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**MONTH YEAR**

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**GRADUATE SCHOOL OF NATURAL & APPLIED SCIENCES**

**M.Sc. in Department’s Name**

**TITLE OF THESIS**

**CE 499 GRADUATION PROJECT**

**IN**

**DEPARTMENT’S NAME**

**NAME SURNAME**

**BY**

**NAME SURNAME**

**MONTH YEAR**

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**in**

**Department’s Name**

**Gaziantep University**

**Supervisor**

**Prof. Dr. Name SURNAME**

**Co-Supervisor (if any)**

**Prof. Dr. Name SURNAME**

**by**

**Name SURNAME**

**Month Year**

**I hereby declare that all information in this document has been obtained and presented in accordance with academic rules and ethical conduct. I also declare that, as required by these rules and conduct, I have fully cited and referenced all material and results that are not original to this work.**

**Name SURNAME**

# ABSTRACT

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**Yüksek Lisans/Doktora Tezi, ……**

**Danışman: Dr. Öğr. Üyesi Adı SOYADI**

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***‘’Dedicated to my family’’***

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# LIST OF SYMBOLS

|  |  |
| --- | --- |
| **α** | Alfa |
| **β**  | Beta |
| **Ω** | Ohm |
| **π** | Pi |

# LIST OF ABBREVIATIONS

|  |  |
| --- | --- |
| **A/D** | Analog to Digital |
| **B-SPM** | Bilinear Static Parametric Model |
| **CE** | Certainty Equivalence |
| **D/A** | Digital to Analog |
| **DC** | Direct Current |
| **DIN** | Dynamic Inertial System |
| **FD** | Fault Detection |
| **FDD** | Fault Detection Diagnosis |
| **FDI** | Fault Detection and Isolation |
| **FTC** | Fault Tolerant Control |
| **g-DIN** | Generalized Dynamic Inertial System |
| **ISE** | Integral Square Error |
| **ISR** | Interrupt Service Routine |
| **LQR** | Linear Quadratic Regulator |
| **LTI** | Linear Time Invariant |
| **MIMO** | Multi Input Multi Output |
| **MRAC** | Model Reference Adaptive Control |
| **MSE** | Mean Square Error |
| **PDJ** | Positive Diagonal Jordan |
| **PEA** | Parametric Eigenstructure Assignment |
| **PSUPA** | Power Supply/Power Amplifier Unit |
| **SISO** | Single Input Single Output |
| **SPR** | Strictly Positive Real  |

# CHAPTER I

# INTRODUCTION

## 1.1 Motivation of Study

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Sunt in culpa qui officia deserunt mollit anim id est laborum. There are wide varieties of control methods in FTC and an extensive research is still conducted. However the lack of a systematical approach is still an open problem. . Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea

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**Figure 1.1** Equivalent control system block diagram for time-varying gain control equivalent is system block diagram for time-varying gains.

There are wide varieties of control methods in FTC and an extensive research is still conducted. However the lack of a systematical approach is still an open problem. The equation sample can be given as follows:

  (1.1)

Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis autte irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum. The table sample is given in Table 1.1

 (1.2)

**Table 1.1** Process parameters

|  |  |
| --- | --- |
| **Parameters** | **Value** |
| Tank height, *hmax* | 25 cm |
| Pomp voltage level | 0-5 V |
| Bottom area, Tank1, Tank2, *A1*, *A2* | 0.01389 m2 |
| Bottom area, Tank3, Tank4, *A3*, *A4* | 0.01389 m2 |
| Out pipe cross-sectional area, *a1,a3,,a2,a4* | 50.26e-6 m2 |
| Pomp constant, *k* | 2.2e-3 lt/Vs |
| Tank1 operating point level *h1o* | 8.0 cm |
| Tank2 operating point level *h2o* | 5.0 cm |
| Tank3 operating point level *h3o* | 1.5 cm |

**Table 1.2** System operating point

|  |  |  |
| --- | --- | --- |
| Control Method | Output1 ISE | Output2 ISE (×103) |
| Design I | 391.59 | 1.0151 |
| Design II | 389.58 | 0.6418 |
| Design III | 379.61 | 0.0001 |

#

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