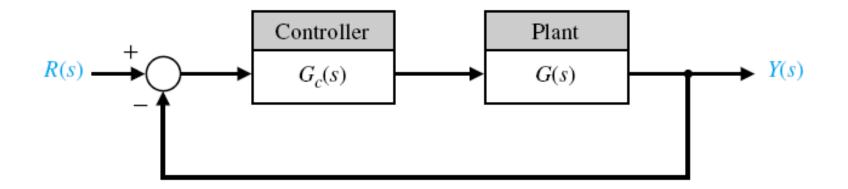
 $T(s) = \frac{K_1 \prod_{j=1}^m (s + Z_j)}{\prod_{i=1}^n (s + r_i)}$ 

 $S_k^T = \frac{\partial \ln K_1}{\partial \ln k} - \sum_{i=1}^n \frac{\partial r_i}{\partial \ln k} \cdot \frac{1}{(s+r_i)}$ 

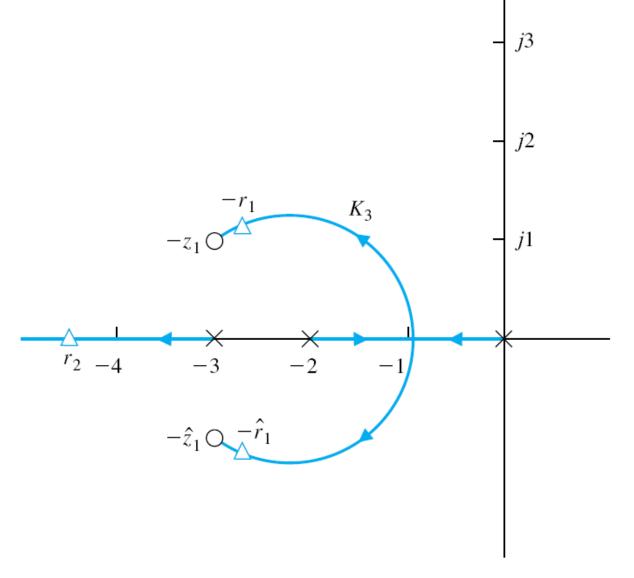
 $\frac{\partial Z_j}{\partial \ln k} = 0, \quad S_k^T = -\sum_{i=1}^n S_k^{r_i} \cdot \frac{1}{(s+r_i)} \quad S_k^{r_i} = \frac{\Delta r_i}{\Delta k/k}$ 



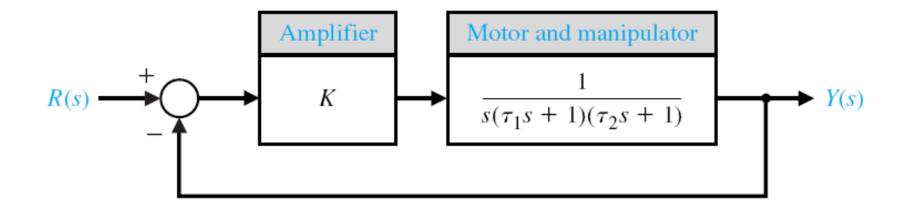
A feedback control system.



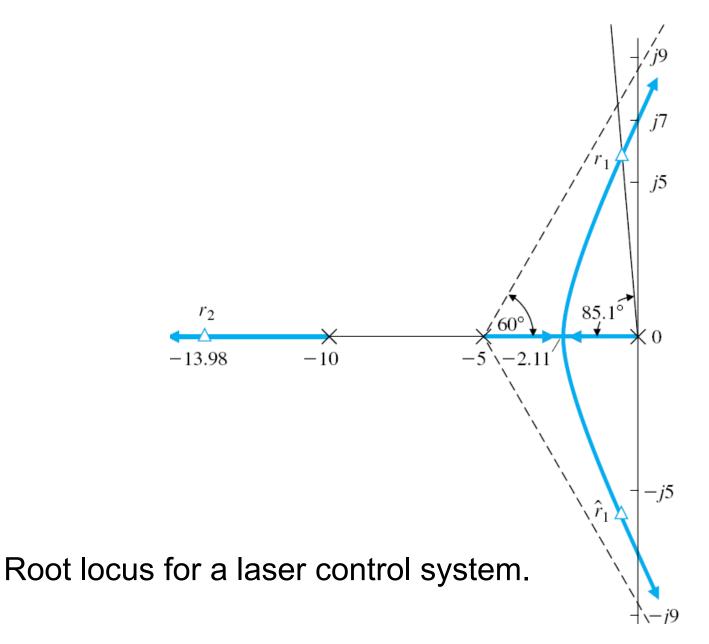
### Closed-loop system with a controller.

