

## Common Laplace Transforms

$$\begin{aligned}
 \delta(t) &\Longleftrightarrow 1 \\
 \delta^{(n)}(t) &\Longleftrightarrow s^n \\
 u(t) &\Longleftrightarrow \frac{1}{s} \\
 e^{-at} u(t) &\Longleftrightarrow \frac{1}{s+a} \\
 te^{-at} u(t) &\Longleftrightarrow \frac{1}{(s+a)^2} \\
 \frac{t^n}{n!} e^{-at} u(t) &\Longleftrightarrow \frac{1}{(s+a)^{n+1}} \\
 \sin(\omega t) u(t) &\Longleftrightarrow \frac{\omega}{s^2 + \omega^2} \\
 \cos(\omega t) u(t) &\Longleftrightarrow \frac{s}{s^2 + \omega^2} \\
 e^{-at} \sin(\omega t) u(t) &\Longleftrightarrow \frac{\omega}{(s+a)^2 + \omega^2} \\
 e^{-at} \cos(\omega t) u(t) &\Longleftrightarrow \frac{s+a}{(s+a)^2 + \omega^2} \\
 \frac{\omega_n}{\sqrt{1-\zeta^2}} e^{-\zeta\omega_n t} \sin(\omega_n \sqrt{1-\zeta^2} t) u(t) &\Longleftrightarrow \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}
 \end{aligned}$$

## Properties of the Laplace Transform

$$\mathcal{L}\{f(t)\} := \int_{0-}^{\infty} f(t) e^{-st} dt \quad \mathcal{L}^{-1}\{F(s)\} := \frac{1}{2\pi j} \int_{c-j\infty}^{c+j\infty} F(s) e^{st} ds$$

Definition:	$f(t) \Longleftrightarrow F(s)$
Linearity:	$af(t) + bg(t) \Longleftrightarrow aF(s) + bG(s)$
t-scaling	$f(ct) \Longleftrightarrow \frac{1}{ c } F\left(\frac{s}{c}\right)$
t-shifting:	$f(t-t_0)u(t-t_0) \Longleftrightarrow e^{-st_0} F(s)$
s-shifting:	$e^{-s_0 t} f(t) \Longleftrightarrow F(s+s_0)$
Differentiation in $t$ :	$f'(t) \Longleftrightarrow sF(s) - f(0)$ $f''(t) \Longleftrightarrow s^2 F(s) - sf(0) - f'(0)$ $f^{(k)} \Longleftrightarrow s^k F(s) - s^{k-1} f(0) - s^{k-2} f'(0) - \dots - f^{(k-1)}(0)$
Integration in $t$ :	$\int_0^t f(\tau) d\tau \Longleftrightarrow \frac{1}{s} F(s)$
Differentiation in $s$ :	$tf(t) \Longleftrightarrow -F'(s)$
Integration in $s$ :	$\frac{f(t)}{t} \Longleftrightarrow \int_s^{\infty} F(\tilde{s}) d\tilde{s}$
Convolution:	$f(t) * g(t) \Longleftrightarrow F(s)G(s)$ $f(t)g(t) \Longleftrightarrow \frac{1}{2\pi j} F(s) * G(s)$
Periodicity	$f(t) \Longleftrightarrow F_1(s) \times \frac{1}{1-e^{-sp}}$ for $f_1(t)$ one cycle of $f(t)$ with period $p$ .
Initial value theorem:	$f(0^+) = \lim_{s \rightarrow \infty} sF(s)$
Final value theorem:	$\lim_{t \rightarrow \infty} f(t) = \lim_{s \rightarrow 0} sF(s)$

(for  $a, b, t_0, s_0 \in \mathbb{R}, c \in \mathbb{R}_{++}$ ).

## Partial Fractions Expansion

If a partial fraction expansion of  $Y(s)$  includes terms  $\frac{A_m}{(s-a)^m} + \frac{A_{m-1}}{(s-a)^{m-1}} + \dots + \frac{A_1}{s-a}$ , then the coefficients of factors having multiplicity  $m > 1$  are given by the following expressions, where  $k \neq m$ .

$$A_m = \lim_{s \rightarrow a} (s-a)^m Y(s)$$
$$A_k = \frac{1}{(m-k)!} \lim_{s \rightarrow a} \frac{d^{m-k}}{ds^{m-k}} (s-a)^m Y(s)$$

