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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. 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. $G_k(j) = 1$ For stability, the eigenvalues of G_{must} have magnitude < 1 . So if the continuous time plant is stable ($\sigma(A) < 0$) 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: $T_s \approx 0.1$ 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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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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Discrete-time linear systems

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