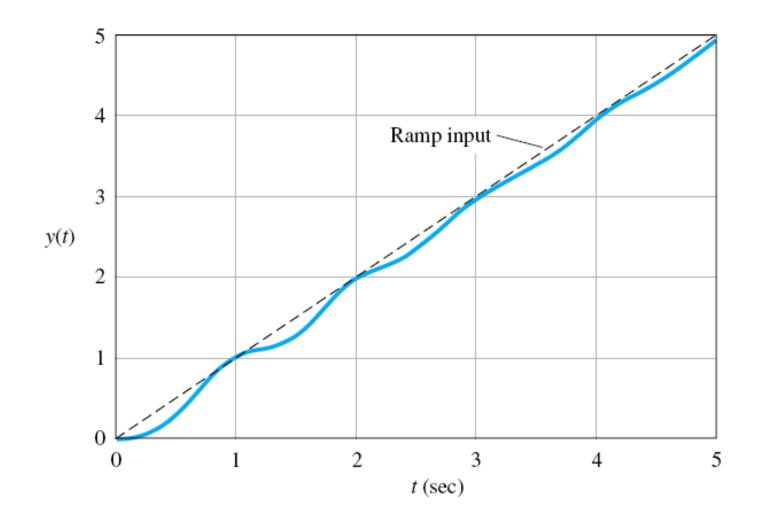


Root locus for plant with a PID controller with complex zeros.

