title of your presentation

July 14, 2015

Outline

Discretization of Continuous-time systems

Use of discretization

Many systems in the real world are continous systems: chemical reactions, rocket trajectories, power plants, ice cap melting... Computers, however, are mainly digital. If we want to simulate the continuous system with a digital device, we need a method to convert the continuous model into a discrete one. This conversion is called "discretization" or "sampling". Discretization also comes in handy when a continuous filter with usefull properties has been designed and a discrete filter with the same properties is required.

Discretization

Problem statement

While converting, some information of the continuous model will be lost due to the different nature of the systems. It is important that the loss of information is minimized. Each discretization method has its own qualities and they will all lead to different discrete representations of the same continuous system.

Discretization methods discussed in this lecture

- Numerical Integration
- Zero-pole equivalent
- Hold equivalents

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Numerical Integration

General approach

The system transfer function H(s) is first represented by a differential equation. Next a difference equation, whose solution is an approximation of this differential equation, is derived:

$H(s) = \frac{a}{s+a}$ is equivalent to the differential equation

$$\frac{\mathrm{d}}{\mathrm{d}t}\big(u(t)\big) + a*u(t) = a*e(t)$$

solving this equation results in the following integral

$$u(t) = \int_0^t \big(-a*u(\tau) + a*e(\tau)\big)\mathrm{d}\tau$$

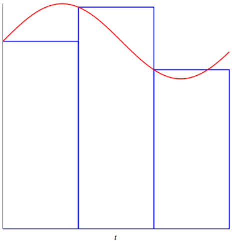
$$u(k*T) = u(k*T-T) + \begin{cases} \text{area of } -a*u(t)+a*e(t) \\ \text{over } k*T-T \le \tau < k*T \end{cases} \tag{8.1}$$

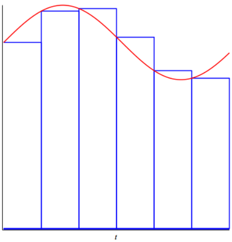
Where T is the sampling time. The transfer function above will be used for all the numerical integration methods.

Forward rectangular rule (=Forward Euler)

General approach

The area is approximated by the rectangle looking **forward** from $(k * T - T)$ toward $k * T$ with an amplitude equal to the value of the function at $(k * T - T)$. A smaller step-size T leads to a more accurate approximation, as shown in the figures.





Forward rectangular rule

Mathematical approach

The general approach (formula (8.1)) applied on the forward rectangle rule, results in an equation u_1:

$$\begin{aligned} u_1(k*T) &= u_1(k*T-T) + T*\big(-a*u_1(k*T-T) \\ &\quad + a*e(k*T-T)\big) \\ &= (1-a*T)*u_1(k*T-T) + a*T*e(k*T-T) \end{aligned}$$

Forward rectangular rule

Mathematical approach

In this case, the transfer function is:

$$H_F(z) = \frac{a}{(z-1)/T+a}$$

Which can also be derived using the following substitution in the given transfer function:

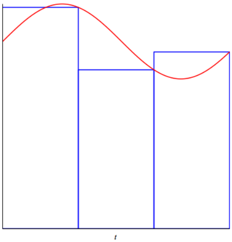
$$s \leftarrow \frac{z-1}{T} \text{ (8.2)}$$

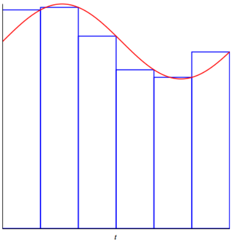
This is extremely usefull while making exercises.

Backward rectangular rule (=Backward Euler)

General approach

The area is approximated by the rectangle looking **backward** from $k * T$ toward $(k * T - T)$ with an amplitude equal to the value of the function at $k * T$.





