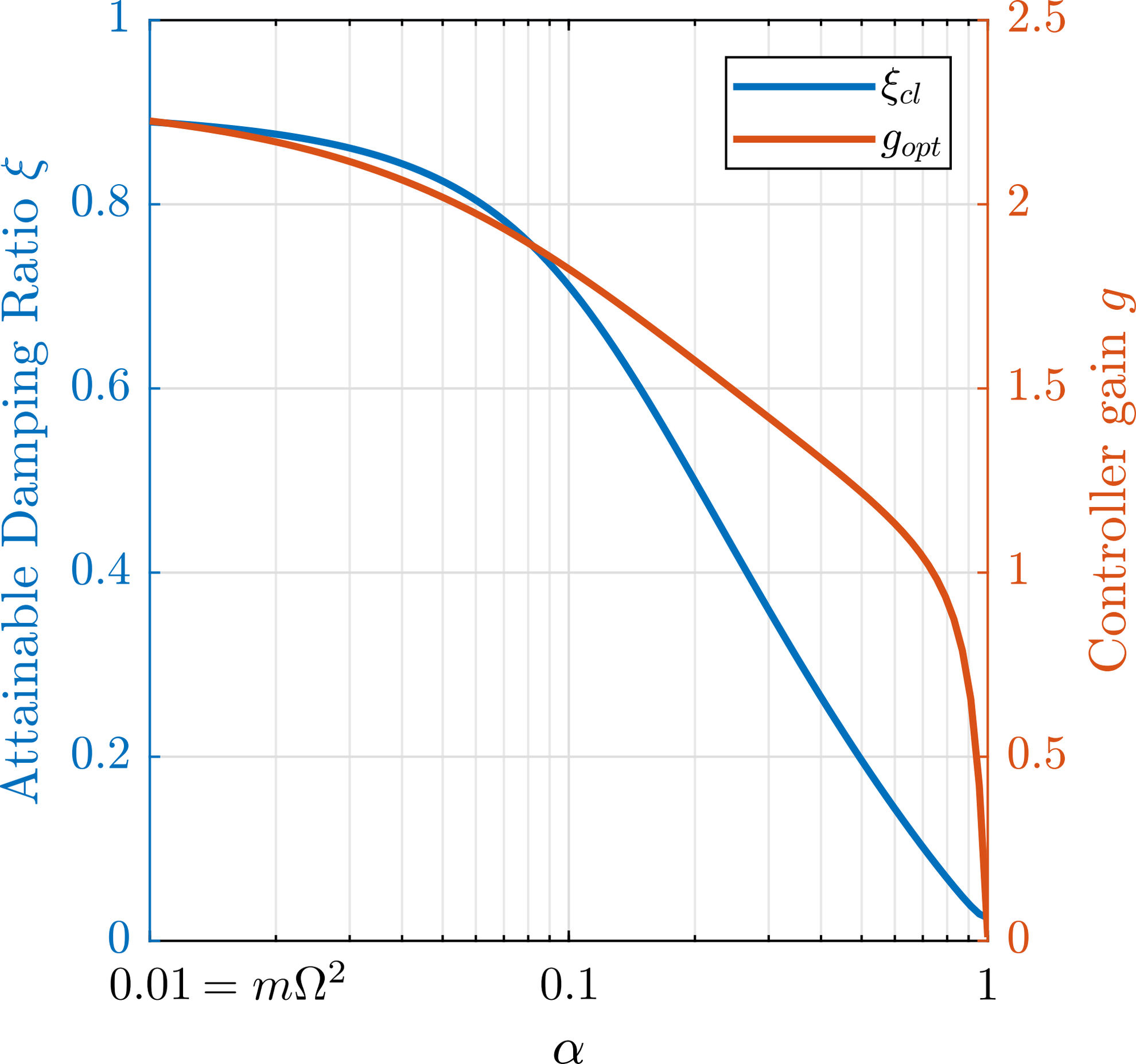
ξ_{cl}
g_{opt}
Attainable Damping Ratio ξ
Controller gain g
α
$0.01 = m\Omega^2$
0.1
1
0
0.2
0.4
0.6
0.8
1
0
0.5
1
1.5
2
2.5