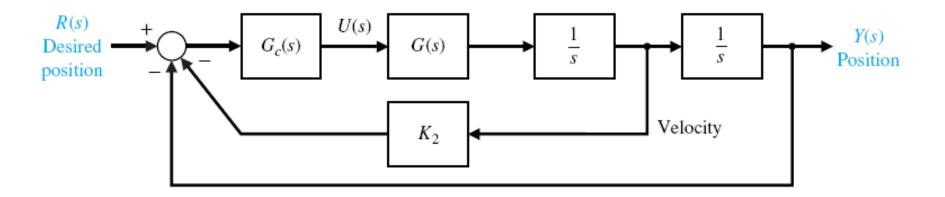


### Laser manipulator control system.

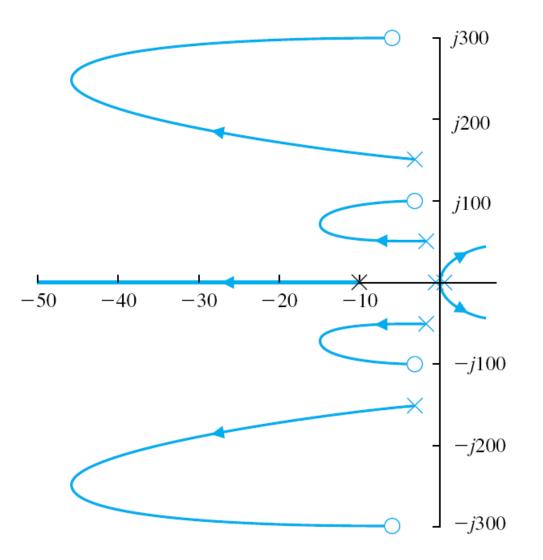




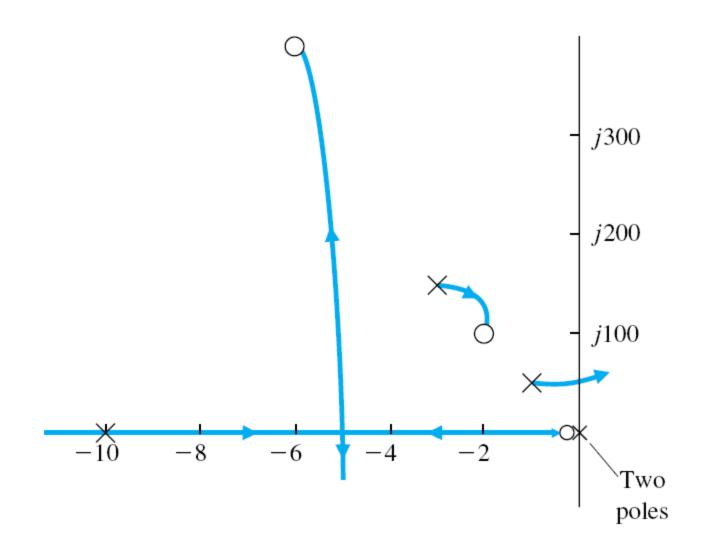
The response to a ramp input for a laser control system.



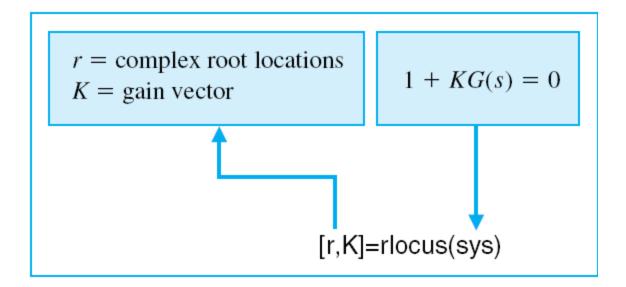
### Proposed configuration for control of the lightweight robot arm.



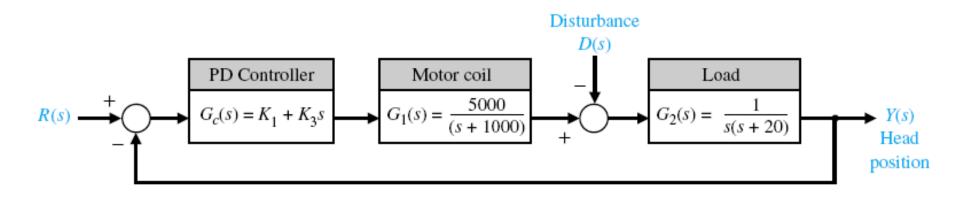
Root locus of the system if  $K_2=0$ ,and K1 is varied from  $K_1=0$  to  $K_1=\infty$ ,and  $G_c(s)=K_1$ .



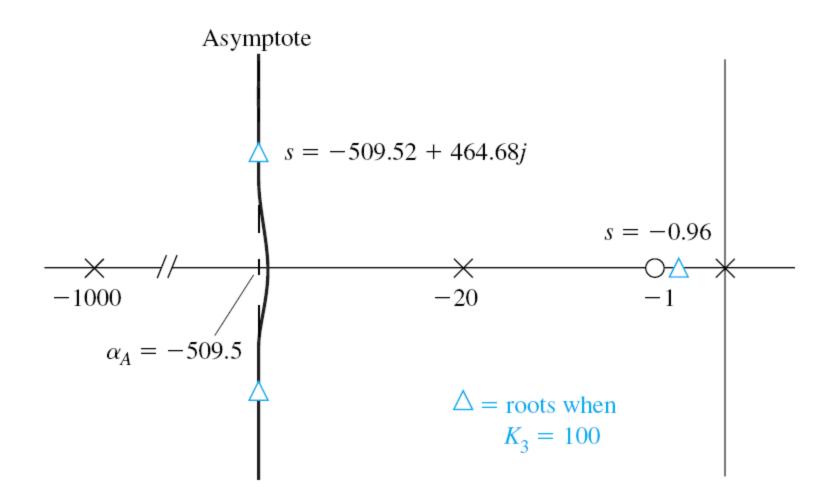
Root locus for the robot controller with a zero inserted at s=-0.2 with  $G_c(s) = K1$ .



