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Control Systems with Scilab Aditya Sengupta Indian Institute of Technology Bombay apsengupta@iitb.ac.in  
December 1, 2010, Mumbai. A simple first order system // Defining a first order system : s = %s // The quicker alternative to using s = poly (0 , 's ') K = 1, T = 1 // Gain and time constant

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