Backward rectangular rule

Mathematical approach

The general approach (formula (8.1)) applied on the forward rectangle rule, results in an equation u_2:

$$\begin{aligned} u_2(k*T) &= u_2(k*T-T) + T*\big(-a*u_2(k*T) + a*e(k*T)\big) \\ &= \frac{u_2(k*T-T)}{1+a*T} + \frac{a*T}{1+a*T}*e(k*T) \end{aligned}$$

Backward rectangular rule

Mathematical approach

In this case, the transfer function is:

$$H_B(z) = \frac{a}{(z-1)/T*z+a}$$

Which can also be derived using the following substitution in the given transfer function:

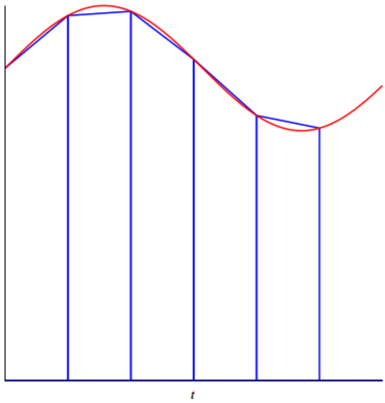
$$s \leftarrow \frac{z-1}{T*z} \quad (8.3)$$

Again this is extremely usefull while making exercises.

Trapezoidal rule (= bilinear or Tusting rule)

General approach

This method makes use of the area of the **trapezoid** formed by the average of the selected rectangles used in the forward en backward rectangle rule.Thus the amplitude equal to the value of the function at $(k * T - T)$ and the amplitude equal to the value of the function at $(k * T) *$ are connected by a line as shown in the illustration.



Trapezoidal rule

Mathematical approach

The general approach (formula (8.1)) applied on the forward rectangle rule, results in an equation u_3:

$$\begin{aligned} u_3(k*T) &= u_3(k*T-T) + T/2*\big(-a*u_3(k*T-T) \\ &\quad + a*e(k*T-T) - a*u_3(k*T) + a*e(k*T)\big) \\ &= \frac{1-(a*T/2)}{1+(a*T/2)}*u_3(k*T-T) \\ &\quad + \frac{a*T/2}{1+(a*T/2)}*\big(e_3(k*T-T)+e_3(k*T)\big) \end{aligned}$$

Trapezoidal rule

Mathematical approach

In this case, the transfer function is:

$$H_T(z) = \frac{a}{\frac{2}{T} * \frac{z-1}{z+1} * a}$$

Which can also be derived using the following substitution in the given transfer function:

$$s \leftarrow \frac{2}{T} * \frac{z-1}{z+1} \quad (8.4)$$

This is extremely usefull while making exercises.

Trapezoidal rule

Example

Given:

$$H(s) = \frac{s+1}{0.1*s+1}$$

We now apply substitution (8.4):

$$H(z) = \frac{(2+T)*(T-2)*z^{-1}}{(0.2+T)+(T-0.2)*z^{-1}}$$

Using T=0.25s, this results in:

$$H(z) = \frac{5*(z-0.7778)}{z+0.1111}$$

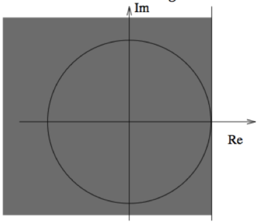
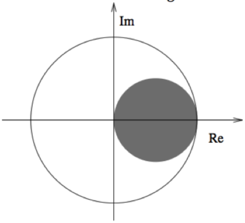
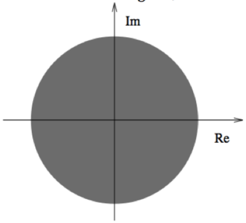
Stability of the numerical integration methods

Stability

As already mentioned, a continuous system is stable when its poles have a negative real part in the s-plane and a discrete system is stable when its poles lie within the unit circle of the z-plane.Subsequently the $(s = j\omega)$-axis is the boundary between poles of stable and unstable continuous systems. Each of the discretization methods can be considered as a map from the s-plane to the z-plane. It is interesting to know how the $j\omega$-axis is mapped by every rule and where the stable part of the s-plane appears in the z-plane. This can be realized by solving formulas (8.2-8.3) to z and replacing s by $j\omega$.

Graphical representation

■ = projection of the left half-plane

Euler	backward rect.	bilinear transf.
$s \longrightarrow \frac{z-1}{T_s}$	$s \longrightarrow \frac{z-1}{zT_s}$	$s \longrightarrow \frac{2}{T_s}\frac{z-1}{z+1}$
		

Bilinear rule with prewarping

Disortion

The bilinear rule maps the stable region of the s-plane into the stable region of the z-plane and the entire $j\omega$-axis is compressed into the 2Π-length of the unit circle, causing a great deal of distortion.

