

Find a complete state-space model (A , B , C , and D matrices, plus \underline{z} , \underline{u} , \underline{y} vectors) for the system shown at left.

The input is the pump pressure source P_s

The two outputs are

- (i) the pressure change across the inertia Q_1 , and
- (ii) the flow through the resistor R

Solution:

Begin by defining the state, input, and output vectors:

$$\underline{z}(t) = \begin{bmatrix} P_{C1} \\ P_{C2} \\ Q_{I1} \\ Q_{I2} \\ Q_{I3} \end{bmatrix} \quad \underline{u}(t) = (P_s) \quad \underline{y}(t) = \begin{bmatrix} P_{I1} \\ Q_{R1} \end{bmatrix}$$

Now proceed to find the state and output equations and fill in A , B , C , and D :

$$\begin{aligned} \dot{P}_{C1} &= \frac{1}{C_1} Q_{C1} = \frac{1}{C_1} [Q_{I1} + Q_{R1} - Q_{I2} - Q_{I3}] = \frac{1}{C_1} \left[Q_{I1} + \frac{P_s - P_{C1}}{R_1} - Q_{I2} - Q_{I3} \right] \\ \dot{P}_{C2} &= \frac{1}{C_2} Q_{C2} = \frac{1}{C_2} Q_{I3} \\ \dot{Q}_{I1} &= \frac{1}{I_1} P_{I1} = \frac{1}{I_1} [P_s - P_{C1}] \\ \dot{Q}_{I2} &= \frac{1}{I_2} P_{I2} = \frac{1}{I_2} P_{C1} \\ \dot{Q}_{I3} &= \frac{1}{I_3} P_{I3} = \frac{1}{I_3} [P_{C1} - P_{C2}] \end{aligned}$$

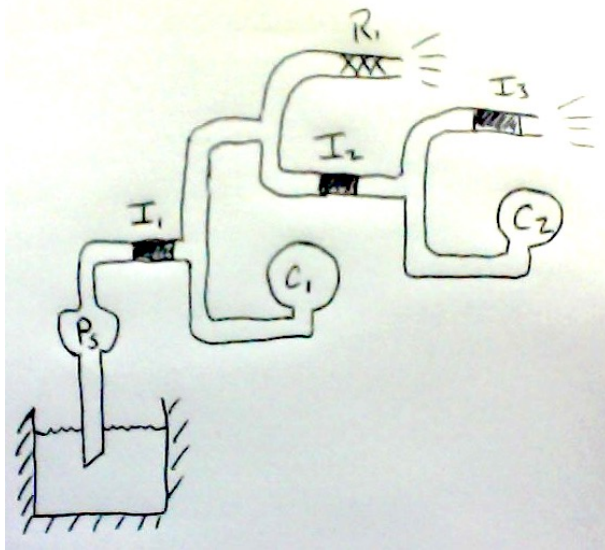
Thus,

$$A = \begin{bmatrix} -\frac{1}{C_1 R_1} & 0 & \frac{1}{C_1} & -\frac{1}{C_1} & -\frac{1}{C_1} \\ 0 & 0 & 0 & 0 & \frac{1}{C_2} \\ -\frac{1}{I_1} & 0 & 0 & 0 & 0 \\ \frac{1}{I_2} & 0 & 0 & 0 & 0 \\ \frac{1}{I_3} & -\frac{1}{I_3} & 0 & 0 & 0 \end{bmatrix} \quad B = \begin{bmatrix} \frac{1}{C_1 R_1} \\ 0 \\ \frac{1}{I_1} \\ 0 \\ 0 \end{bmatrix}$$

The output equation is

$$\underline{y}(t) = \begin{bmatrix} P_{I1} \\ Q_{R1} \end{bmatrix} = \begin{bmatrix} P_s - P_{C1} \\ \frac{1}{R_1} (P_s - P_{C1}) \end{bmatrix}$$

$$C = \begin{bmatrix} -1 & 0 & 0 & 0 & 0 \\ -\frac{1}{R_1} & 0 & 0 & 0 & 0 \end{bmatrix} \quad D = \begin{bmatrix} 1 \\ \frac{1}{R_1} \end{bmatrix}$$



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The input is the pump pressure source P_s

The two outputs are

- (i) the flow into the capacitance C_1 , and
- (ii) the flow through the resistor R_1

Solution:

Begin by defining the state, input, and output vectors:

$$\underline{z}(t) = \begin{bmatrix} P_{C1} \\ P_{C2} \\ Q_{I1} \\ Q_{I2} \\ Q_{I3} \end{bmatrix} \quad \underline{u}(t) = (P_s) \quad \underline{y}(t) = \begin{bmatrix} Q_{C1} \\ Q_{R1} \end{bmatrix}$$

Now proceed to find the state and output equations and fill in A , B , C , and D :

$$\begin{aligned} \dot{P}_{C1} &= \frac{1}{C_1} Q_{C1} = \frac{1}{C_1} [Q_{I1} - Q_{I2} - Q_{R1}] = \frac{1}{C_1} \left[Q_{I1} - Q_{I2} - \frac{P_{C1}}{R_1} \right] \\ \dot{P}_{C2} &= \frac{1}{C_2} Q_{C2} = \frac{1}{C_2} (Q_{I2} - Q_{I3}) \\ \dot{Q}_{I1} &= \frac{1}{I_1} P_{I1} = \frac{1}{I_1} (P_s - P_{C1}) \\ \dot{Q}_{I2} &= \frac{1}{I_2} P_{I2} = \frac{1}{I_2} (P_{C1} - P_{C2}) \\ \dot{Q}_{I3} &= \frac{1}{I_3} P_{I3} = \frac{1}{I_3} P_{C2} \end{aligned}$$

Thus,

$$A = \begin{bmatrix} -\frac{1}{C_1 R_1} & 0 & \frac{1}{C_1} & -\frac{1}{C_1} & 0 \\ 0 & 0 & 0 & \frac{1}{C_2} & -\frac{1}{C_2} \\ -\frac{1}{I_1} & 0 & 0 & 0 & 0 \\ \frac{1}{I_2} & -\frac{1}{I_2} & 0 & 0 & 0 \\ 0 & \frac{1}{I_3} & 0 & 0 & 0 \end{bmatrix} \quad B = \begin{bmatrix} 0 \\ 0 \\ \frac{1}{I_1} \\ 0 \\ 0 \end{bmatrix}$$

The output equation is

$$\underline{y}(t) = \begin{bmatrix} Q_{C1} \\ Q_{R1} \end{bmatrix} = \begin{bmatrix} Q_{I1} - Q_{I2} - \frac{P_{C1}}{R_1} \\ \frac{P_{C1}}{R_1} \end{bmatrix}$$

$$C = \begin{bmatrix} -\frac{1}{R_1} & 0 & 1 & -1 & 0 \\ \frac{1}{R_1} & 0 & 0 & 0 & 0 \end{bmatrix} \quad D = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$