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## Trigonometric Identities

$$\sin(\theta \pm \phi) = \sin \theta \cos \phi \pm \cos \theta \sin \phi \quad \Longrightarrow \quad \begin{cases} \sin(\theta + \frac{\pi}{2}) &= \cos(\theta) \\ \sin(\theta - \frac{\pi}{2}) &= -\cos(\theta) \end{cases}$$
$$\cos(\theta \pm \phi) = \cos \theta \cos \phi \mp \sin \theta \sin \phi \quad \Longrightarrow \quad \begin{cases} \cos(\theta + \frac{\pi}{2}) &= -\sin(\theta) \\ \cos(\theta - \frac{\pi}{2}) &= \sin(\theta) \end{cases}$$
$$\begin{aligned} \sin(2\theta) &= 2 \sin \theta \cos \theta \\ \cos(2\theta) &= \cos^2 \theta - \sin^2 \theta \\ &= 2 \cos^2 \theta - 1 \\ &= 1 - 2 \sin^2 \theta \end{aligned}$$

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## First Order Systems

For a first order system with transfer function  $G(s) = \frac{1}{s + a}$ ,

Rise time (10–90%) is  $t_r = 2.2\tau$

Settling time (to 2%) is  $t_s = 4\tau$

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## Second Order Systems

The following relationships hold for an underdamped second order system having transfer function

$$G(s) = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} \quad .$$

The time taken to reach the peak value is  $t_{\text{peak}} = \frac{\pi}{\omega_n \sqrt{1 - \zeta^2}}$ .

The percentage overshoot is related to damping ratio by

$$\begin{aligned} \%OS &= 100 \times \exp\left(-\frac{\zeta\pi}{\sqrt{1 - \zeta^2}}\right) \\ \Rightarrow \zeta &= \frac{-\ln(\%OS/100)}{\sqrt{\pi^2 + \ln^2(\%OS/100)}} \end{aligned}$$

Settling time (to  $\pm 2\%$ ) is  $t_s = \frac{4}{\zeta\omega_n} = 4\tau$ .

Phase margin -  $\zeta$  relation.

$$\begin{aligned} \text{PM} &= \arctan \frac{2\zeta}{\sqrt{-2\zeta^2 + \sqrt{1 + 4\zeta^4}}} \\ &\approx 100\zeta \quad \text{for } \zeta \leq 0.6 \end{aligned}$$

The frequency response has a peak magnitude of  $M_p = \frac{1}{2\zeta\sqrt{1 - \zeta^2}}$ , at  $\omega_p = \omega_n\sqrt{1 - 2\zeta^2}$ .

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## Steady State Errors

The following hold for a unity-gain, negative-feedback system with transfer function  $G(s)$ .

$$\begin{aligned}e_{\text{step}}(\infty) &= \frac{1}{1 + K_p} := \frac{1}{1 + \lim_{s \rightarrow 0} G(s)} \\e_{\text{ramp}}(\infty) &= \frac{1}{K_v} := \frac{1}{\lim_{s \rightarrow 0} sG(s)} \\e_{\text{parabola}}(\infty) &= \frac{1}{K_a} := \frac{1}{\lim_{s \rightarrow 0} s^2 G(s)}\end{aligned}$$

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## Compensator Topologies

Proportional Compensator

$$C(s) = K_p$$

Proportional-Integral (PI) Compensator

$$C(s) = K_p \frac{s + \omega_b}{s} \equiv K_p \frac{\frac{s}{\omega_b} + 1}{\frac{s}{\omega_b}}$$

Lag Compensator

$$C(s) = K_p \frac{s + \omega_b}{s + \frac{\omega_b}{\alpha}} \equiv K_p \alpha \frac{\frac{s}{\omega_b} + 1}{\frac{\alpha s}{\omega_b} + 1}, \quad \text{where } \alpha > 1.$$

Proportional-Derivative (PD) Compensator

$$C(s) = K_p \left( \frac{s}{\omega_b} + 1 \right)$$

Lead Compensator

$$C(s) = \frac{K_p}{\alpha} \frac{s + \omega_b}{s + \frac{\omega_b}{\alpha}} \equiv K_p \frac{\frac{s}{\omega_b} + 1}{\frac{\alpha s}{\omega_b} + 1}, \quad \text{where } \alpha < 1.$$

The maximum phase lead of  $\phi_{\max} = \arcsin\left(\frac{1 - \alpha}{1 + \alpha}\right)$  occurs at a frequency  $\omega = \frac{\omega_b}{\sqrt{\alpha}}$ . Consequently,

$$\alpha = \frac{1 - \sin(\phi_{\max})}{1 + \sin(\phi_{\max})}$$