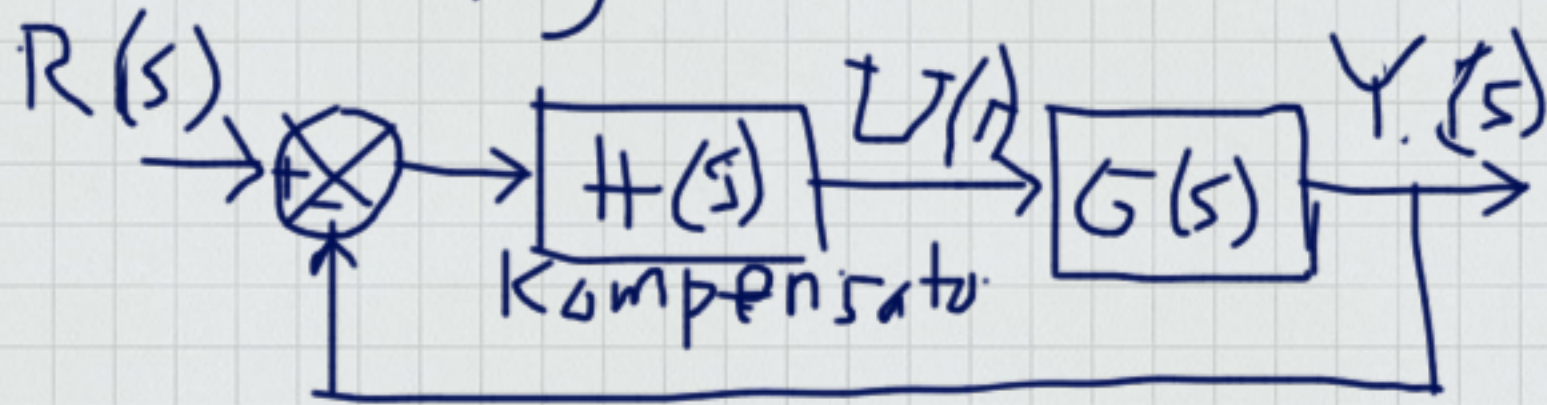
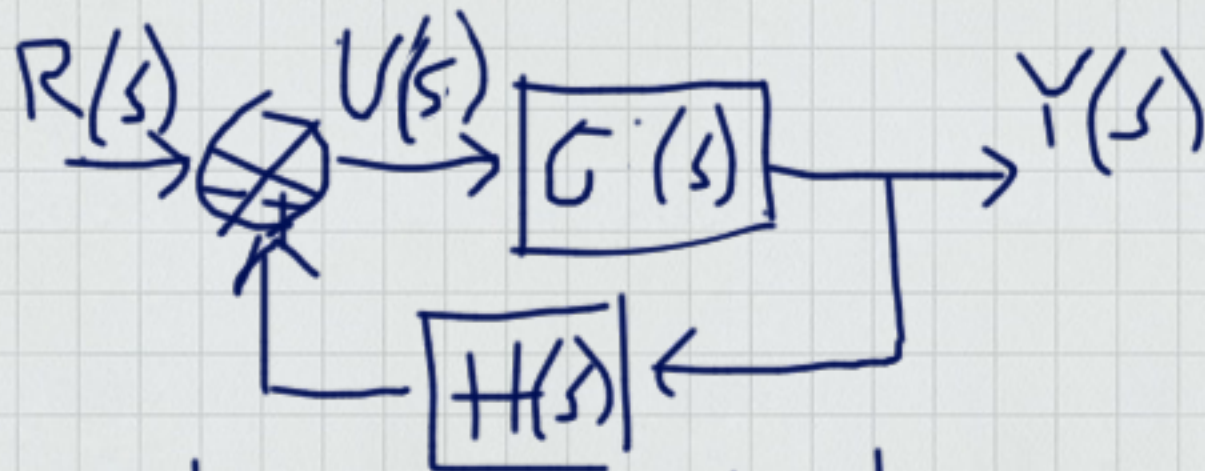


Dua konfigurasi sistem kendali.



Sistem Kendali dengan
KOMPENSATOR

$$\text{CLTF} \\ G_T(s) = \frac{Y(s)}{R(s)} = \frac{G(s)H(s)}{1 + G(s)H(s)}$$



Sistem Kendali dengan
UMPAH BALIK

$$\text{CLTF} = G_T(s) = \frac{Y(s)}{R(s)} = \frac{G(s)}{1 + G(s)H(s)}$$

Persamaan karakteristik: $1 + G(s)H(s) = 0$