

$$\ddot{y} + 3\dot{y} = 2u, \quad h(t) > 0 \text{ for } t < 0.$$

$$(s+3)\hat{y}(s) = 2\hat{u}(s)$$

$$\frac{\hat{y}(s)}{\hat{u}(s)} = \frac{2}{s+3} \quad h(s) = \frac{2}{s+3}$$

$$\text{impulse response} = h(t) = \mathcal{L}^{-1}\left(\frac{2}{s+3}\right) = 2e^{-3t}$$

$$b) \quad u(t) = 5e^{at} \quad (\text{unforced, open loop control})$$

$$\ddot{y} + 3\dot{y} = 10e^{at}$$

$$\hat{y}(s)(s+3) = \frac{10}{s-a}$$

$$\hat{y}(s) = \frac{10}{(s-a)(s+3)} = \mathcal{L}^{-1}\left(\frac{10((s-a) - (s+3))}{-(a+3)(s-a)(s+3)}\right)$$

$$= \frac{-10}{a+3} \left(\mathcal{L}^{-1}\left(\frac{1}{s+3}\right) - \mathcal{L}^{-1}\left(\frac{1}{s-a}\right) \right)$$

$$= \frac{-10}{a+3} (e^{-3t} - e^{at})$$

$$c) \quad y(t) = \int_0^t u(\tau) h(t-\tau) d\tau$$

$$= \int_0^t 5e^{a\tau} \cdot 2e^{-3(t-\tau)} d\tau$$

$$= \int_0^t 10 e^{a\tau - 3t + 3\tau} d\tau$$

$$= 10e^{-3t} \int_0^t e^{(a+3)\tau} d\tau$$

$$y(t) = \frac{10e^{-3t}}{(a+3)} \left[e^{(a+3)\tau} \right]_0^t$$

$$= \frac{10e^{-3t} (e^{t(a+3)} - 1)}{a+3}$$

$$= \frac{10(e^{at} - e^{-3t})}{a+3}$$

$$= \frac{-10(e^{-3t} - e^{at})}{a+3}$$

$$d) y(t) = \frac{10}{a+3} (e^{at} - e^{3t})$$

Scaled for only, e^{at} eigen function.

$$\frac{1}{5} \times \frac{10}{a+3} (1 - e^{(3-a)t}) = \frac{2}{a+3} (1 - e^{(3-a)t})$$

Coef. of exponent e^{at} , $= \frac{2}{a+3}$ in at/t / int

$$\frac{1}{s-a}$$

$$g(s) = \frac{2}{s+3}$$

$$y(t) = \frac{10}{a+3} (e^{at} - e^{3t})$$

$$u(s) = \frac{2}{s+3}$$

$$\frac{2}{a+3} (1 - e^{(a-3)t})$$

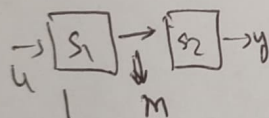
$$\frac{10}{a+3}$$

part eigen function

Q2) a) —

$$b) \int_0^t C_0 e^{5\tau} d\tau = \frac{C_0}{5} (e^{5t} - 1)$$

Q-3)



$$m = u * h_1$$

$$y = u * h_1 * h_2$$

$$y = (h_1 * h_2) * u$$

$$h_{int} = h_1 * h_2$$

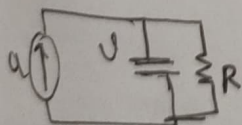
$$h_{int} = \mathcal{L}^{-1} (\hat{h}_1(s) \hat{h}_2(s))$$

$$= \mathcal{L}^{-1} \left(\frac{C_0}{5} \times \frac{1}{s-5} \right)$$

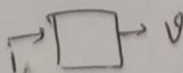
$$= \frac{C_0}{5} \mathcal{L}^{-1} \left(\frac{1}{s-5} \right)$$

