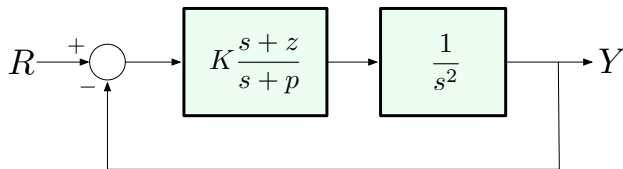# Dynamic Compensation

Objectives: stabilize the system and satisfy given time response specs using a *stable, causal* controller.

Characteristic equation:

$$1 + K \cdot \frac{s+z}{s+p} \cdot \frac{1}{s^2} = 1 + KL(s) = 0$$