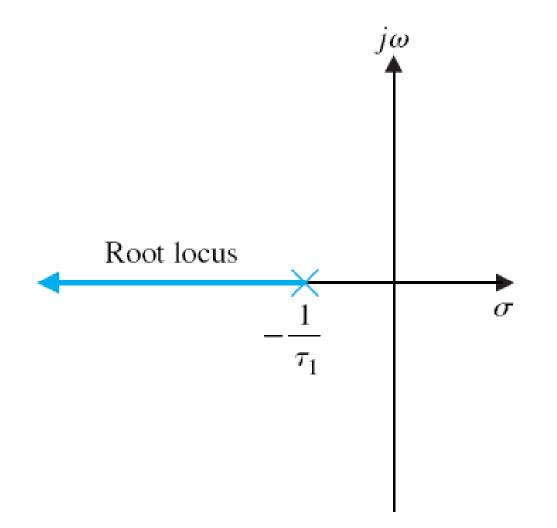
Using the rlocus function.

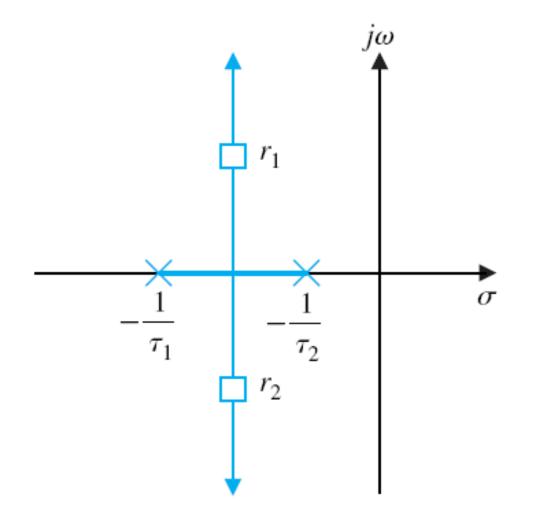


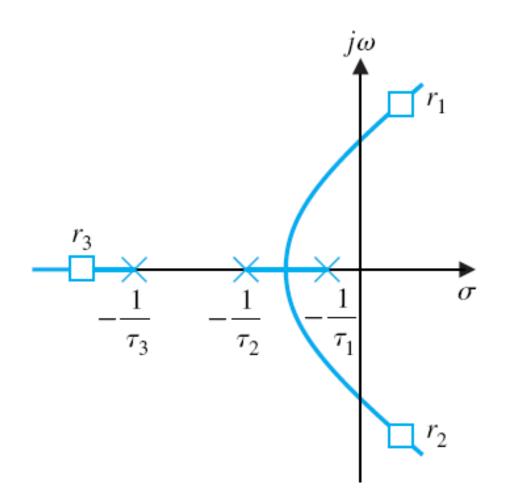
### Disk drive control system with a PD controller.

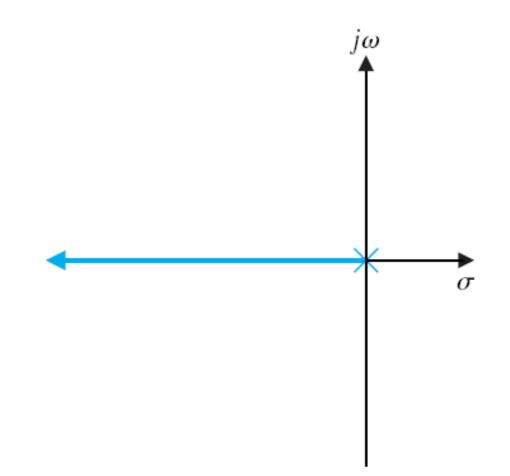


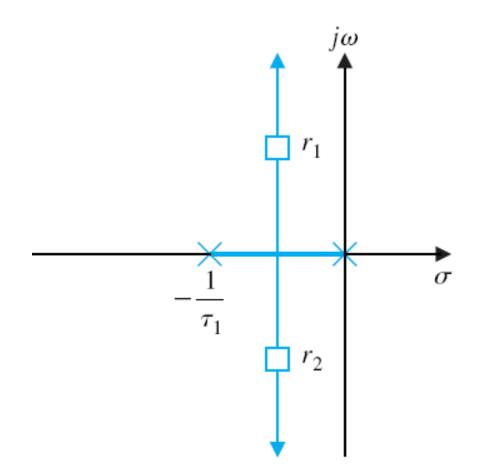
Sketch of the root locus.

