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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 The Analog-to-Digital Converter (ADC). 3 The Controller (μP), a microprocessor with a “ real-time ” OS. 4 The Digital-to-Analog Converter (DAC)

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which one or more variable can change only at discrete instants of time. These instants which are denoted by t_k or kT , $k = 0, 1, 2, \dots$, specify the times at which some physical measurements are performed. The time interval between two discrete instants

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Introduction to Discrete-Time Control Systems

Includes the design of model matching control systems. emphasizes the usefulness of MATLAB for studying discrete-time control systems — showing how to use MATLAB optimally to obtain numerical solutions that involve various types of vector-matrix operations, plotting response curves, and system design based on quadratic optimal control.

Discrete-Time Control Systems 1995.

The time interval between two discrete instants is taken to be sufficiently short that the data for the time between them can be approximated by simple interpolation.

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Discrete-time control systems differ from continuous-time control systems in that signals for a discrete-time control system are in sampled-data form or in digital form.

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Figure 1: A discrete time control input with zero order hold applied to a continuous time system. $G_k(j) = \frac{1}{s} H(s) U(s)$: (11)
For stability, the eigenvalues of G must have magnitude < 1 . So if the continuous time plant is stable ($\text{eig}(A) < 0$) the discrete time plant will have eigenvalues with magnitude less than 1.

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Lecture: Discrete-time linear systems

Sampling continuous-time systems. Exact

sampling. Rule of thumb: $T_s \sim 1/10$ of

the rise time = time to move from 10% to 90% of the steady-state value, for input $u(t)$

$1, x(0) = 0$.

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