Trapezoid rule with prewarping

By extending the trapezoidal rule one step we can correct the distortion of the real frequencies mapped by the rule. This results in following substitution formula:

$$s \leftarrow \frac{\omega_0}{tan\left(\frac{\omega_0 * T}{2}\right)} * \frac{z-1}{z+1} \quad (8.4)$$

Outline

Zero-pole equivalent

General approach

The map $z = e^{sT}$ is applied to the poles as well as to the zeros of the continuous system. The following rules must be followed:

1. if $s = -a$ is a pole of H(s), then $z = e^{-a*T}$
2. all finite zeros $s = -b$ are mapped by $z = e^{-b*T}$
3. zeros at ∞ are mapped to $z = -1$
4. the gain of the digital filter must match the gain of H(s) at the band center or a similar critical point.

Zero-pole equivalent

Example

Given:

$$H(s) = \frac{s+1}{0.1*s+1}$$

Pole at $s = -10$ and zero at $s = -1$.
New discrete transfer function with equivalent poles and zeros:

$$H(z) = K * \frac{z-e^{-1*T}}{z-e^{-10*T}}$$

K is chosen so that $\mid H(z) \mid_{z=1} = \mid H(s) \mid_{s=0} \rightarrow K = 4.150$
Using $T = 0.25$, this results in:

$$H(z) = 4.150 * \frac{z-0.7788}{z-0.0821}$$

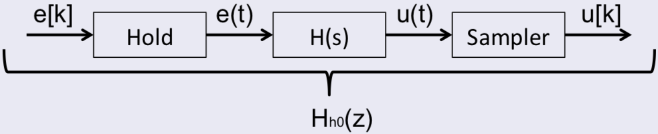
Outline

Hold equivalent

General approach

This method uses a discrete system consisting of 3 subsystems, each with its own purpose.

1. Hold: approximating $e_h(t)$ from the samples $e[k]$
2. H(s): putting the $e_h(t)$ through the given transfer function H(s) of the continuous system, resulting in u(t)
3. Sampler: sampling u(t)



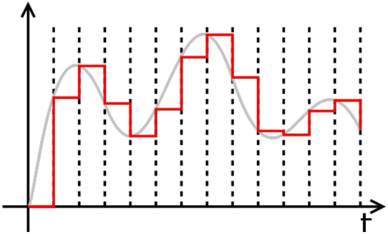
There are many techniques for holding a sequence of samples.

Zero-order hold equivalent (ZOH)

Practical rule

The zero-order hold equivalent transfer function $H_{zoh}(z)$ can be found by computing the following:

$$H_{zoh}(z) = (1 - z^{-1}) * \mathcal{Z}\{\frac{H(s)}{s}\}$$



Zero-order hold equivalent

Example

$$H(s) = \frac{0.1}{s+0.1}$$

Step 1: multiply by 1/s and perform partial fraction expansion

$$\frac{H(s)}{s} = \frac{0.1}{s*(s+0.1)} = \frac{1}{s} - \frac{1}{s+0.1}$$

Step 2: perform z-transformation

$$\mathcal{Z}\left\{\frac{H(s)}{s}\right\} = \frac{1}{1-z^{-1}} - \frac{1}{1-e^{-0.1T}*z^{-1}}$$

Step3: simplify and multiply by $(1 - z^1)$

$$H_{ho}(z) = \frac{1-e^{-0.1T}}{z-e^{0.1T}}$$

Non-causal first-order (= Triangle-hold equivalent (TRI))

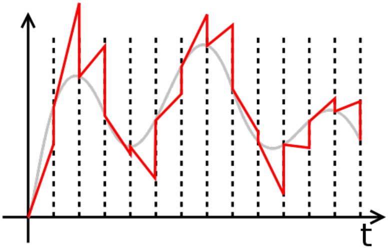
Practical rule

The non-causal first-order hold equivalent transfer function $H_{tri}(z)$ can be found by computing the following:

$$H_{tri}(z) = \frac{(z-1)^2}{T*z} * \mathcal{Z}\left\{\frac{H(s)}{s^2}\right\}$$

Non-causal vs causal

A causal first-order hold equivalent introduces a time-delay resulting in a less accurate approximation.