$$h_{int} = \frac{C_0}{5} (e^{5t} - 1) = \frac{C_0}{5} (e^{5t} - 1)$$

Q4)



$$C = 1F, R = 10^3 \Omega$$



$$a) \frac{dv}{dt} + \frac{v}{R} = i(t)$$

$$(s + \frac{1}{R}) \hat{v}(s) = \hat{i}(s)$$

$$\frac{1}{1+sR} = \frac{\hat{v}(s)}{\hat{i}(s)}$$

$$G(s) = \frac{R}{1+sR}$$

b) Pole at -5,

$$1 + sR, s = -\frac{1}{R}, \text{ root.}$$

$$-\frac{1}{R} = -5, R = 0.2$$

Pole at -1, $-\frac{1}{R} = -1, R = 1$

c) $|G(j\omega)|$ vs ω ,

$$|G(j\omega)| = \left| \frac{R}{1 + 2\pi f R j} \right|$$

$$\frac{R}{\sqrt{1 + (2\pi f R)^2}} = \frac{R}{\sqrt{1 + (\omega R)^2}}$$

low pass filter

e) $|G(j\omega)| = \frac{1}{\sqrt{2}}, R^2 \omega^2 = 1 + \omega^2 R^2$

$$\frac{1}{2 - \omega^2} = 10^3$$

$$10^6 = \frac{1}{2 - \omega^2}$$

$$R^2 = \frac{1}{(2 - \omega^2)}$$

$$\sqrt{2 - 10^6} = \omega$$

Q5) $F = \ddot{\theta} - \theta$

$$\hat{F}(s) = (s^2 - 1)\hat{\theta}(s)$$

$$\frac{\hat{\theta}(s)}{\hat{F}(s)} = \frac{1}{s^2 - 1}$$

(a) $S = \pm 1$,

One root in RHP, inverted pendulum.

(b) $F = K_p \theta$

$$\ddot{\theta} - \theta = K_p \theta$$

$$(s^2 - (1 + K_p))\hat{\theta}(s) = 0$$

$$s^2 = 1 + K_p$$

Root in open LHP, \Rightarrow Not possible

Closed LHP $\rightarrow K_p \leq -1$

(c) $F = D\ddot{\theta} + K_d\dot{\theta}$

$\ddot{\theta} - (K_p+1)\theta - K_d\dot{\theta} = 0$

$(s^2 - (K_p+1) - K_d s) \theta(s) = 0$

$s^2 - K_d s - (K_p+1) = 0$

time const = 0.3 sec,

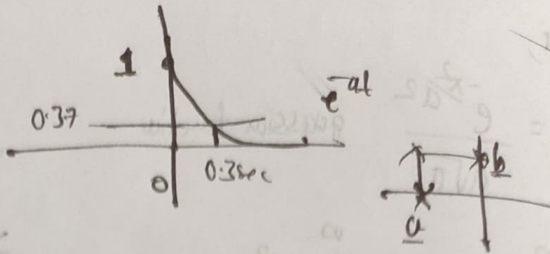
oscillation freq = 2 rad/sec

$$\frac{K_d \pm \sqrt{K_d^2 - 4(K_p+1)}}{2}$$

$K_d \pm \sqrt{K_d^2 - 4(K_p+1)} = -\frac{20}{3} \pm 4j$

$K_d = -\frac{20}{3}$

$\frac{400}{9} - 4(K_p+1) = -16$



$e^{-a \times 0.3} = e^{-1}$
 $a = 1/0.3$

$a = 1/0.3, b = 2$

$-\frac{10}{3} \pm 2j$

(d) $(s^3 + 4s^2 + s - 6) \hat{y}(s) = \hat{u}(s)$

$(s^3 + 4s^2 + s - 6 - K) \hat{y}(s) = 0$

closed loop is stable,

$K_0 = K_1 K_2$

$(-6 - K) = 4$

$K = -10 \rightarrow$ No of RL



$-10 \leq K \leq -6$