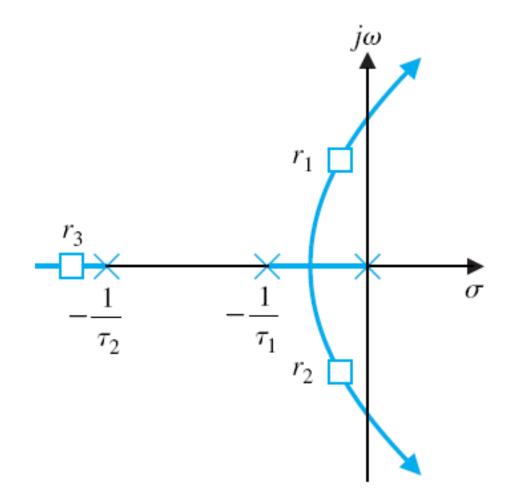


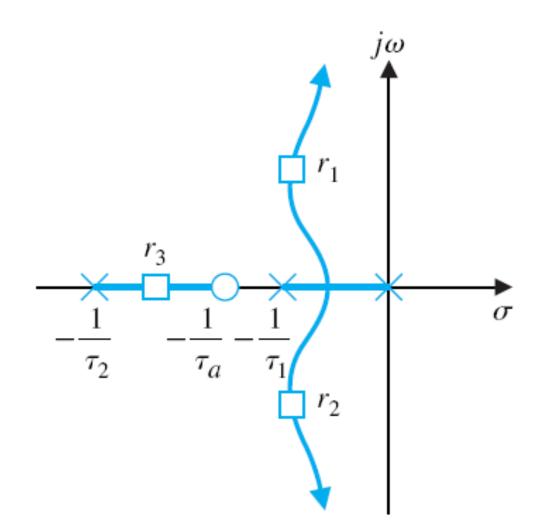


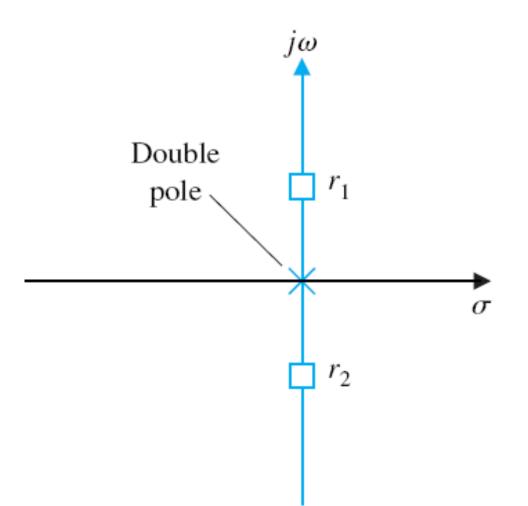


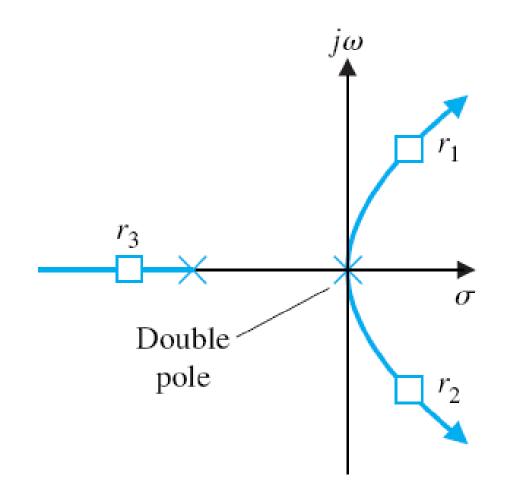


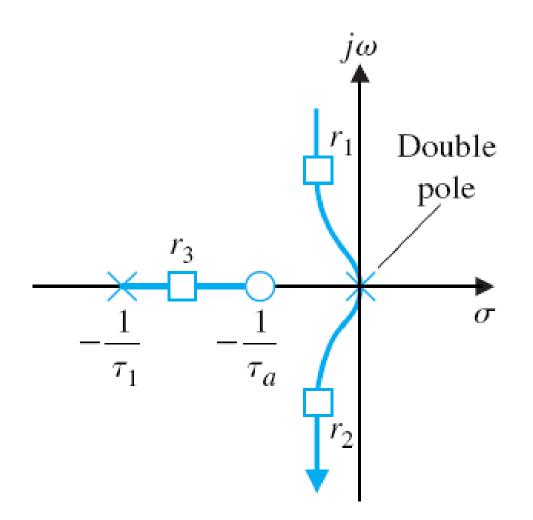


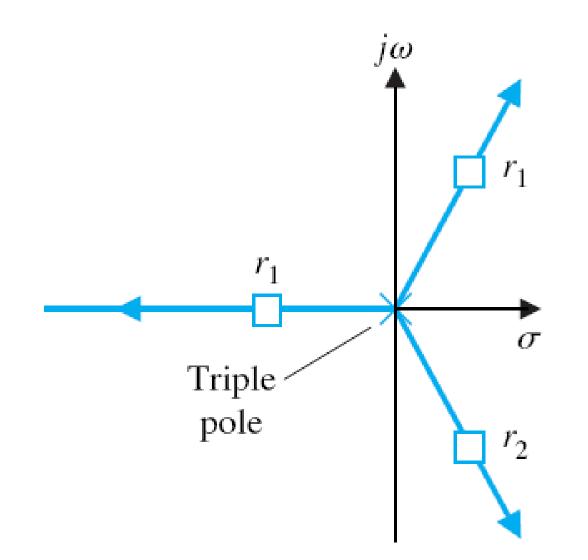


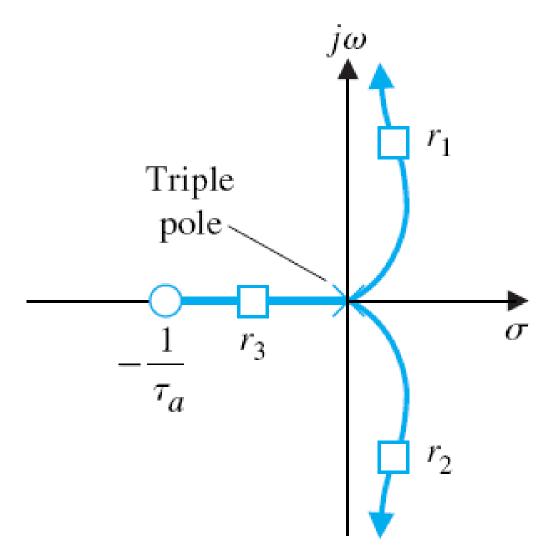












Root Locus Plots for Typical Transfer Functions (continued).