Triangle-hold equivalent

Example

$$H(s) = \frac{1}{s^2}$$

Step 1: multiply by $1/s^2$ and perform partial fraction expansion

$$H(s) = \frac{1}{s^4}$$

Step 2: perform z-transformation

$$\mathcal{Z}\{\frac{H(s)}{s^2}\} = \frac{T^3}{6} * \frac{(z^2+4*z+1)*z}{(z-1)^4}$$

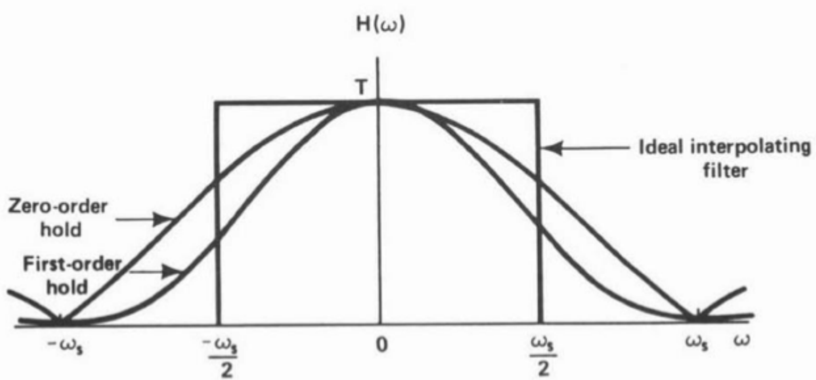
Step 3: simplify and multiply by $\frac{(z-1)^2}{T*z}$

$$H_{tri}(z) = \frac{T^2}{6} * \frac{z^2+4*z+1}{(z-1)^2}$$

Effect of zero- and first-order hold equivalents

Effects on the spectrum

Some information will be permanently lost.



Outline

Sampling time T based on the frequency response

Nyquist-Shannon sampling theorem

If a function $x(t)$ contains no frequencies higher than B hertz, it is completely determined by giving its ordinates at a series of points spaced $1/(2B)$ seconds apart. A sufficient sample-rate is therefore **2B samples/second**. This is called the **"Nyquist sampling rate"**. Equivalently, for a given sample rate f_s, perfect reconstruction is guaranteed possible for a bandlimit $Bf_s/2$.

Practical rule

A higher sampling rate creates a margin of error, a good rule of thumb is **2,2B samples/second**.

Sampling time T based on the time response

Impuls response

If the time response is given, you need to calculate

Outline

Matlab

Matlab Command

Control System Toolbox offers extensive support for discretization and resampling of linear systems:

- "c2d(system,sampling time,method)" used for discretization
- "d2c(system,sampling time,method)" used for reconstruction
- "d2d(system,sampling time,method)" used for resampling

Available methods

- zero-order hold equivalent: "zoh"
- first-order hold equivalent: "foh"
- bilinear: "tustin"
- zero-pole matching period: "matched"

Zero-order hold equivalent

Example

Given:

$H(s) = e^{-s} * \frac{s-2}{s^2+3*s+20}$

sampling frequency = 10Hz

Commands in Matlab:

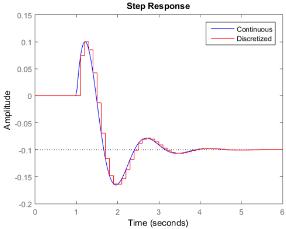
H = tf([1 -2],[1 3 20],'inputdelay',1);

Ts = 0.1;

Hd = c2d(H,Ts,zoh)

Result:

$Hd(z) = z^{-10} * \frac{(0.07462*z-0.09162)}{z^2-1,571*z+0.7408}$



First-order hold equivalent

Example

Given:

$H(s) = e^{-0.3s} * \frac{s-1}{s^2+4*s+5}$

sampling frequency $= 10$Hz

Commands in Matlab:

H = tf([1 -1],[1 4 5],'InputDelay', 0.3);

Hd = c2d(H,0.1,'foh');

Hd = c2d(H,Ts,zoh)

Result: