Introduction

- We have already discussed the affect of location of poles and zeros on the transient response of 1st order systems.

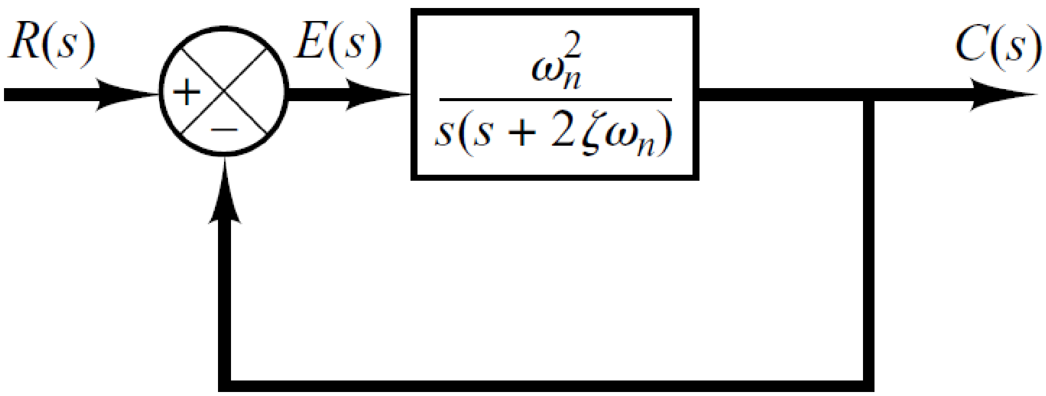
- Compared to the simplicity of a first-order system, a second-order system exhibits a wide range of responses that must be analyzed and described.

- Varying a first-order system's parameter (T, K) simply changes the speed and offset of the response
- Whereas, changes in the parameters of a second-order system can change the *form of* the response.

- A second-order system can display characteristics much like a first-order system or, depending on component values, display damped or *pure oscillations* for its *transient response*.

Introduction

- A general second-order system is characterized by the following transfer function.



$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

Introduction

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

$\omega_n \longrightarrow$ un-damped natural frequency of the second order system, which is the frequency of oscillation of the system without damping.

$\zeta \longrightarrow$ damping ratio of the second order system, which is a measure of the degree of resistance to change in the system output.

Example#1

- Determine the un-damped natural frequency and damping ratio of the following second order system.

$$\frac{C(s)}{R(s)} = \frac{4}{s^2 + 2s + 4}$$

- Compare the numerator and denominator of the given transfer function with the general 2nd order transfer function.

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

$$\omega_n^2 = 4 \quad \Rightarrow \omega_n = 2\ rad/\sec$$

$$\cancel{s^2} + 2\zeta\omega_n s + \cancel{\omega_n^2} = \cancel{s^2} + 2s + \cancel{4}$$

$$\Rightarrow 2\zeta\omega_n s = 2s$$

$$\Rightarrow \zeta\omega_n = 1$$

$$\Rightarrow \zeta = 0.5$$

Introduction

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

- Two poles of the system are

$$-\omega_n\zeta + \omega_n\sqrt{\zeta^2 - 1}$$

$$-\omega_n\zeta - \omega_n\sqrt{\zeta^2 - 1}$$

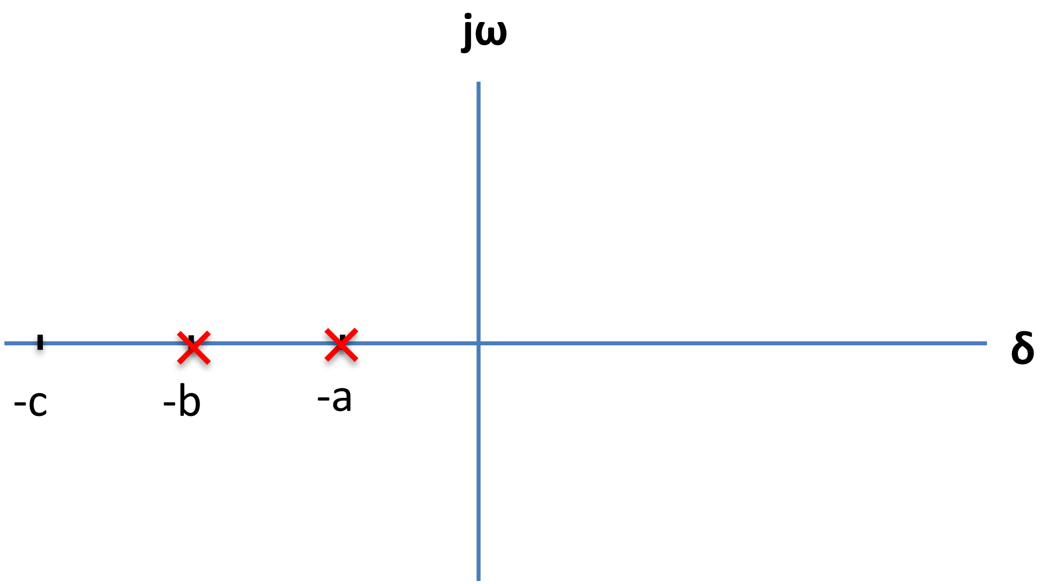
Introduction

$$-\omega_n\zeta + \omega_n\sqrt{\zeta^2 - 1}$$

$$-\omega_n\zeta - \omega_n\sqrt{\zeta^2 - 1}$$

- According the value of ζ , a second-order system can be set into one of the four categories:

  1. Overdamped - when the system has two real distinct poles (ζ >1).



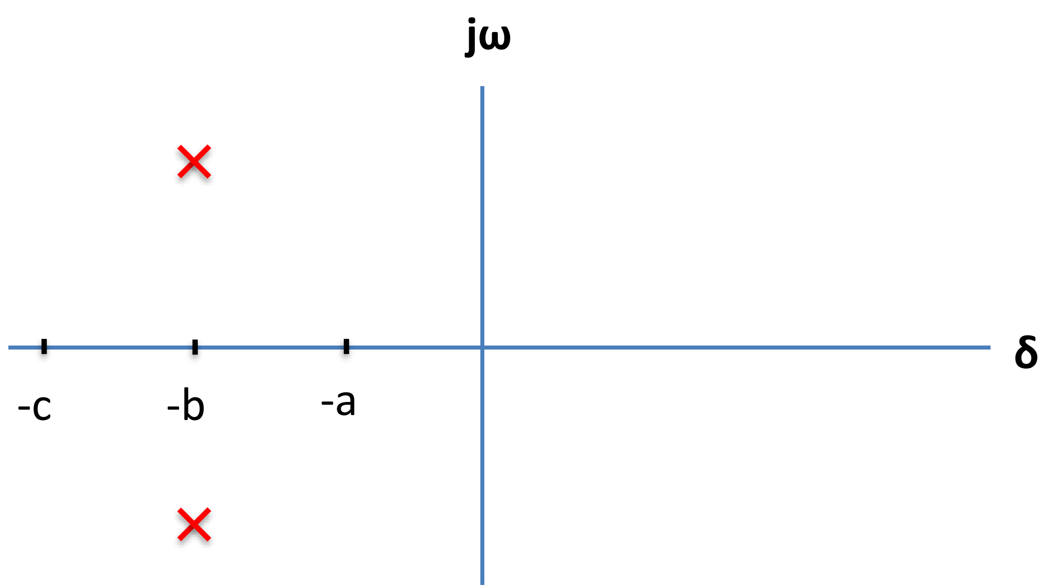
Introduction

$$-\omega_n\zeta + \omega_n\sqrt{\zeta^2 - 1}$$

$$-\omega_n\zeta - \omega_n\sqrt{\zeta^2 - 1}$$

- According the value of ζ , a second-order system can be set into one of the four categories:

2. *Underdamped* - when the system has two complex conjugate poles (0 <ζ <1)



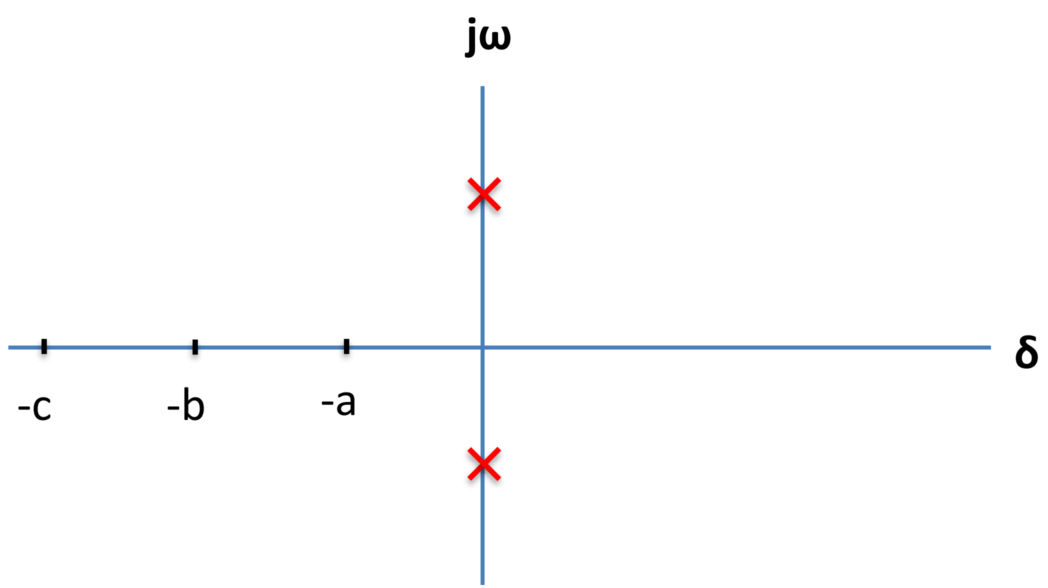
Introduction

$$-\omega_n\zeta+\omega_n\sqrt{\zeta^2-1}$$

$$-\omega_n\zeta-\omega_n\sqrt{\zeta^2-1}$$

- According the value of ζ, a second-order system can be set into one of the four categories:

3. *Undamped* - when the system has two imaginary poles (ζ = 0).

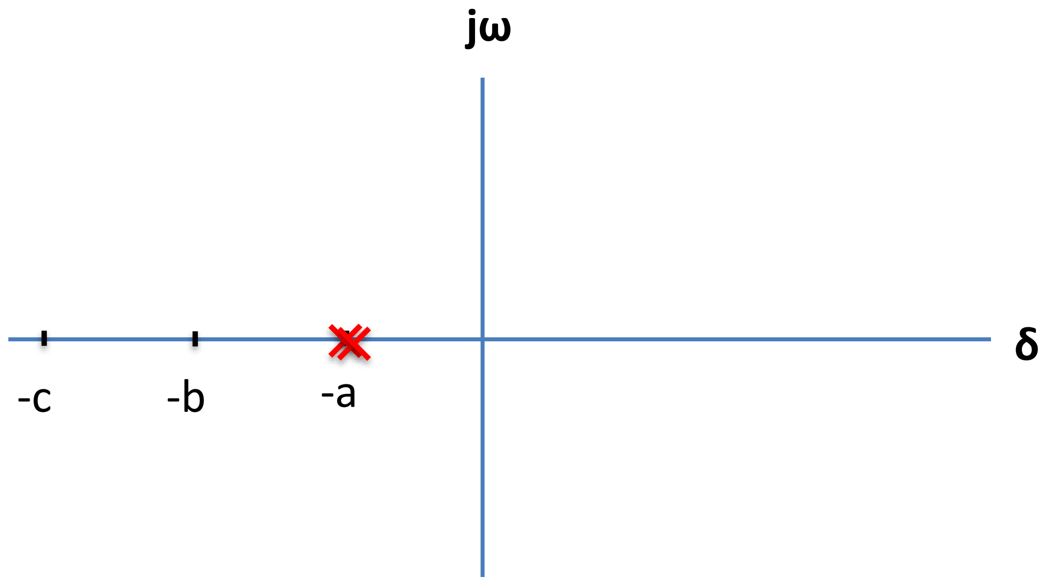


Introduction

$$-\omega_n\zeta + \omega_n\sqrt{\zeta^2 - 1}$$
$$-\omega_n\zeta - \omega_n\sqrt{\zeta^2 - 1}$$

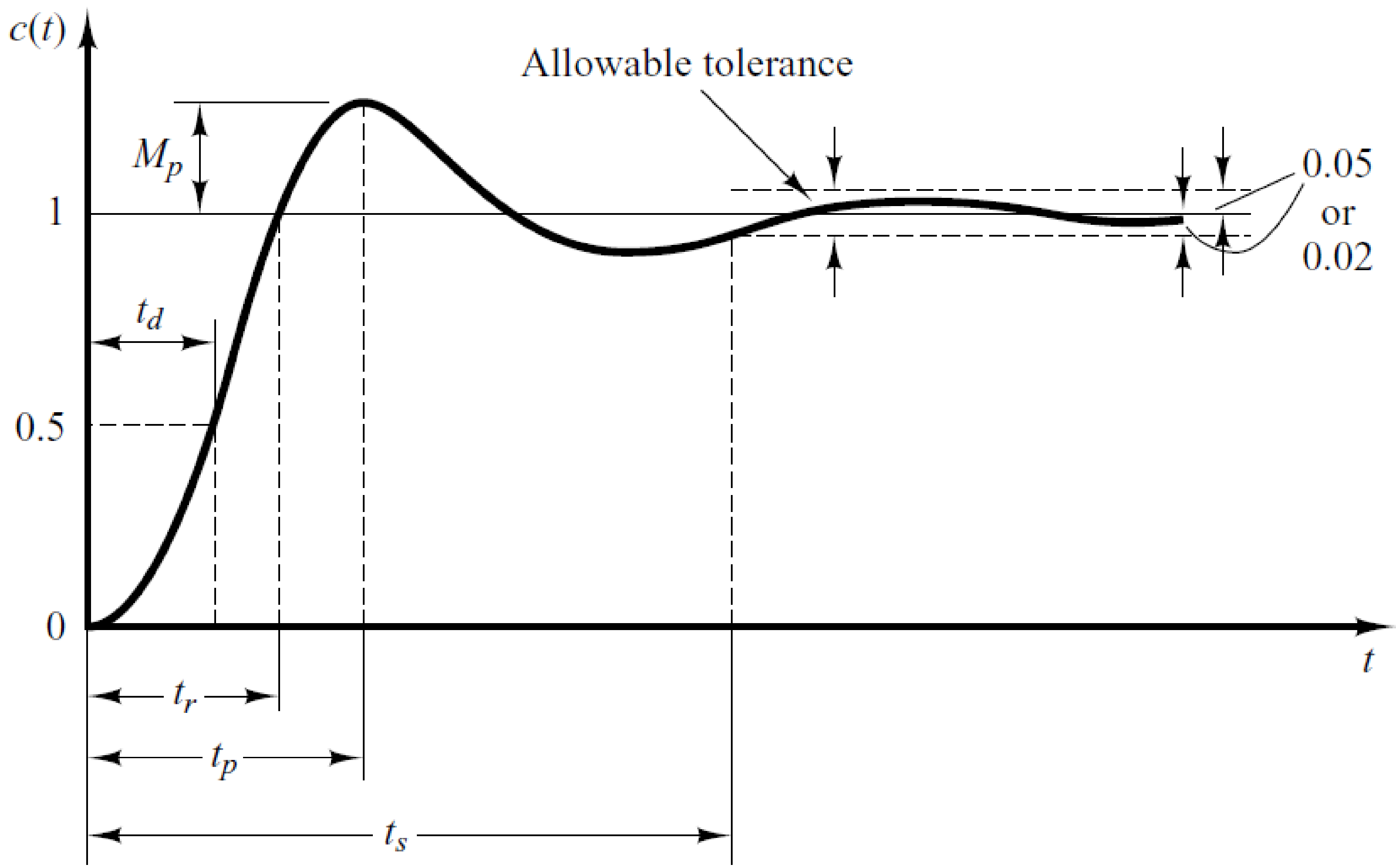
- According the value of ζ , a second-order system can be set into one of the four categories:

4. *Critically damped* - when the system has two real but equal poles (ζ = 1).



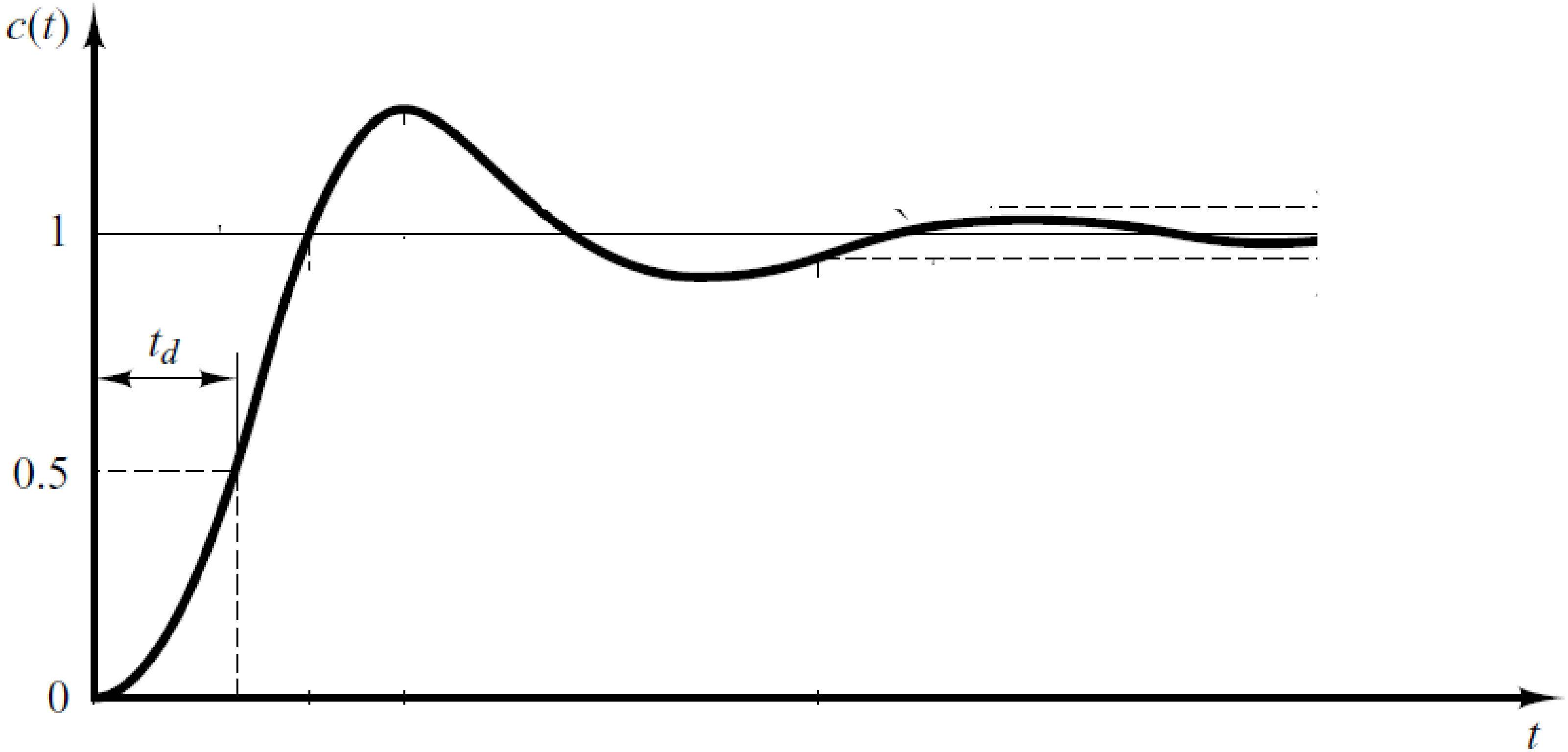
Time-Domain Specification

For $0<\zeta<1$ and $\omega_n > 0$, the 2nd order system's response due to a unit step input looks like



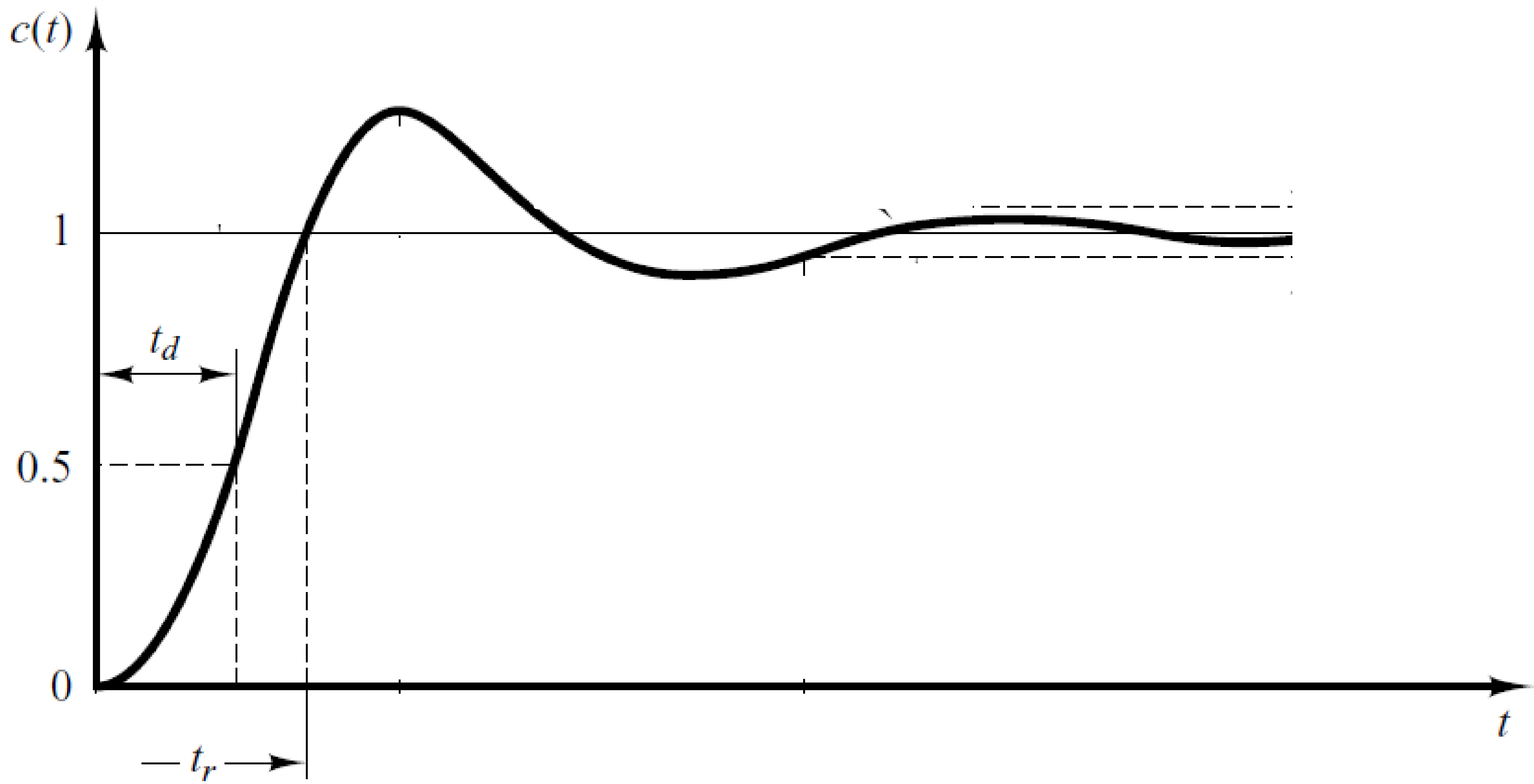
Time-Domain Specification

- The delay (t_d) time is the time required for the response to reach half the final value the very first time.



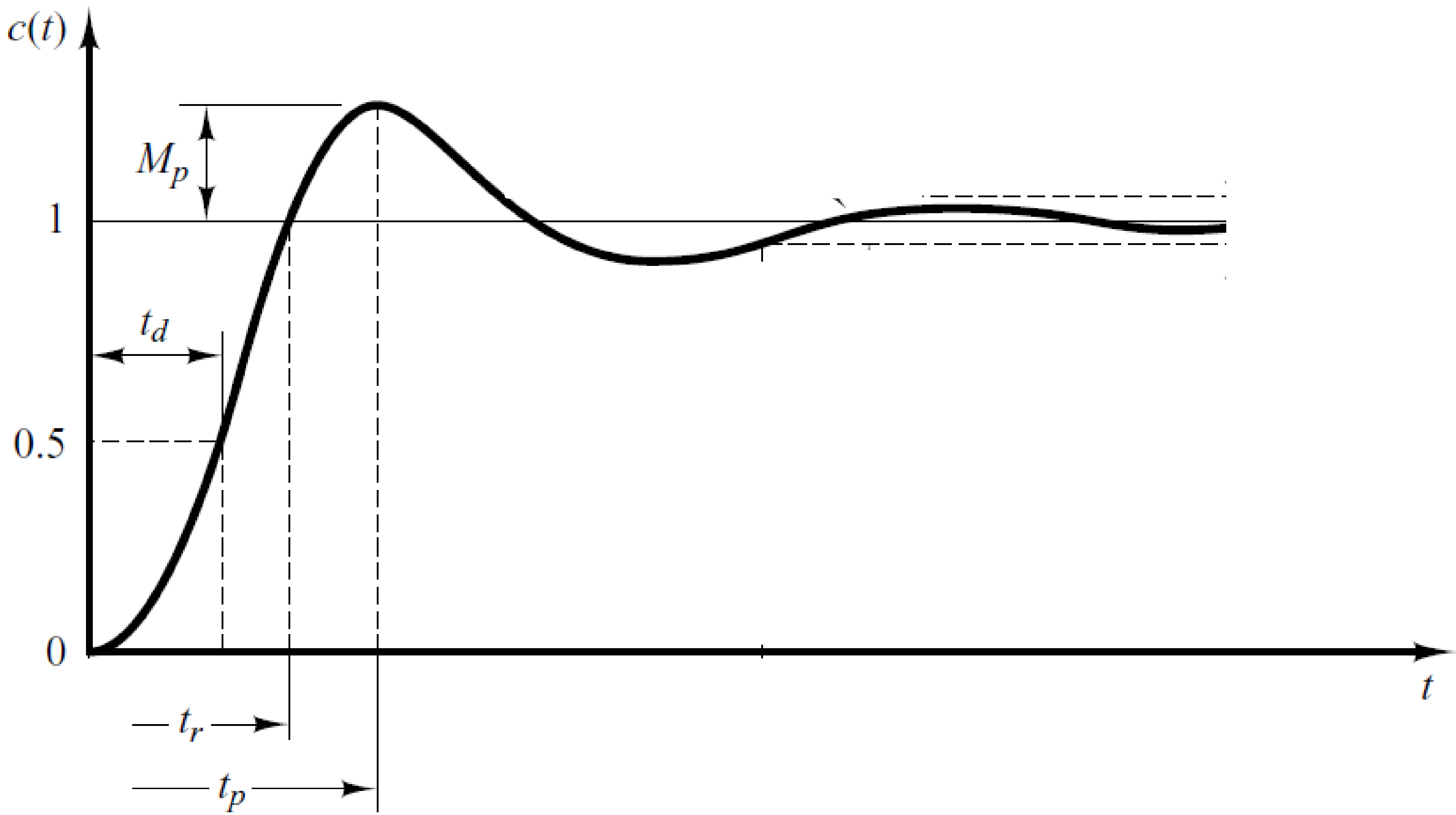
Time-Domain Specification

- The rise time is the time required for the response to rise from 10% to 90%, 5% to 95%, or 0% to 100% of its final value.
- For underdamped second order systems, the 0% to 100% rise time is normally used. For overdamped systems, the 10% to 90% rise time is commonly used.



Time-Domain Specification

- The peak time is the time required for the response to reach the first peak of the overshoot.



Time-Domain Specification

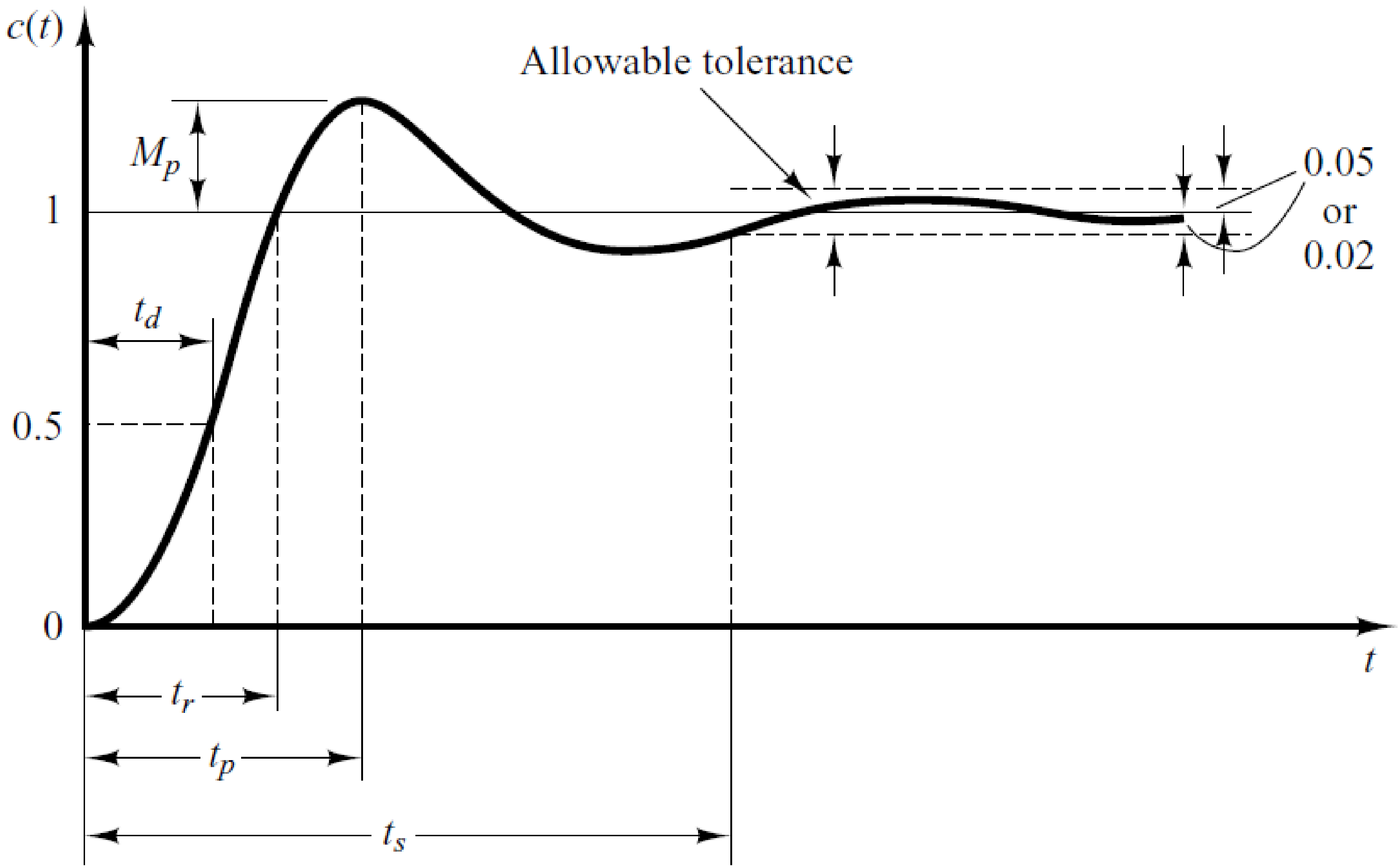
The maximum overshoot is the maximum peak value of the response curve measured from unity. If the final steady-state value of the response differs from unity, then it is common to use the maximum percent overshoot. It is defined by

$$\text{Maximum percent overshoot} = \frac{c(t_p) - c(\infty)}{c(\infty)} \times 100\%$$

The amount of the maximum (percent) overshoot directly indicates the relative stability of the system.

Time-Domain Specification

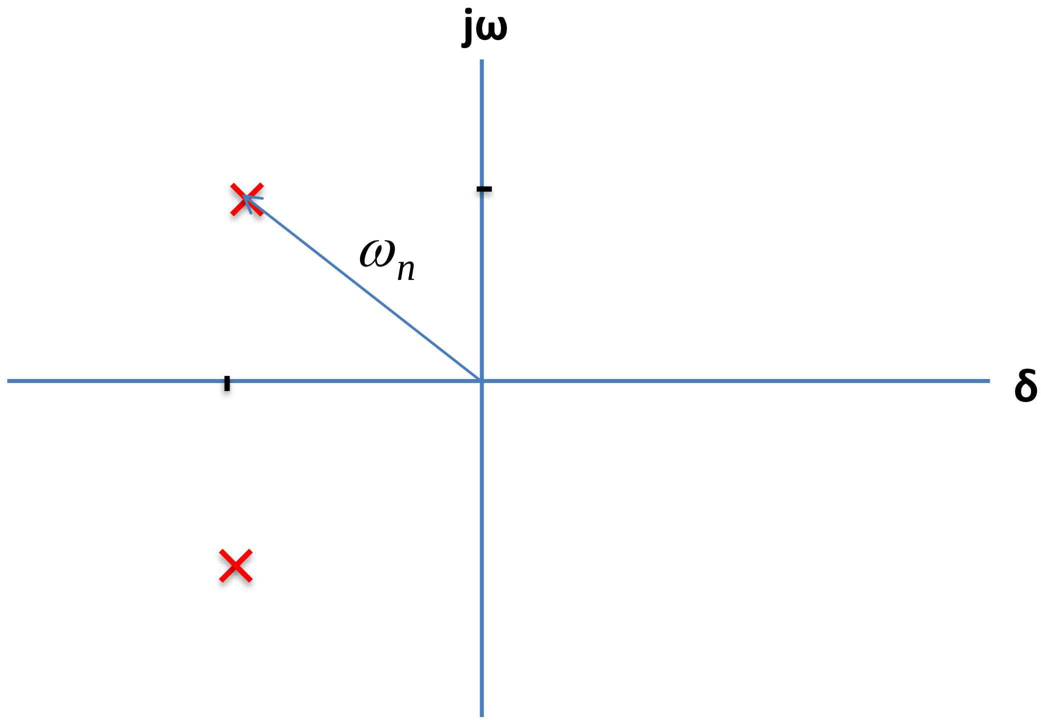
- The settling time is the time required for the response curve to reach and stay within a range about the final value of size specified by absolute percentage of the final value (usually 2% or 5%).



S-Plane

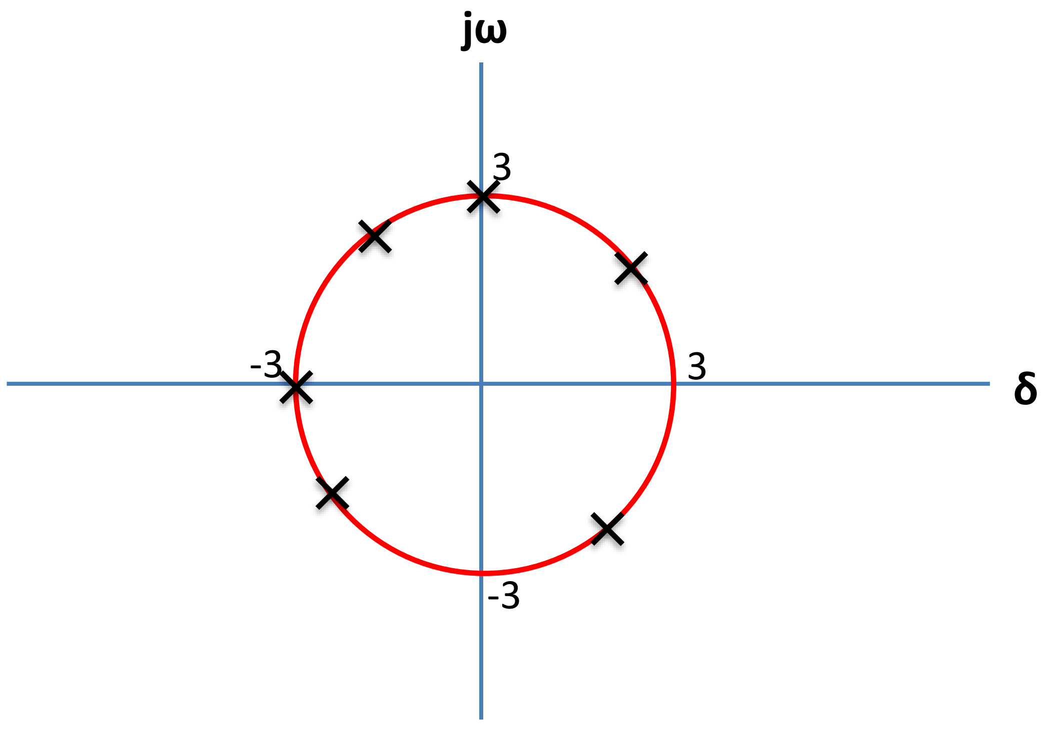
- Natural Undamped Frequency.

- Distance from the origin of s-plane to pole is natural undamped frequency in rad/sec.



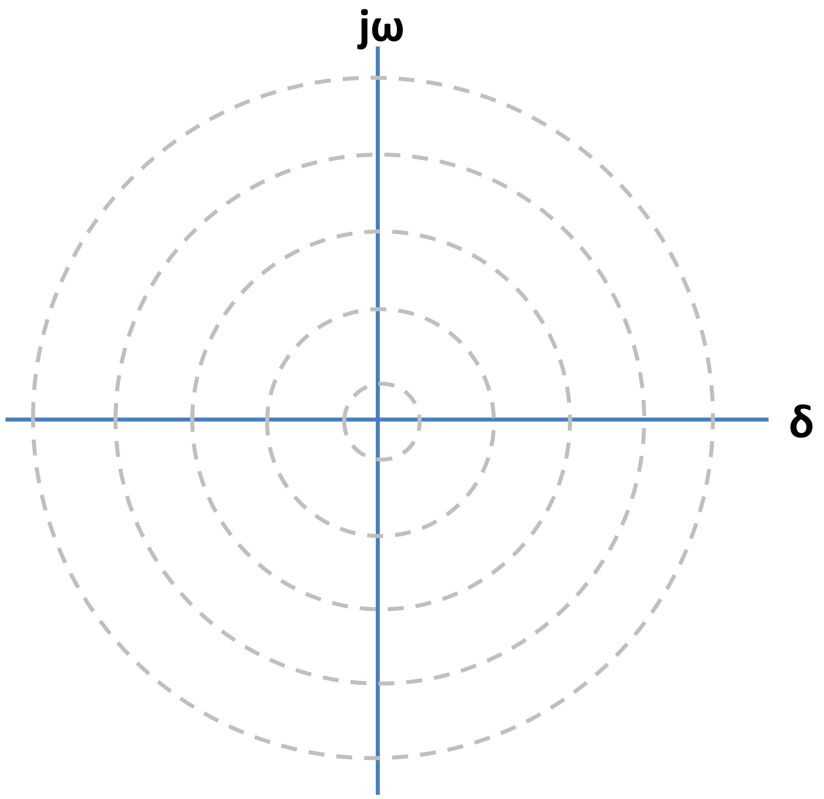
S-Plane

- Let us draw a circle of radius 3 in s-plane.
- If a pole is located anywhere on the circumference of the circle the natural undamped frequency would be *3 rad/sec*.



S-Plane

- Therefore the s-plane is divided into Constant Natural Undamped Frequency (**ω_n**) Circles.

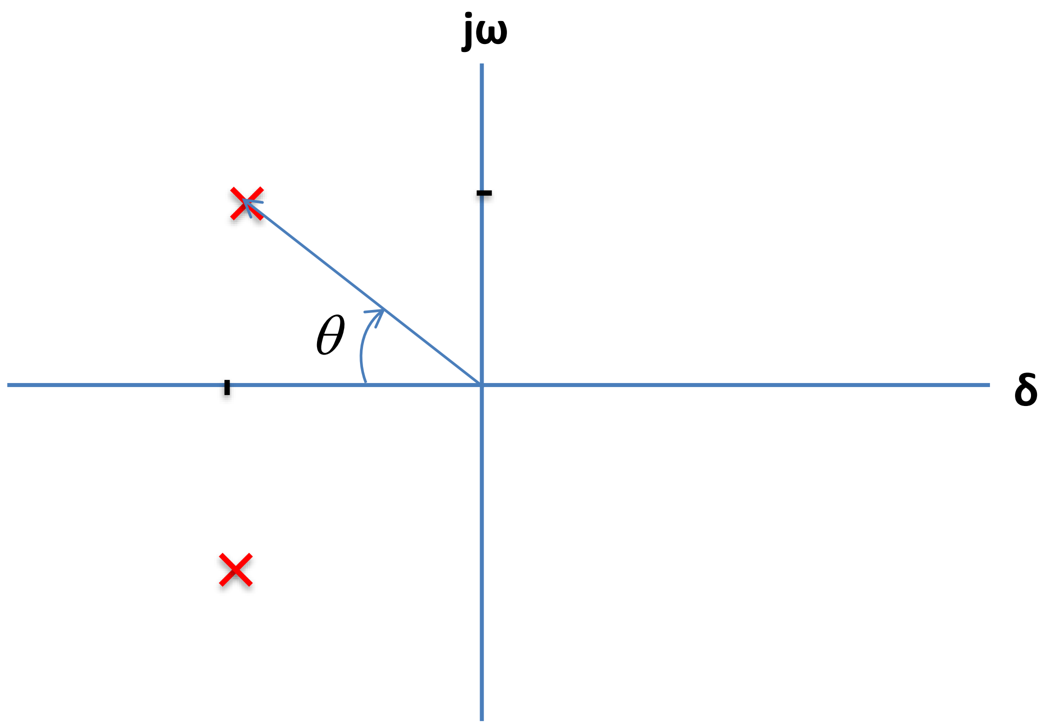


S-Plane

- Damping ratio.

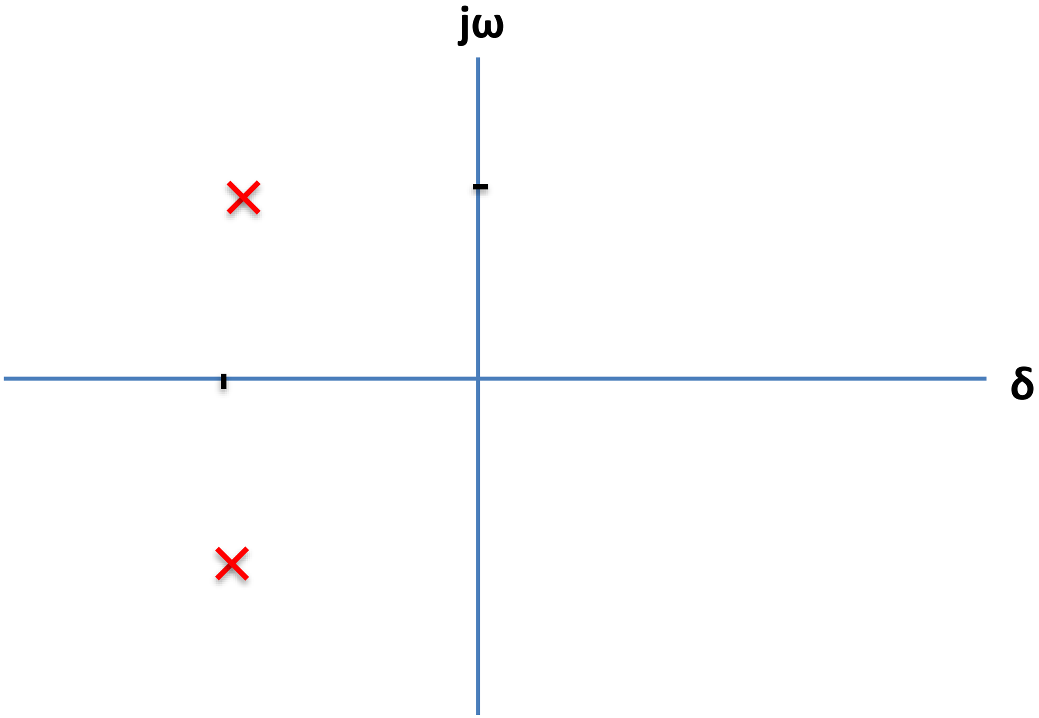
- Cosine of the angle between vector connecting origin and pole and –ve real axis yields damping ratio.

$$\zeta = \cos\theta$$



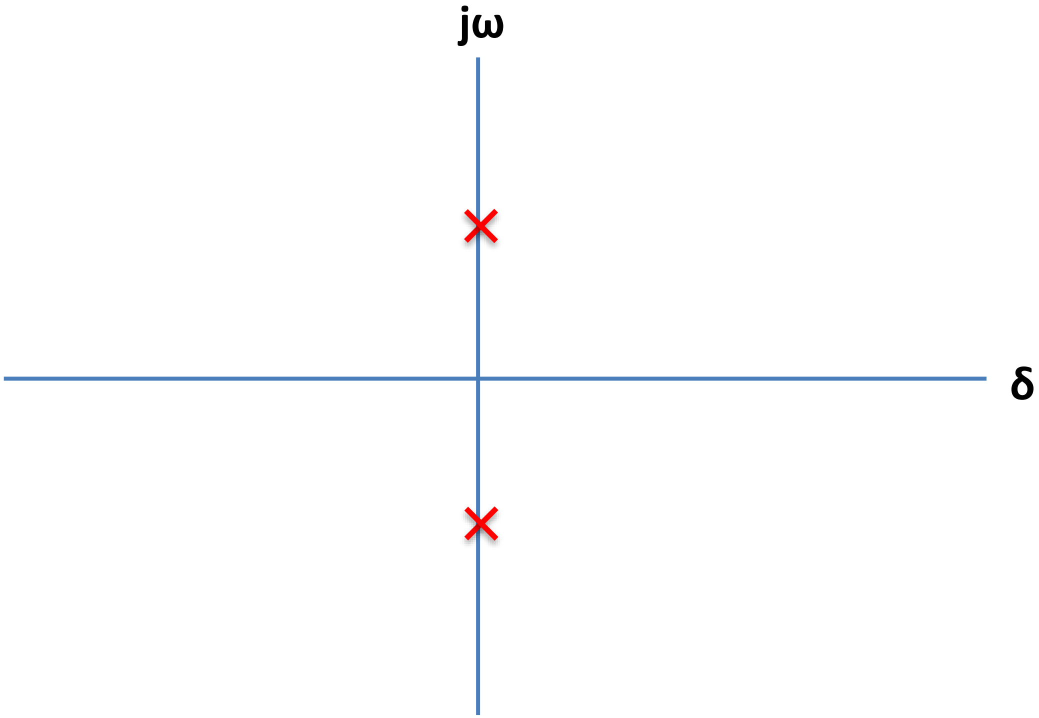
S-Plane

- For Underdamped system $0^\circ < \theta < 90^\circ$ therefore, $0 < \zeta < 1$



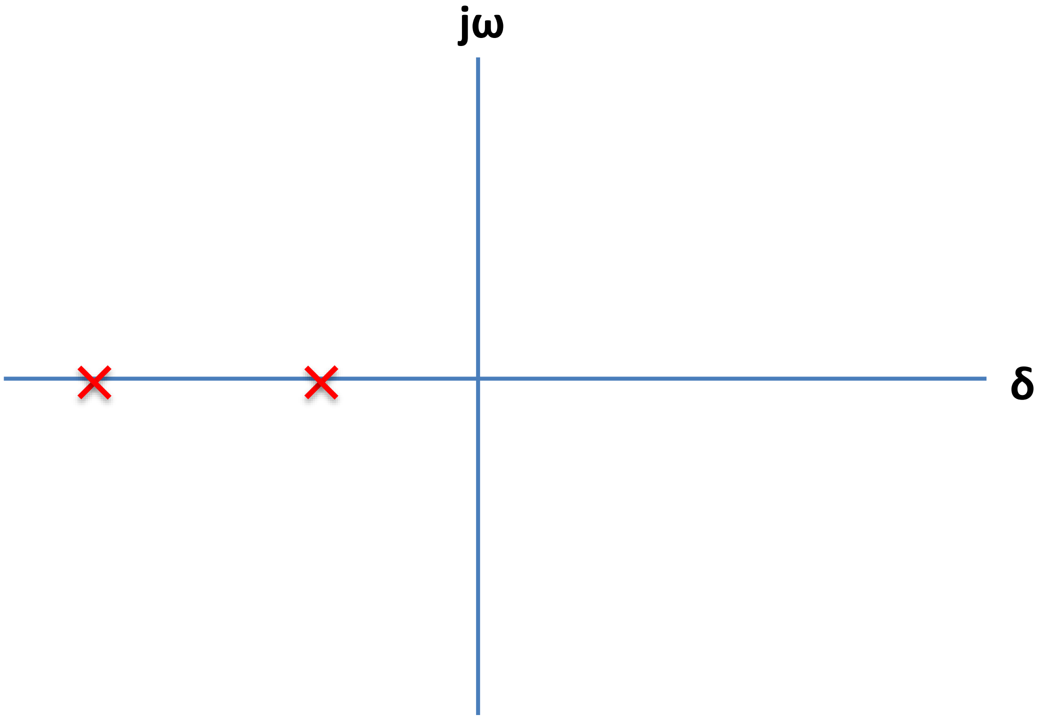
S-Plane

- For Undamped system $\theta = 90^\circ$ therefore, $\zeta = 0$



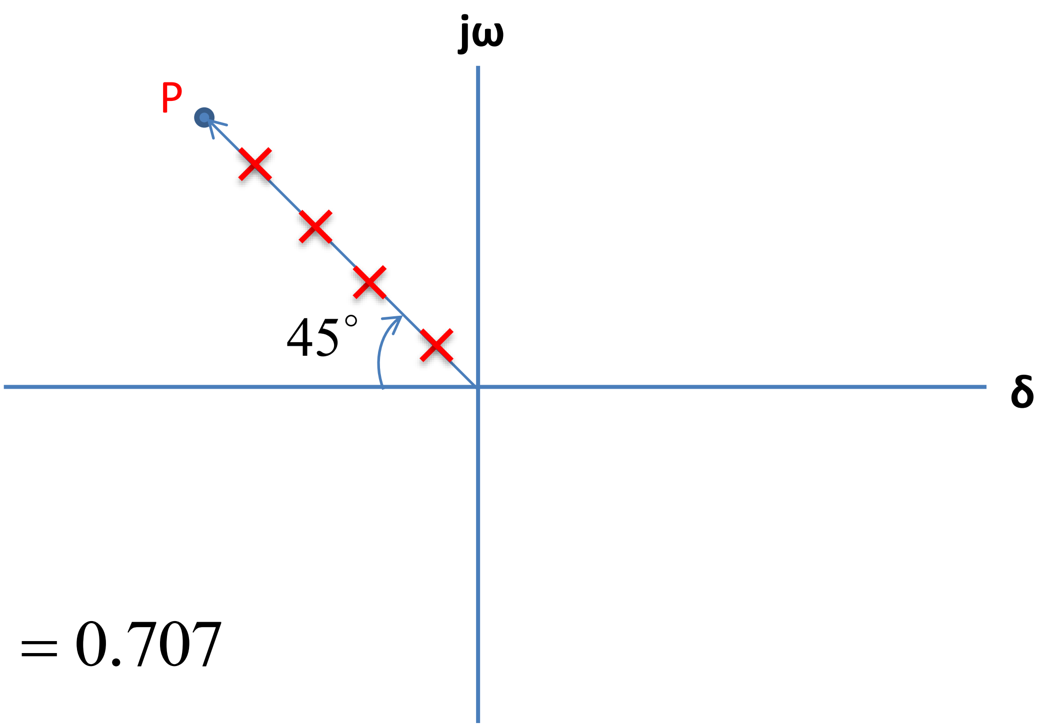
S-Plane

- For overdamped and critically damped systems $\theta = 0^{\circ}$ therefore, $\zeta \geq 0$



S-Plane

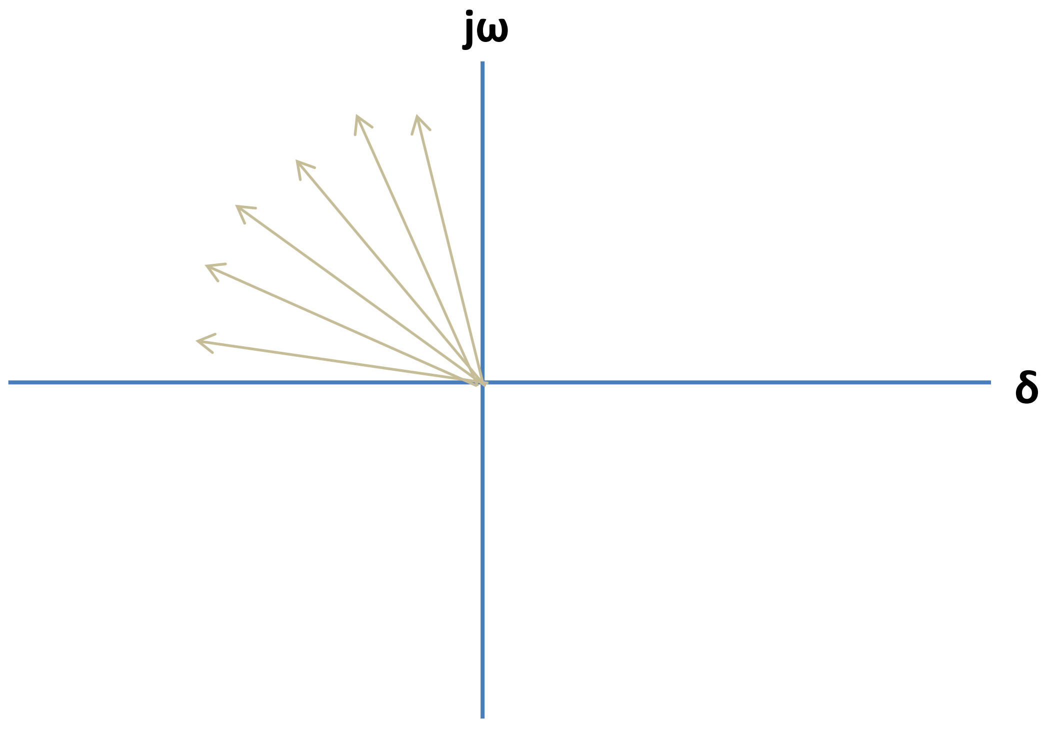
- Draw a vector connecting origin of s-plane and some point P.



$$\zeta = \cos 45^\circ = 0.707$$

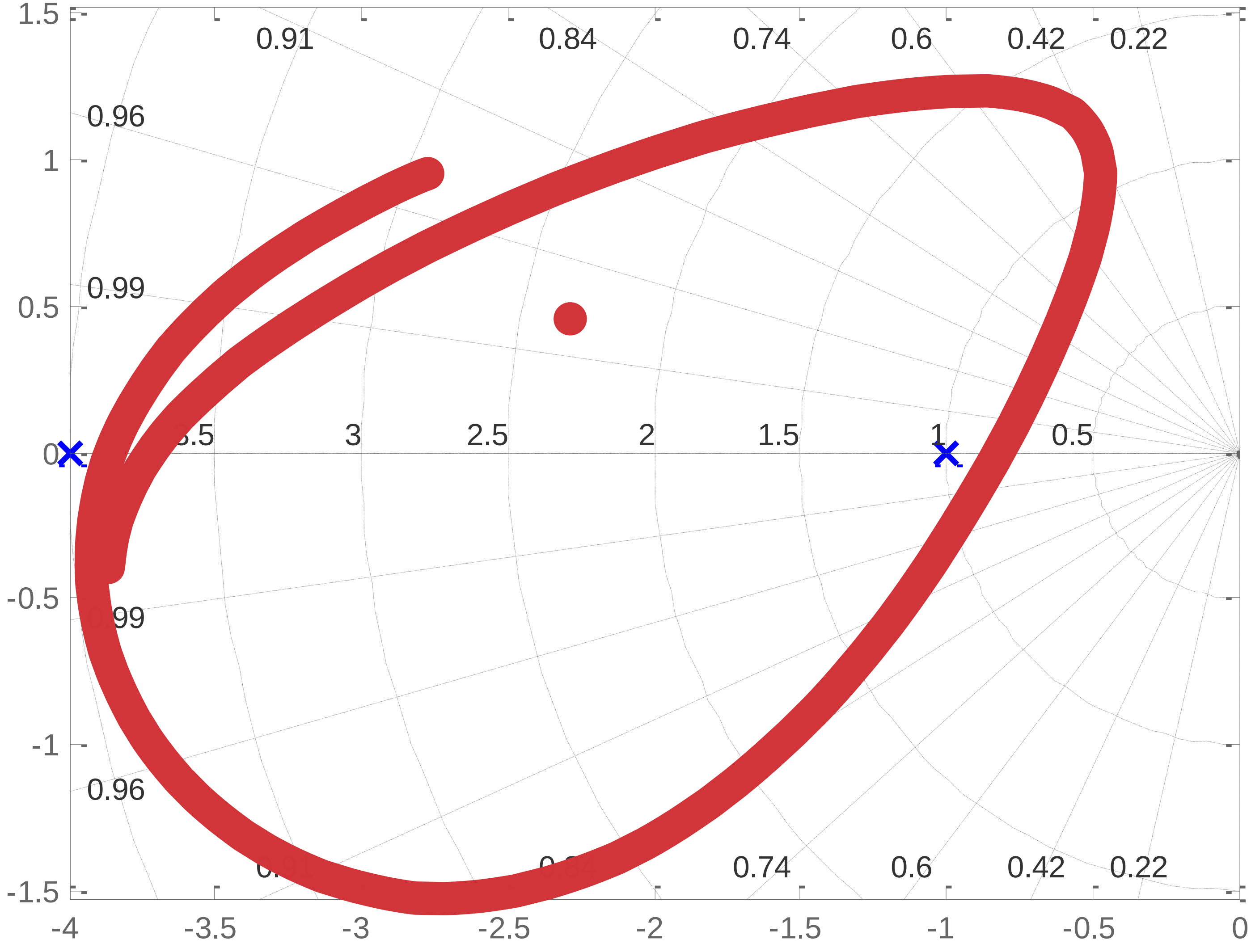
S-Plane

- Therefore, s-plane is divided into sections of constant damping ratio lines.



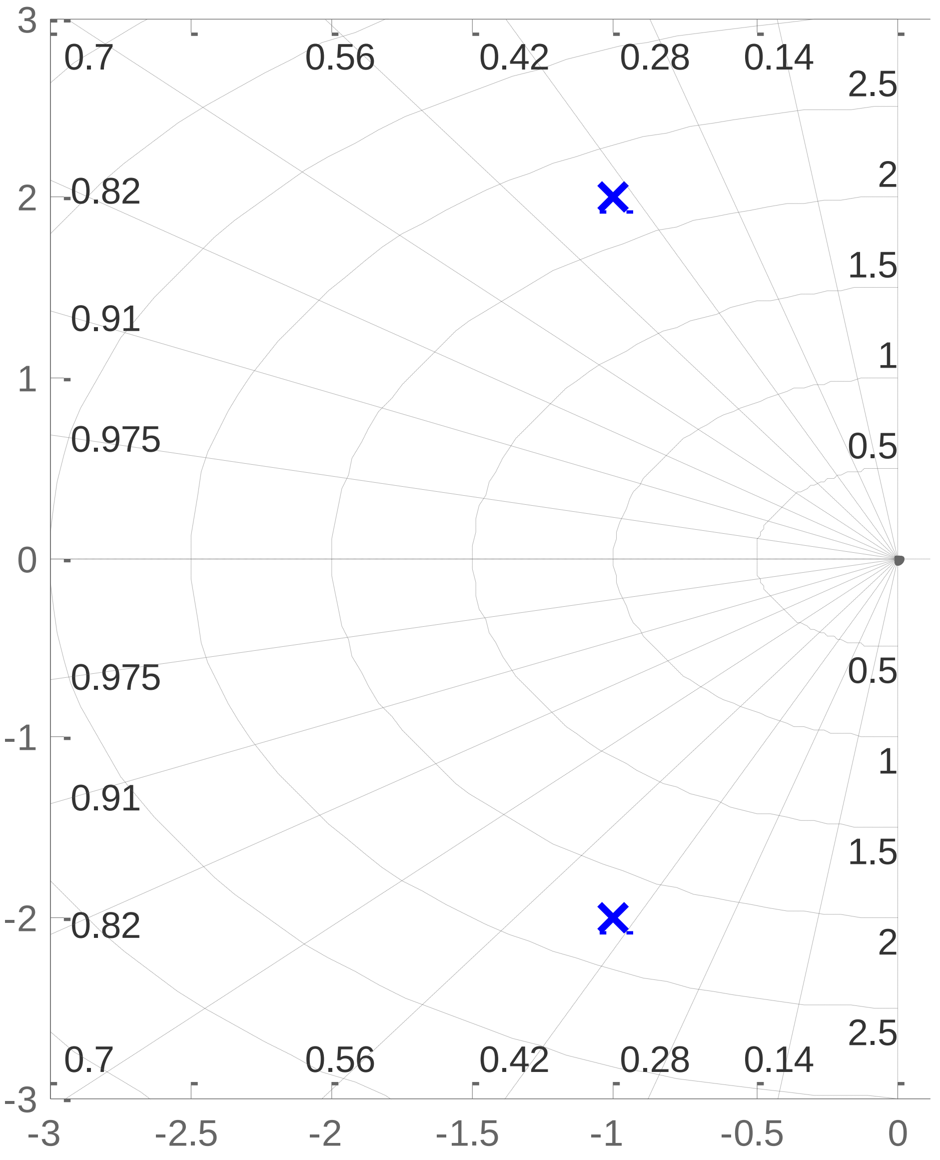
Example-2

- Determine the natural frequency and damping ratio of the poles from the following pz-map.



Example-3

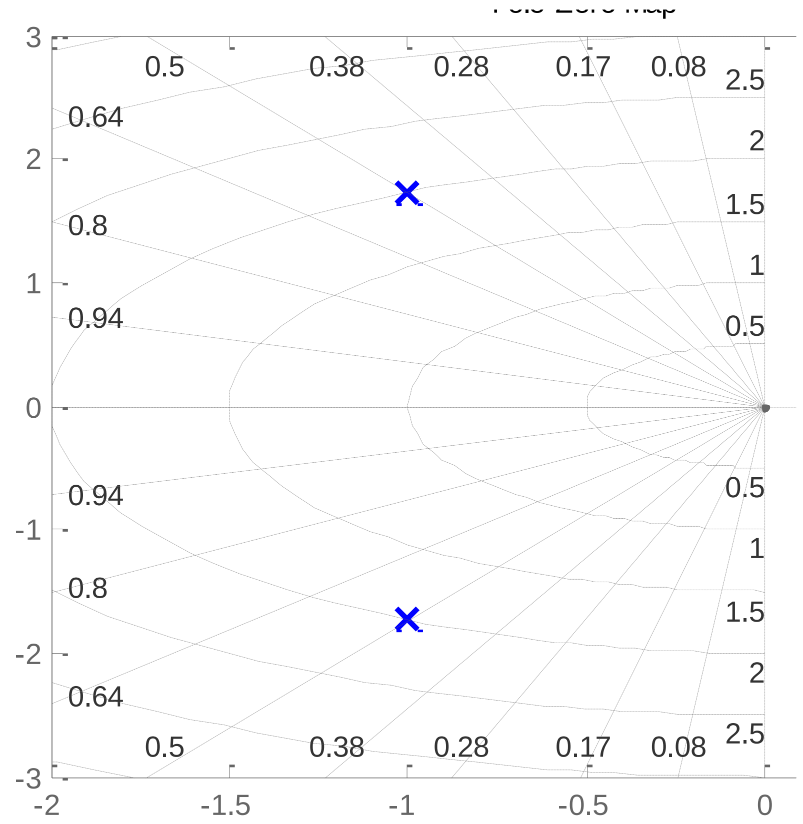
- Determine the natural frequency and damping ratio of the poles from the given pz-map.
- Also determine the transfer function of the system and state whether system is underdamped, overdamped, undamped or critically damped.



Example-4

- The natural frequency of closed loop poles of 2nd order system is 2 rad/sec and damping ratio is 0.5.

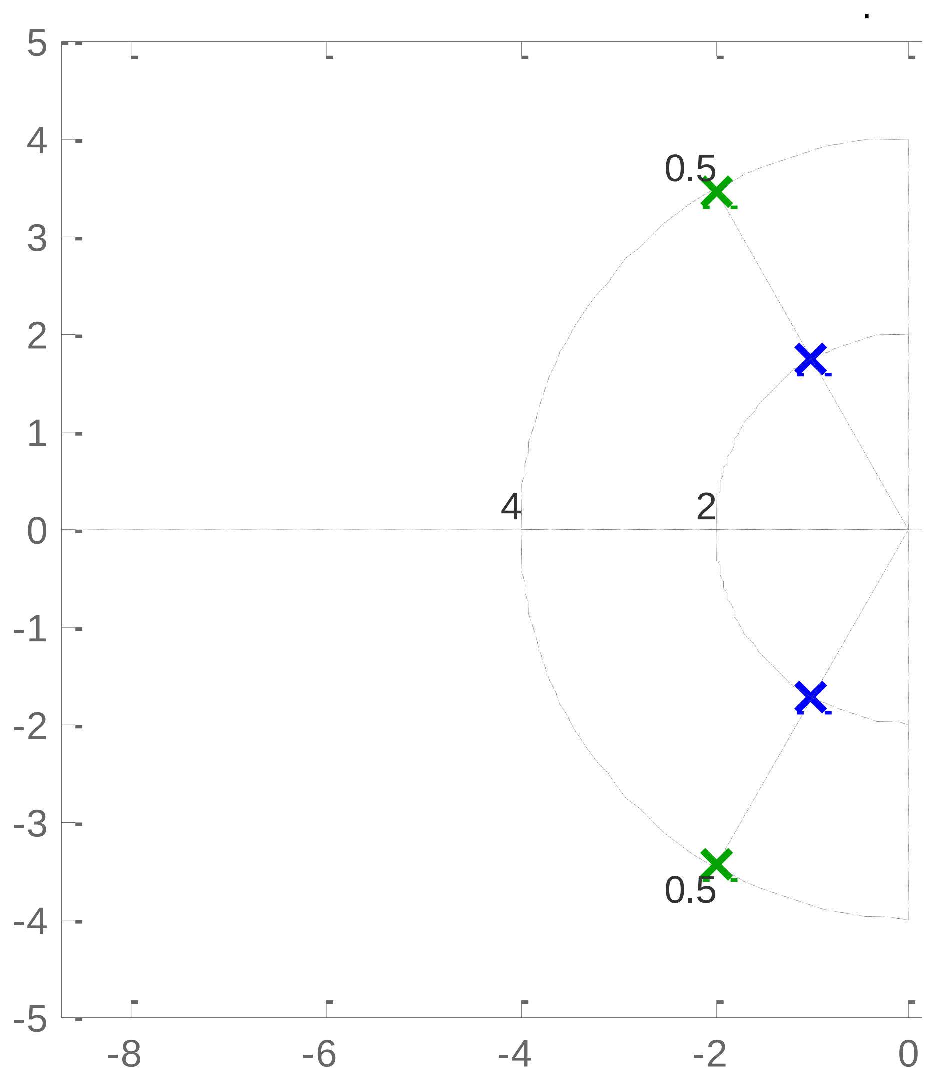
- Determine the location of closed loop poles so that the damping ratio remains same but the natural undamped frequency is doubled.



$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} = \frac{4}{s^2 + 2s + 4}$$

Example-4

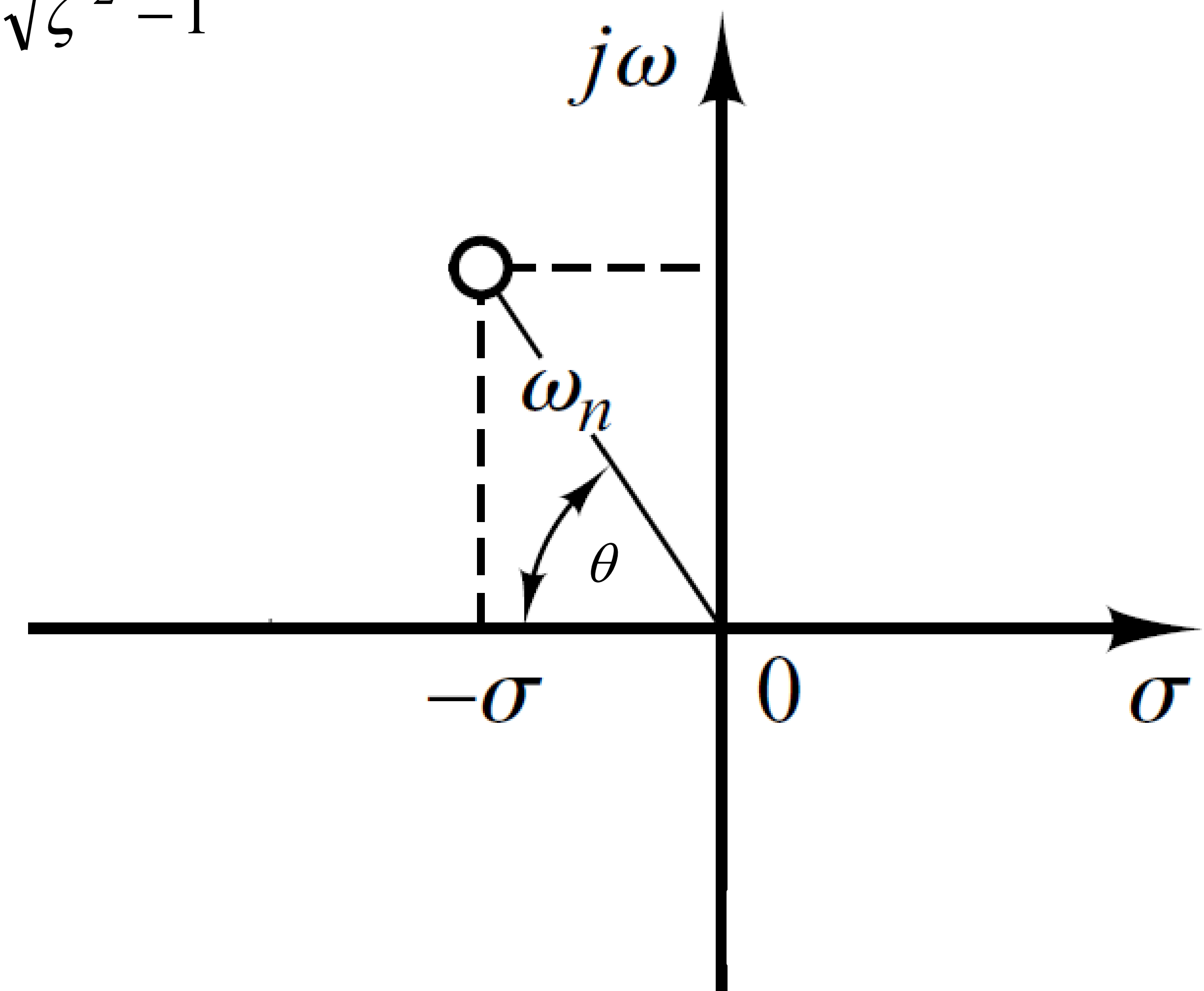
Determine the location of closed loop poles so that the damping ratio remains same but the natural undamped frequency is doubled.



S-Plane

$$-\omega_n\zeta + \omega_n\sqrt{\zeta^2 - 1}$$

$$-\omega_n\zeta - \omega_n\sqrt{\zeta^2 - 1}$$



Step Response of underdamped System

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} \xrightarrow{\text{Step Response}} C(s) = \frac{\omega_n^2}{s\left(s^2 + 2\zeta\omega_n s + \omega_n^2\right)}$$

- The partial fraction expansion of above equation is given as

$$C(s) = \frac{1}{s} - \frac{s + 2\zeta\omega_n}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

$$\omega_n^2\left(1 - \zeta^2\right)$$

$$C(s) = \frac{1}{s} - \frac{s + 2\zeta\omega_n}{s^2 + 2\zeta\omega_n s + \zeta^2\omega_n^2 + \omega_n^2 - \zeta^2\omega_n^2}$$

$$\left(s + 2\zeta\omega_n\right)^2$$

$$C(s) = \frac{1}{s} - \frac{s + 2\zeta\omega_n}{\left(s + \zeta\omega_n\right)^2 + \omega_n^2\left(1 - \zeta^2\right)}$$

Step Response of underdamped System

$$C(s) = \frac{1}{s} - \frac{s + 2\zeta\omega_n}{(s + \zeta\omega_n)^2 + \omega_n^2(1 - \zeta^2)}$$

- Above equation can be written as

$$C(s) = \frac{1}{s} - \frac{s + 2\zeta\omega_n}{(s + \zeta\omega_n)^2 + \omega_d^2}$$

- Where $\omega_d = \omega_n\sqrt{1 - \zeta^2}$, is the frequency of transient oscillations and is called damped natural frequency.

- The inverse Laplace transform of above equation can be obtained easily if C(s) is written in the following form:

$$C(s) = \frac{1}{s} - \frac{s + \zeta\omega_n}{(s + \zeta\omega_n)^2 + \omega_d^2} - \frac{\zeta\omega_n}{(s + \zeta\omega_n)^2 + \omega_d^2}$$

Step Response of underdamped System

$$C(s)=\frac{1}{s}-\frac{s+\zeta\omega_n}{(s+\zeta\omega_n)^2+\omega_d^2}-\frac{\zeta\omega_n}{(s+\zeta\omega_n)^2+\omega_d^2}$$

$$C(s)=\frac{1}{s}-\frac{s+\zeta\omega_n}{(s+\zeta\omega_n)^2+\omega_d^2}-\frac{\frac{\zeta}{\sqrt{1-\zeta^2}}\omega_n\sqrt{1-\zeta^2}}{(s+\zeta\omega_n)^2+\omega_d^2}$$

$$C(s)=\frac{1}{s}-\frac{s+\zeta\omega_n}{(s+\zeta\omega_n)^2+\omega_d^2}-\frac{\zeta}{\sqrt{1-\zeta^2}}\frac{\omega_d}{(s+\zeta\omega_n)^2+\omega_d^2}$$

$$c(t)=1-e^{-\zeta\omega_n t}\cos\omega_d t-\frac{\zeta}{\sqrt{1-\zeta^2}}e^{-\zeta\omega_n t}\sin\omega_d t$$

Step Response of underdamped System

$$c(t) = 1 - e^{-\zeta\omega_n t}\cos\omega_d t - \frac{\zeta}{\sqrt{1-\zeta^2}} e^{-\zeta\omega_n t}\sin\omega_d t$$

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

- When $\zeta = 0$

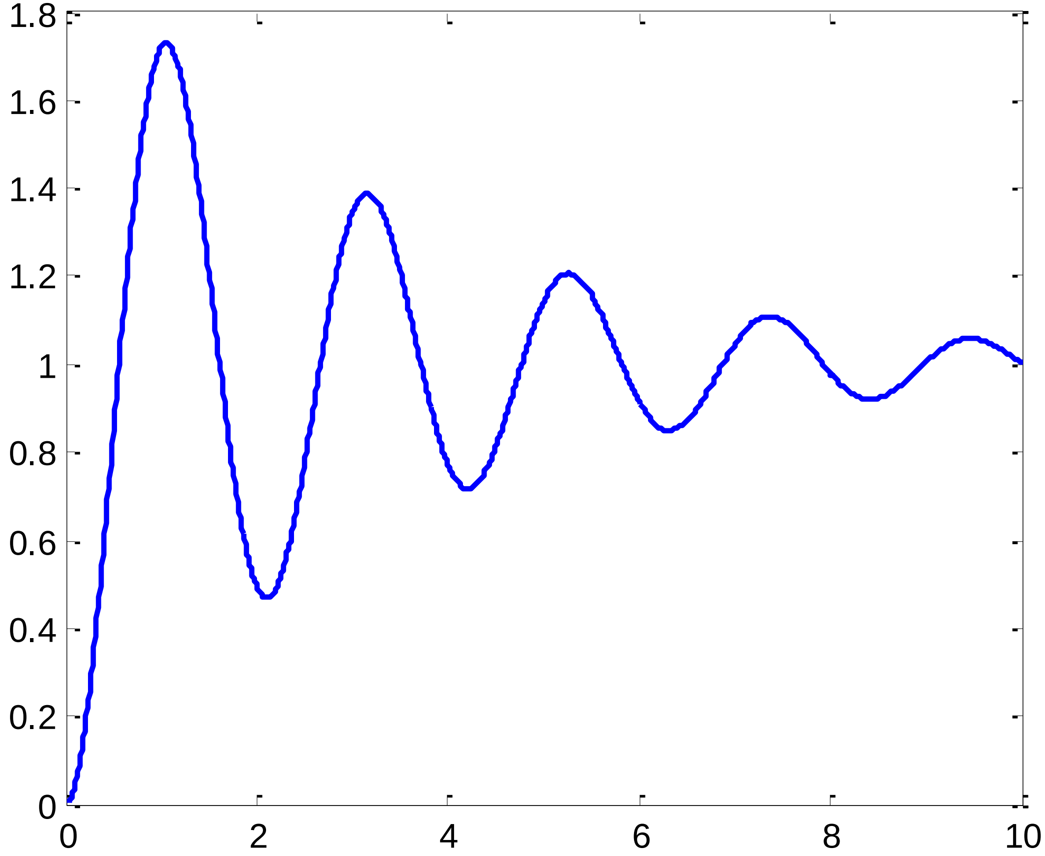
$$\begin{aligned}\omega_d &= \omega_n\sqrt{1-\zeta^2}\\ &= \omega_n\end{aligned}$$

$$c(t) = 1 - \cos\omega_n t$$

Step Response of underdamped System

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

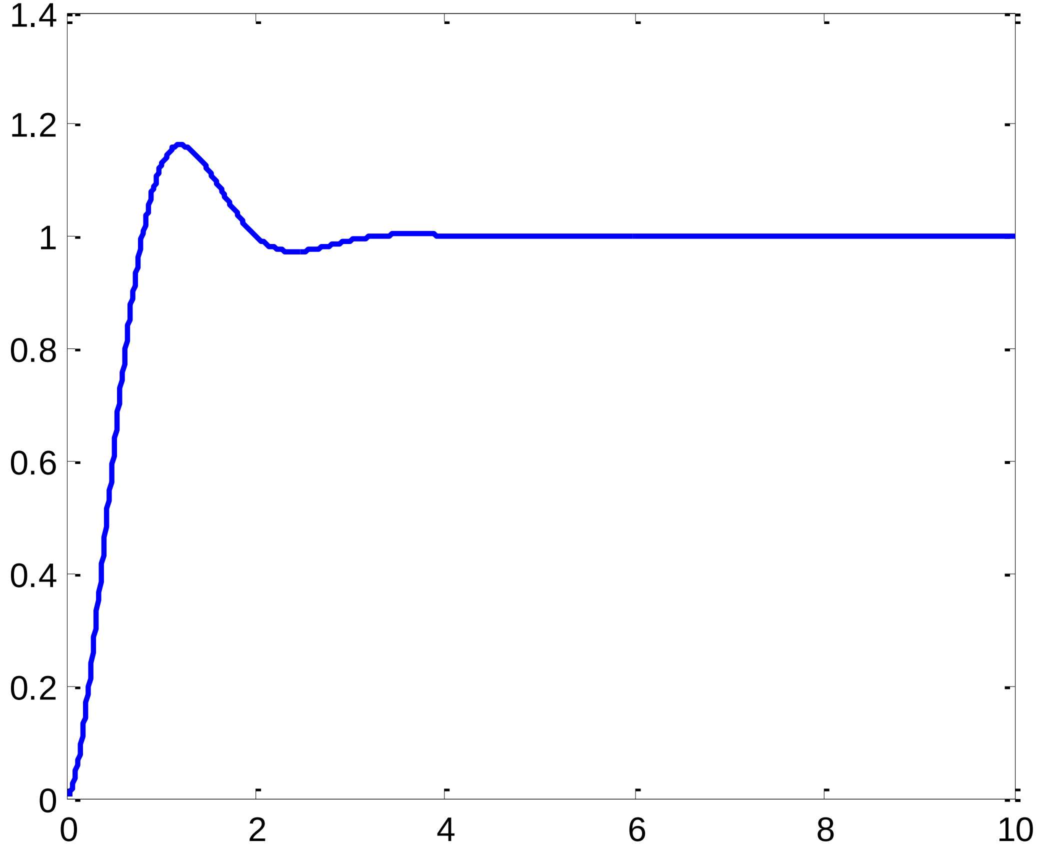
if $\zeta = 0.1$ and $\omega_n = 3 \ \ rad/\sec$



Step Response of underdamped System

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

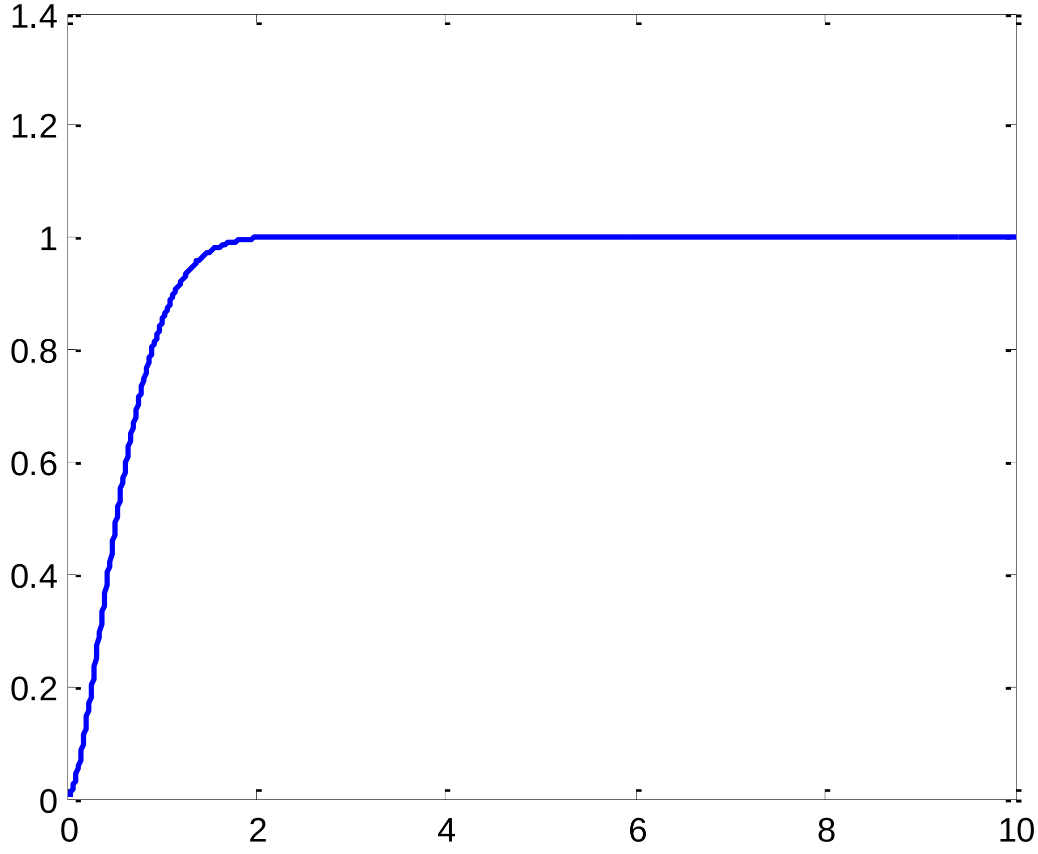
if $\zeta = 0.5$ and $\omega_n = 3 \ rad/\sec$



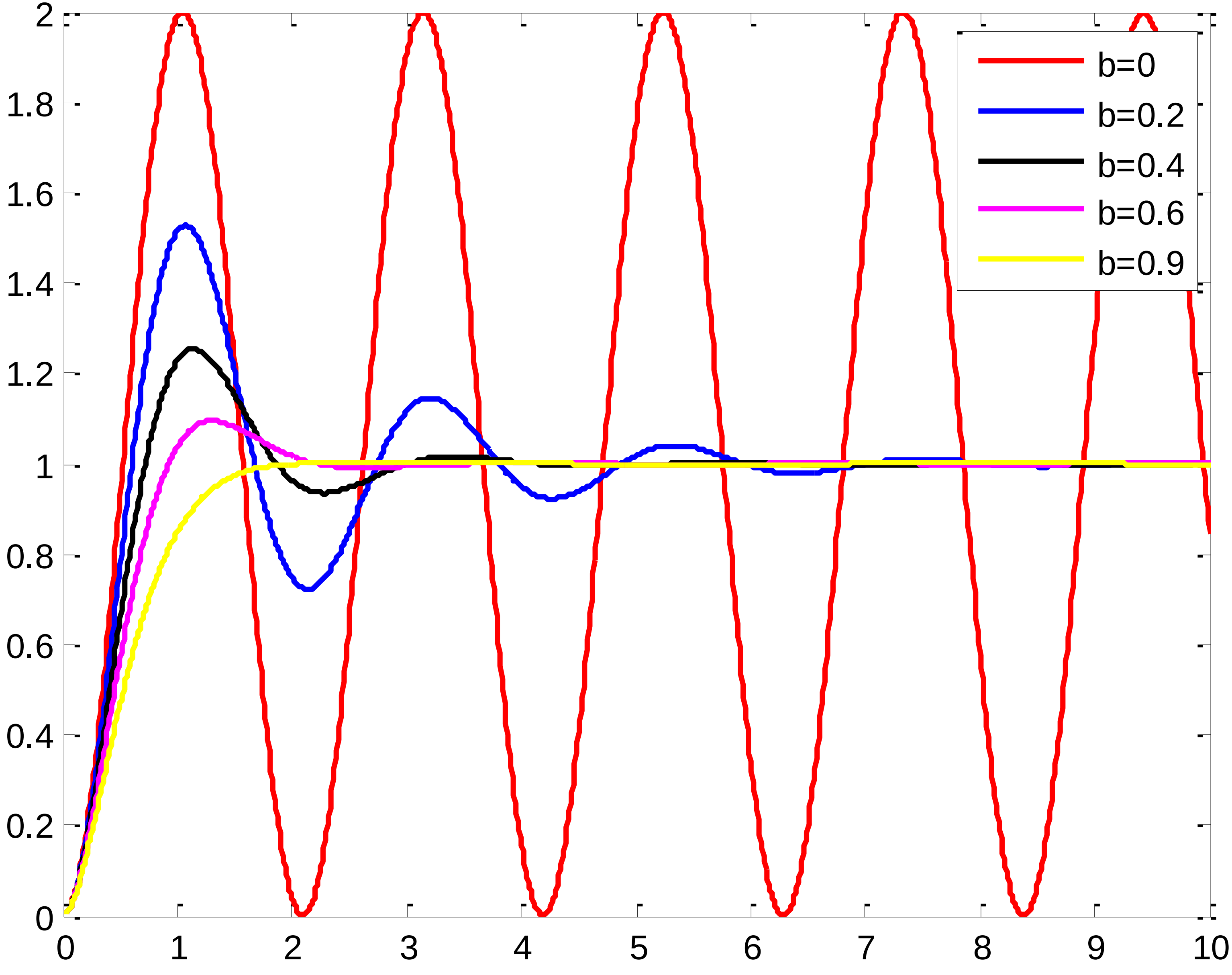
Step Response of underdamped System

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

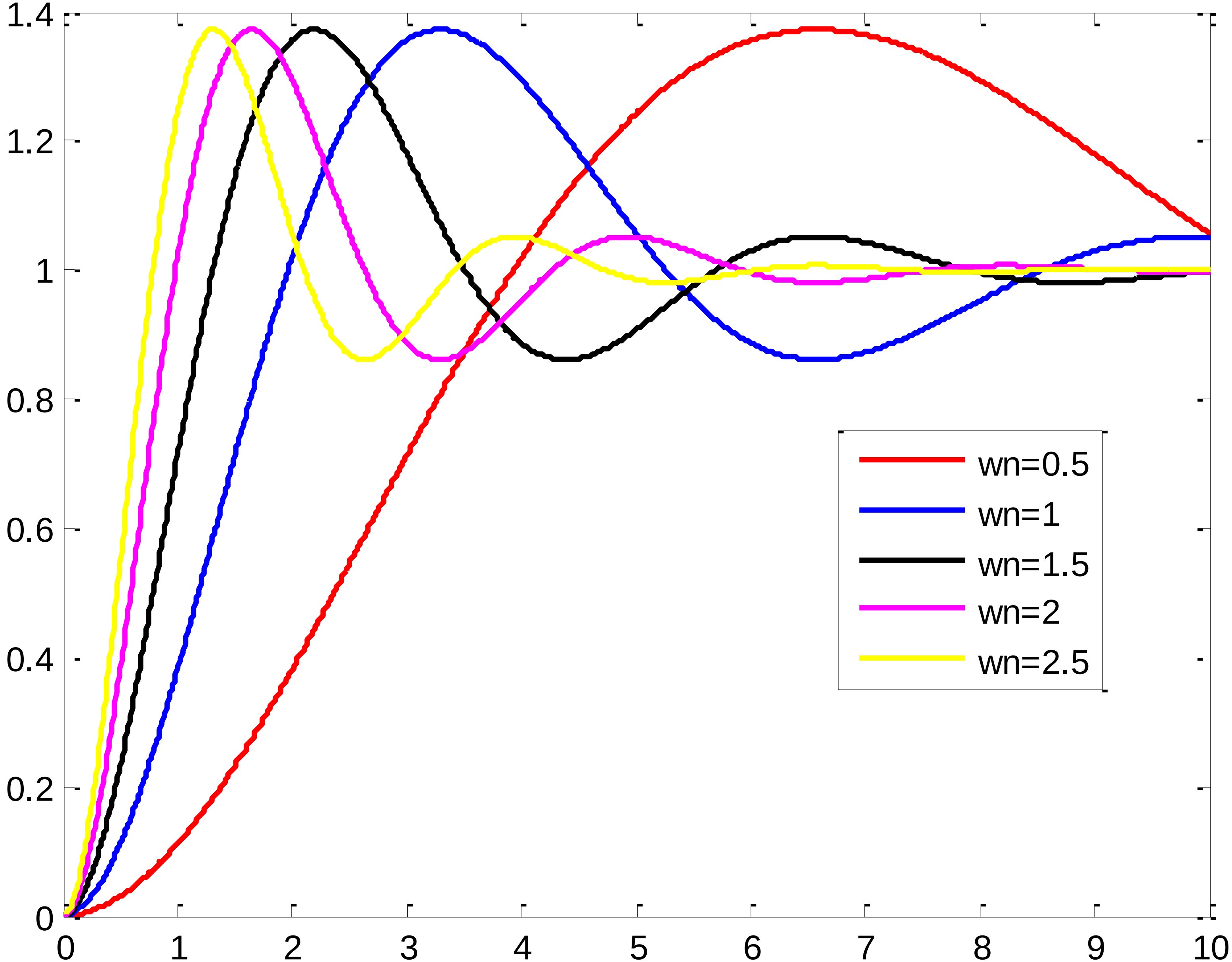
if $\zeta = 0.9$ and $\omega_n = 3 \ rad/\sec$



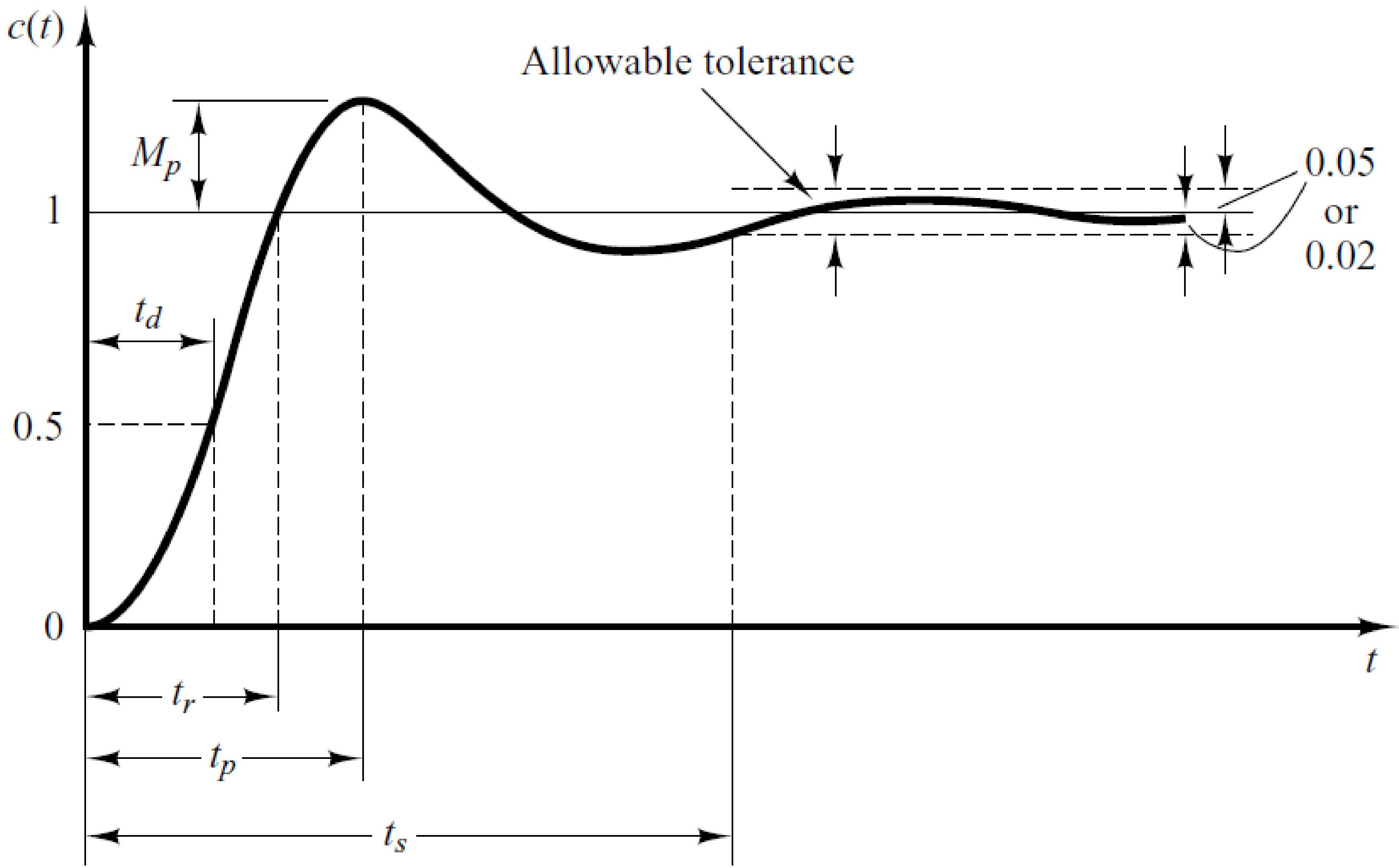
Step Response of underdamped System



Step Response of underdamped System



Time Domain Specifications of Underdamped system



Time Domain Specifications (Rise Time)

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

Put $t = t_r$ in above equation

$$c(t_r) = 1 - e^{-\zeta\omega_n t_r}\left[\cos\omega_d t_r + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_r\right]$$

Where $c(t_r) = 1$

$$0 = -e^{-\zeta\omega_n t_r}\left[\cos\omega_d t_r + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_r\right]$$

$$-e^{-\zeta\omega_n t_r} \neq 0 \qquad 0 = \left[\cos\omega_d t_r + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_r\right]$$

Time Domain Specifications (Rise Time)

$$\left[\cos\omega_d t_r + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_r\right] = 0$$

above equation can be re - writen as

$$\sin\omega_d t_r = -\frac{\sqrt{1-\zeta^2}}{\zeta}\cos\omega_d t_r$$

$$\tan\omega_d t_r = -\frac{\sqrt{1-\zeta^2}}{\zeta}$$

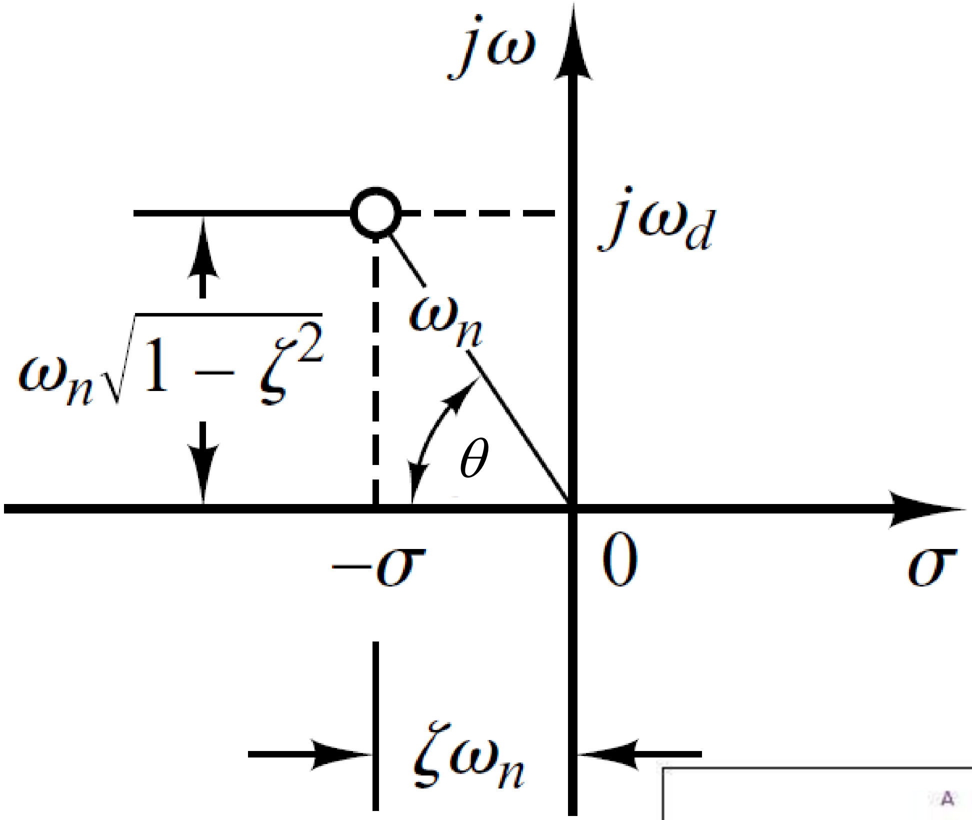
$$\omega_d t_r = \tan^{-1}\left(-\frac{\sqrt{1-\zeta^2}}{\zeta}\right)$$

Time Domain Specifications (Rise Time)

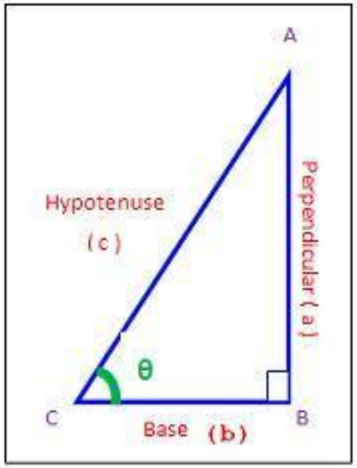
$$\omega_d t_r = \tan^{-1}\left(-\frac{\sqrt{1-\zeta^2}}{\zeta}\right)$$

$$t_r = \frac{1}{\omega_d}\tan^{-1}\left(-\frac{\omega_n\sqrt{1-\zeta^2}}{\omega_n\zeta}\right)$$

$$t_r = \frac{\pi - \theta}{\omega_d}$$



$$\theta = \tan^{-1}\frac{a}{b}$$



Time Domain Specifications (Peak Time)

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$

- In order to find peak time let us differentiate above equation w.r.t *t*.

$$\frac{dc(t)}{dt} = \zeta\omega_n e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right] - e^{-\zeta\omega_n t}\left[-\omega_d\sin\omega_d t + \frac{\zeta\omega_d}{\sqrt{1-\zeta^2}}\cos\omega_d t\right]$$

$$0 = e^{-\zeta\omega_n t}\left[\zeta\omega_n\cos\omega_d t + \frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}}\sin\omega_d t + \omega_d\sin\omega_d t - \frac{\zeta\omega_d}{\sqrt{1-\zeta^2}}\cos\omega_d t\right]$$

$$0 = e^{-\zeta\omega_n t}\left[\zeta\cancel{\omega_n}\cos\omega_d t + \frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}}\sin\omega_d t + \omega_d\sin\omega_d t - \frac{\zeta\omega_n\cancel{\sqrt{1-\zeta^2}}}{\cancel{\sqrt{1-\zeta^2}}}\cos\omega_d t\right]$$

Time Domain Specifications (Peak Time)

$$0 = e^{-\zeta\omega_n t}\left[\cancel{\zeta\omega_n}\cos\omega_d t + \frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}}\sin\omega_d t + \omega_d \sin\omega_d t - \frac{\zeta\omega_n \cancel{\sqrt{1-\zeta^2}}}{\cancel{\sqrt{1-\zeta^2}}}\cos\omega_d t\right]$$

$$e^{-\zeta\omega_n t}\left[\frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}}\sin\omega_d t + \omega_d \sin\omega_d t\right] = 0$$

$$e^{-\zeta\omega_n t} \neq 0 \qquad \left[\frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}}\sin\omega_d t + \omega_d \sin\omega_d t\right] = 0$$

$$\sin\omega_d t\left[\frac{\zeta^2\omega_n}{\sqrt{1-\zeta^2}} + \omega_d\right] = 0$$

Time Domain Specifications (Peak Time)

$$\sin \omega_d t \left[\frac{\zeta^2 \omega_n}{\sqrt{1-\zeta^2}} + \omega_d \right] = 0$$

$$\left[\frac{\zeta^2 \omega_n}{\sqrt{1-\zeta^2}} + \omega_d \right] \neq 0$$

$$\sin \omega_d t = 0$$

$$\omega_d t = \sin^{-1} 0$$

$$t = \frac{0, \pi, 2\pi, \cdots}{\omega_d}$$

- Since for underdamped stable systems first peak is maximum peak therefore,

$$\boxed{t_p = \frac{\pi}{\omega_d}}$$

Time Domain Specifications (Maximum Overshoot)

$$\text{Maximum percent overshoot} = \frac{c(t_p) - c(\infty)}{c(\infty)} \times 100\%$$

$$c(t_p) = 1 - e^{-\zeta\omega_n t_p}\left[\cos\omega_d t_p + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_p\right]$$

$$c(\infty) = 1$$

$$M_p = \left[\cancel{1} - e^{-\zeta\omega_n t_p}\left(\cos\omega_d t_p + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t_p\right) - \cancel{1}\right] \times 100$$

Put $t_p = \dfrac{\pi}{\omega_d}$ in above equation

$$M_p = \left[-e^{-\zeta\omega_n \frac{\pi}{\omega_d}}\left(\cos\omega_d\frac{\pi}{\omega_d} + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d\frac{\pi}{\omega_d}\right)\right] \times 100$$

Time Domain Specifications (Maximum Overshoot)

$$M_p = \left[-e^{-\zeta\omega_n \frac{\pi}{\omega_d}} \left(\cos \cancel{\omega_d} \frac{\pi}{\cancel{\omega_d}} + \frac{\zeta}{\sqrt{1-\zeta^2}} \sin \cancel{\omega_d} \frac{\pi}{\cancel{\omega_d}} \right) \right] \times 100$$

Put $\omega_d = \omega_n \sqrt{1\text{-}\zeta^2}$ in above equation

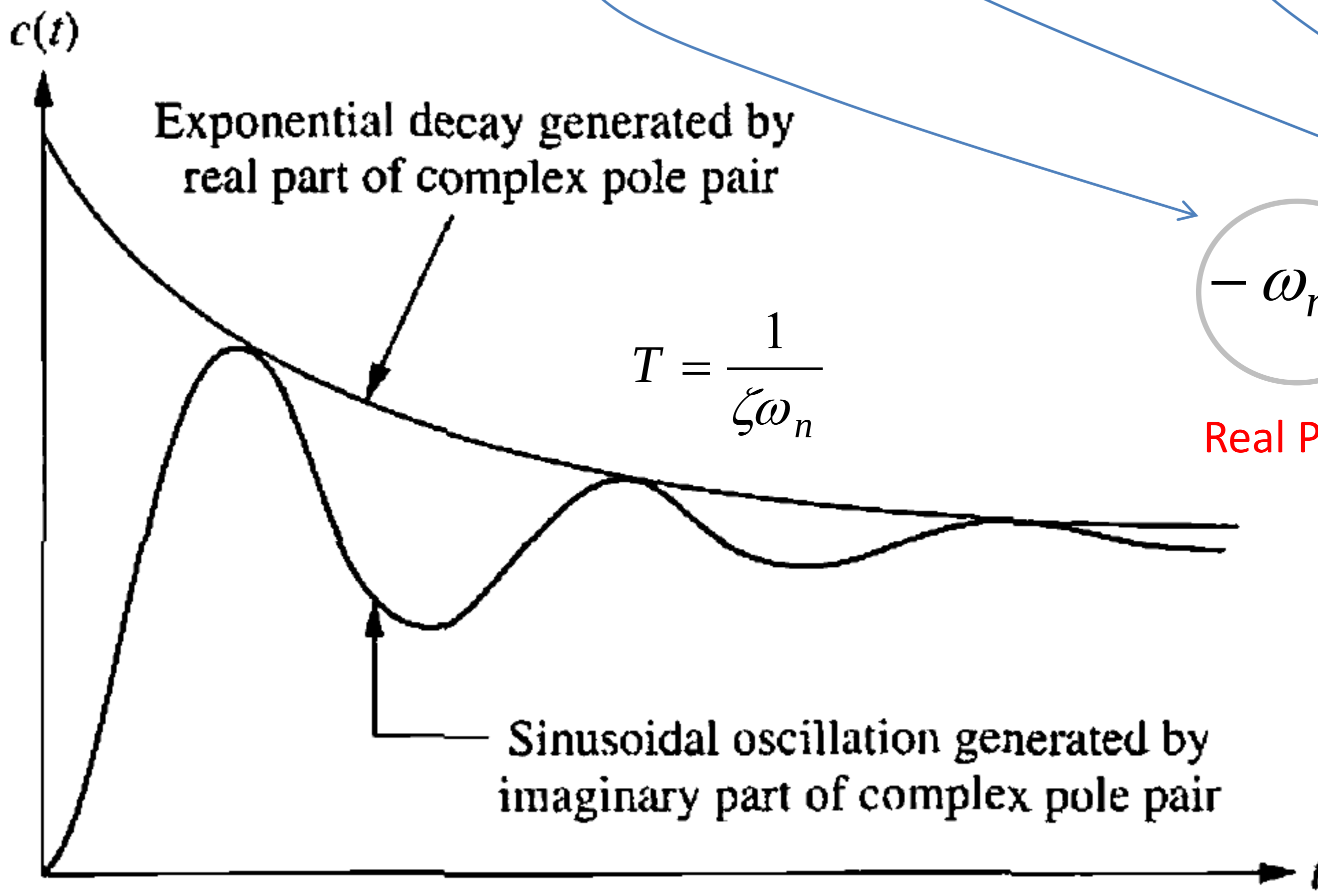
$$M_p = \left[-e^{-\zeta\cancel{\omega_n} \frac{\pi}{\cancel{\omega_n}\sqrt{1-\zeta^2}}} \left(\cos\pi + \frac{\zeta}{\sqrt{1-\zeta^2}} \sin\pi \right) \right] \times 100$$

$$M_p = \left[-e^{-\frac{\pi\zeta}{\sqrt{1-\zeta^2}}} (-1+0) \right] \times 100$$

$$\boxed{M_p = e^{-\frac{\pi\zeta}{\sqrt{1-\zeta^2}}} \times 100}$$

Time Domain Specifications (Settling Time)

$$c(t) = 1 - e^{-\zeta\omega_n t}\left[\cos\omega_d t + \frac{\zeta}{\sqrt{1-\zeta^2}}\sin\omega_d t\right]$$



$$-\omega_n\zeta \pm \omega_n\sqrt{\zeta^2 - 1}$$

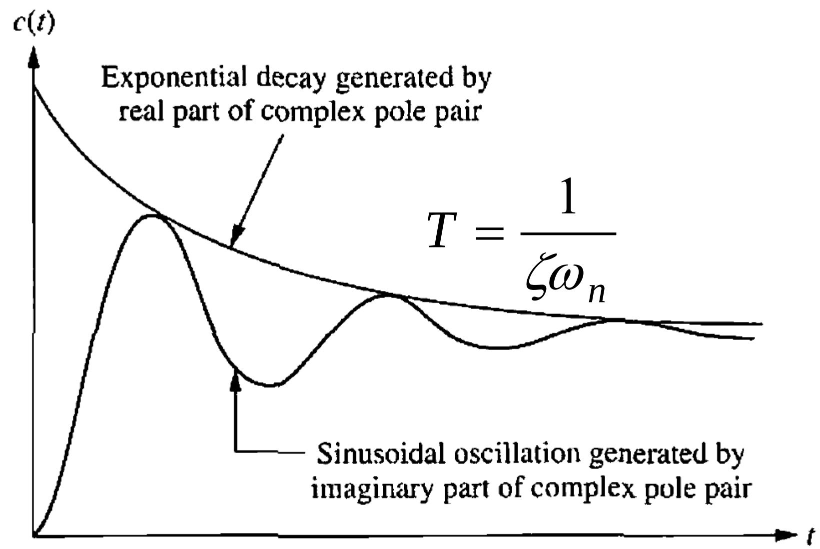
Real Part

Imaginary Part

Time Domain Specifications (Settling Time)

- Settling time (2%) criterion
  - Time consumed in exponential decay up to 98% of the input.

$$t_s = 4T = \frac{4}{\zeta\omega_n}$$



- Settling time (5%) criterion
  - Time consumed in exponential decay up to 95% of the input.

$$t_s = 3T = \frac{3}{\zeta\omega_n}$$

Summary of Time Domain Specifications

Rise Time

$$t_r = \frac{\pi - \theta}{\omega_d} = \frac{\pi - \theta}{\omega_n \sqrt{1 - \zeta^2}}$$

Peak Time

$$t_p = \frac{\pi}{\omega_d} = \frac{\pi}{\omega_n \sqrt{1 - \zeta^2}}$$

Settling Time (2%)

$$t_s = 4T = \frac{4}{\zeta \omega_n}$$

$$t_s = 3T = \frac{3}{\zeta \omega_n}$$

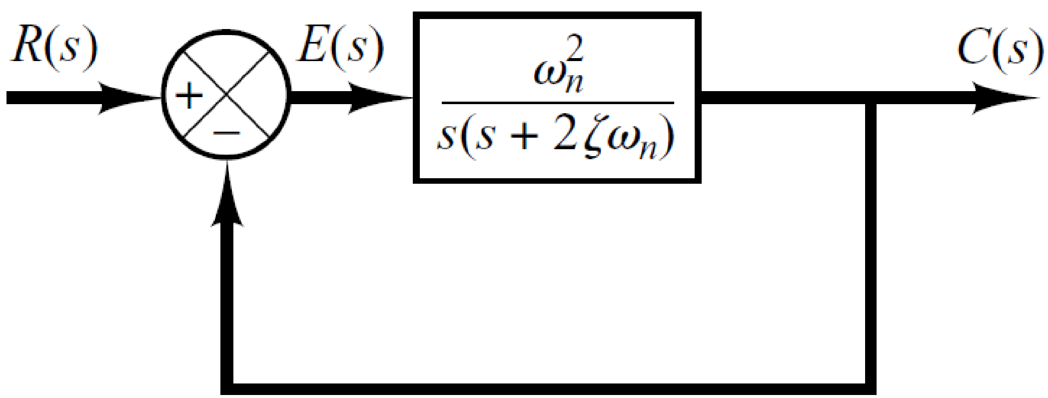
Settling Time (4%)

Maximum Overshoot

$$M_p = e^{-\frac{\pi \zeta}{\sqrt{1-\zeta^2}}} \times 100$$

Example#5

- Consider the system shown in following figure, where damping ratio is 0.6 and natural undamped frequency is 5 rad/sec. Obtain the rise time t_r, peak time t_p, maximum overshoot M_p, and settling time 2% and 5% criterion t_s when the system is subjected to a unit-step input.



Example#5

Rise Time

$$t_r = \frac{\pi - \theta}{\omega_d}$$

Peak Time

$$t_p = \frac{\pi}{\omega_d}$$

Settling Time (2%)

$$t_s = 4T = \frac{4}{\zeta \omega_n}$$

$$t_s = 3T = \frac{3}{\zeta \omega_n}$$

Settling Time (4%)

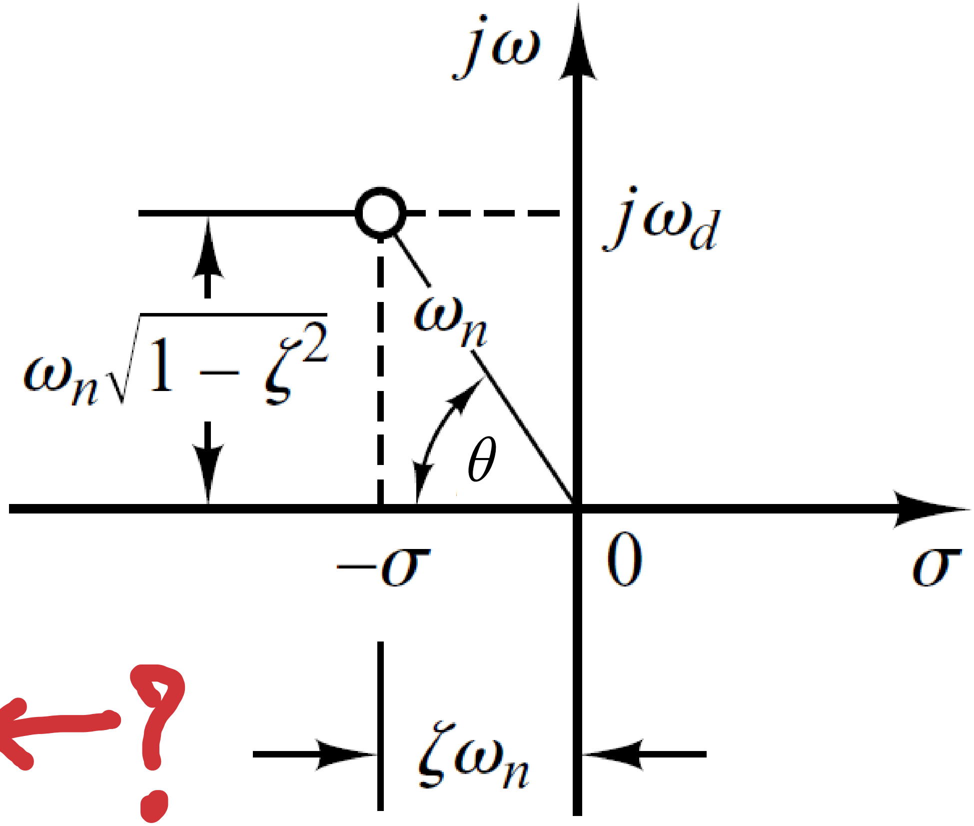
Maximum Overshoot

$$M_p = e^{-\frac{\pi \zeta}{\sqrt{1-\zeta^2}}} \times 100$$

Example#5

Rise Time

$$t_r = \frac{\pi - \theta}{\omega_d}$$



$$t_r = \frac{3.141 - \theta}{\omega_n\sqrt{1-\zeta^2}}$$

$$\theta = \tan^{-1}\left(\frac{\omega_n\sqrt{1-\zeta^2}}{\zeta\omega_n}\right) = 0.93 \text{ rad}$$

?

$$t_r = \frac{3.141 - 0.93}{5\sqrt{1-0.6^2}} = 0.55s$$

Example#5

Peak Time

$$t_p = \frac{\pi}{\omega_d}$$

$$t_p = \frac{3.141}{4} = 0.785s$$

Settling Time (2%)

$$t_s = \frac{4}{\zeta\omega_n}$$

$$t_s = \frac{4}{0.6 \times 5} = 1.33s$$

Settling Time (4%)

$$t_s = \frac{3}{\zeta\omega_n}$$

$$t_s = \frac{3}{0.6 \times 5} = 1s$$

Example#5

Maximum Overshoot

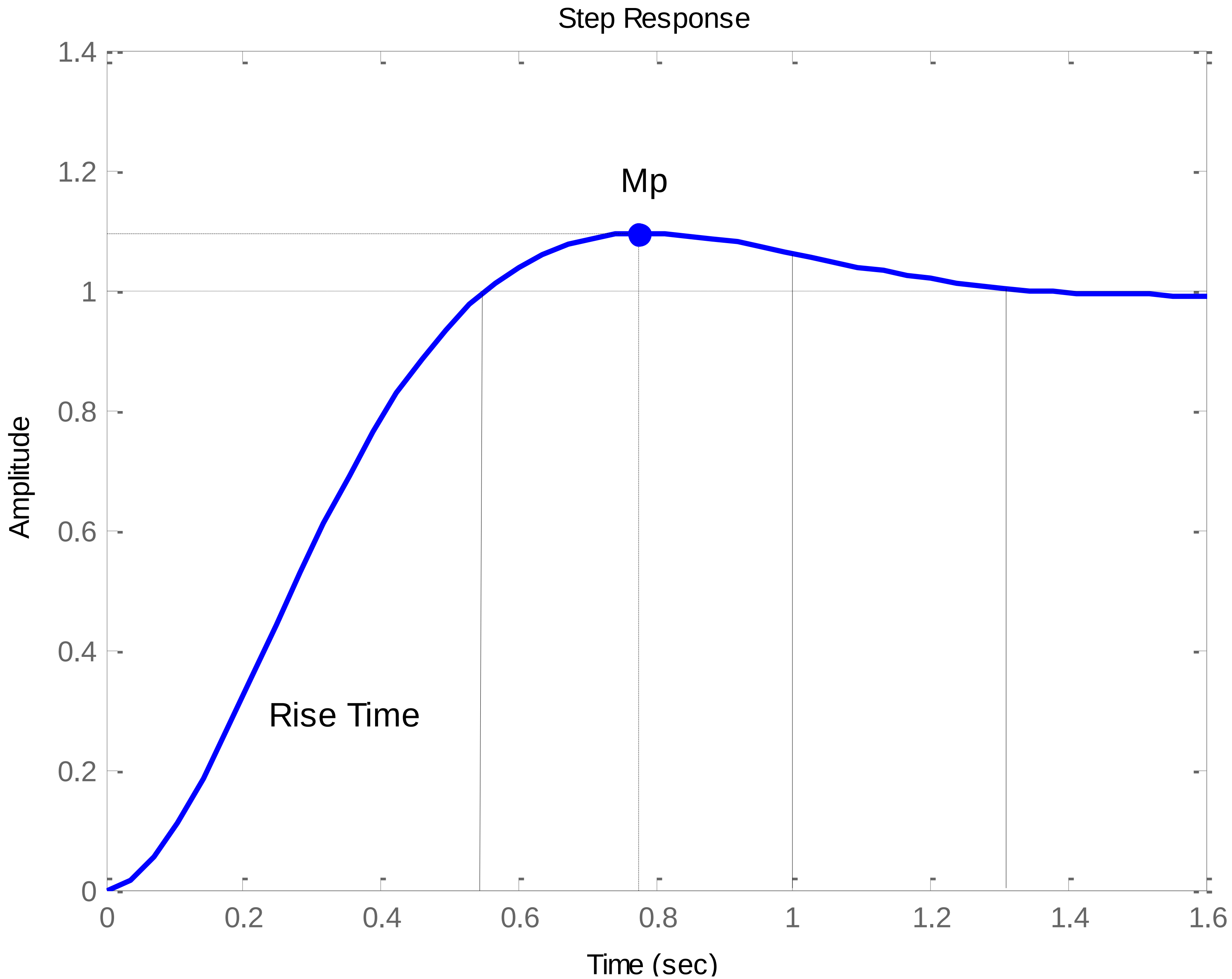
$$M_p = e^{-\frac{\pi\zeta}{\sqrt{1-\zeta^2}}} \times 100$$

$$M_p = e^{-\frac{3.141\times 0.6}{\sqrt{1-0.6^2}}} \times 100$$

$$M_p = 0.095 \times 100$$

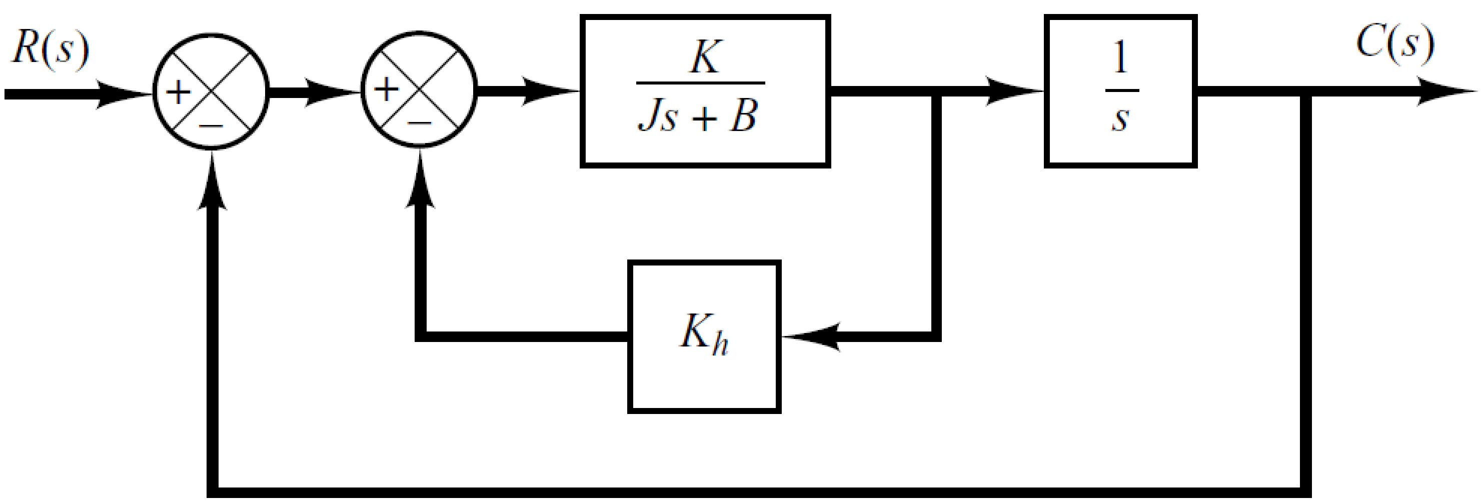
$$M_p = 9.5\%$$

Example#5

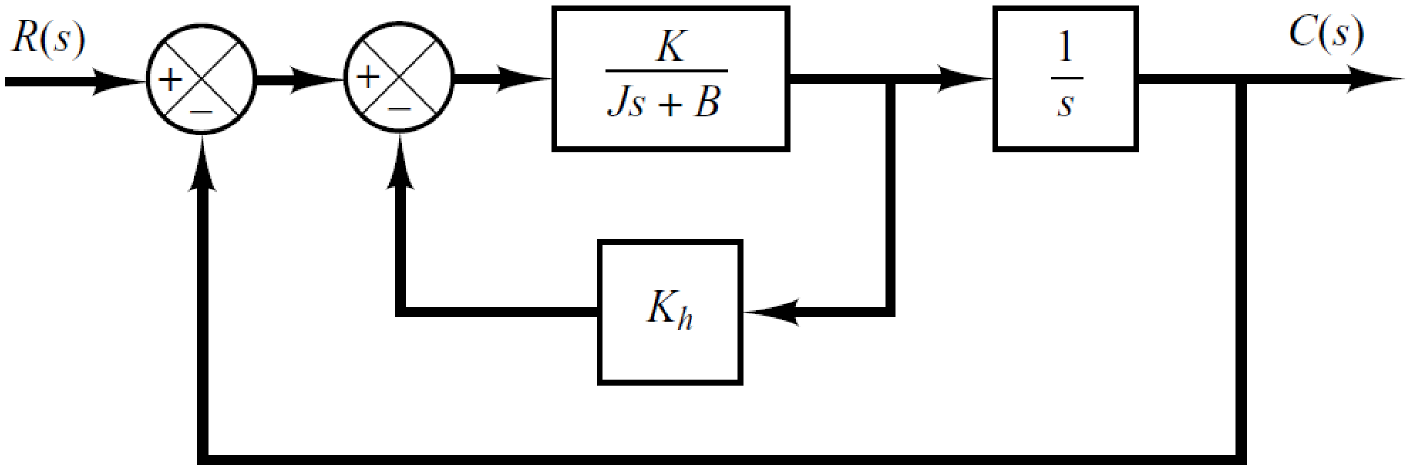

Step Response
Mp
Rise Time
Amplitude
Time (sec)
0
0.2
0.4
0.6
0.8
1
1.2
1.4
1.6
0
0.2
0.4
0.6
0.8
1
1.2
1.4

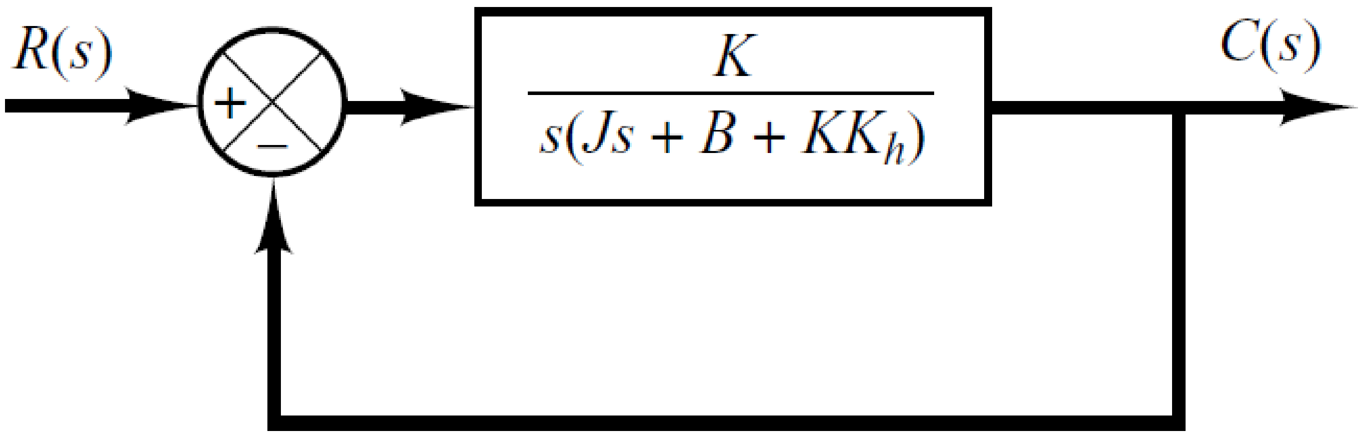
Example#6

- For the system shown in Figure-(a), determine the values of gain K and velocity-feedback constant K_h so that the maximum overshoot in the unit-step response is 0.2 and the peak time is 1 sec. With these values of K and K_h, obtain the rise time and settling time. Assume that J=1 kg-m^2 and B=1 N-m/rad/sec.



Example#6





$$\frac{C(s)}{R(s)} = \frac{K}{Js^2 + (B + KK_h)s + K}$$

Example#6

$$\frac{C(s)}{R(s)} = \frac{K}{Js^2 + (B + KK_h)s + K}$$

Since $J = 1\ kgm^2$ and $B = 1$ Nm/rad/sec

$$\frac{C(s)}{R(s)} = \frac{K}{s^2 + (1 + KK_h)s + K}$$

- Comparing above T.F with general 2nd order T.F

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$$

$$\omega_n = \sqrt{K} \qquad \zeta = \frac{(1 + KK_h)}{2\sqrt{K}}$$

Example#6

$$\omega_n = \sqrt{K}$$

$$\zeta = \frac{(1+KK_h)}{2\sqrt{K}}$$

- Maximum overshoot is 0.2.
- The peak time is 1 sec

$$M_p = e^{-(\zeta/\sqrt{1-\zeta^2})\pi}$$

$$e^{-(\zeta/\sqrt{1-\zeta^2})\pi} = 0.2$$

$$\ln\left(e^{-\frac{\pi\zeta}{\sqrt{1-\zeta^2}}}\right) = \ln(0.2)$$

$$\frac{\zeta\pi}{\sqrt{1-\zeta^2}} = 1.61$$

?

$$\zeta = 0.456$$

$$t_p = \frac{\pi}{\omega_d}$$

$$1 = \frac{3.141}{\omega_n\sqrt{1-\zeta^2}}$$

$$\omega_n = \frac{3.141}{\sqrt{1-0.456^2}}$$

$$\omega_n = 3.53$$

Example#6

$$\zeta = 0.456$$

$$\omega_n = 3.96$$

$$\omega_n = \sqrt{K}$$

$$3.53 = \sqrt{K}$$

$$3.53^2 = K$$

$$K = 12.5$$

$$\zeta = \frac{(1 + KK_h)}{2\sqrt{K}}$$

$$0.456 \times 2\sqrt{12.5} = (1 + 12.5K_h)$$

$$K_h = 0.178$$

Example#6

$\zeta = 0.456$

$\omega_n = 3.96$

$$t_r = \frac{\pi - \theta}{\omega_n \sqrt{1-\zeta^2}}$$

$$t_s = \frac{4}{\zeta \omega_n}$$

$t_r = 0.65s$

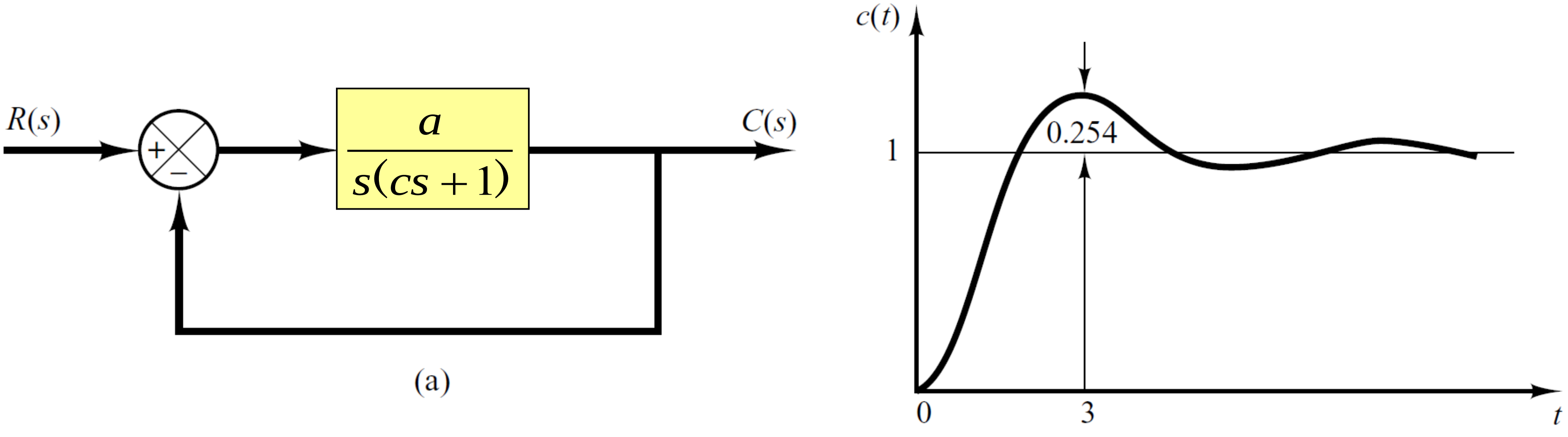
$t_s = 2.48s$

$$t_s = \frac{3}{\zeta \omega_n}$$

$t_s = 1.86s$

Example#7

When the system shown in Figure(a) is subjected to a unit-step input, the system output responds as shown in Figure(b). Determine the values of *a* and *c* from the response curve.

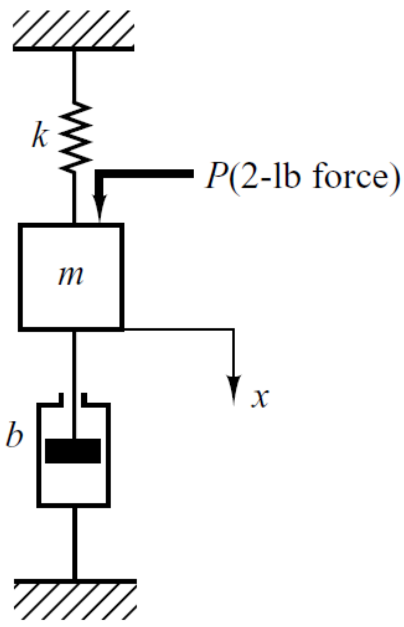


(a)

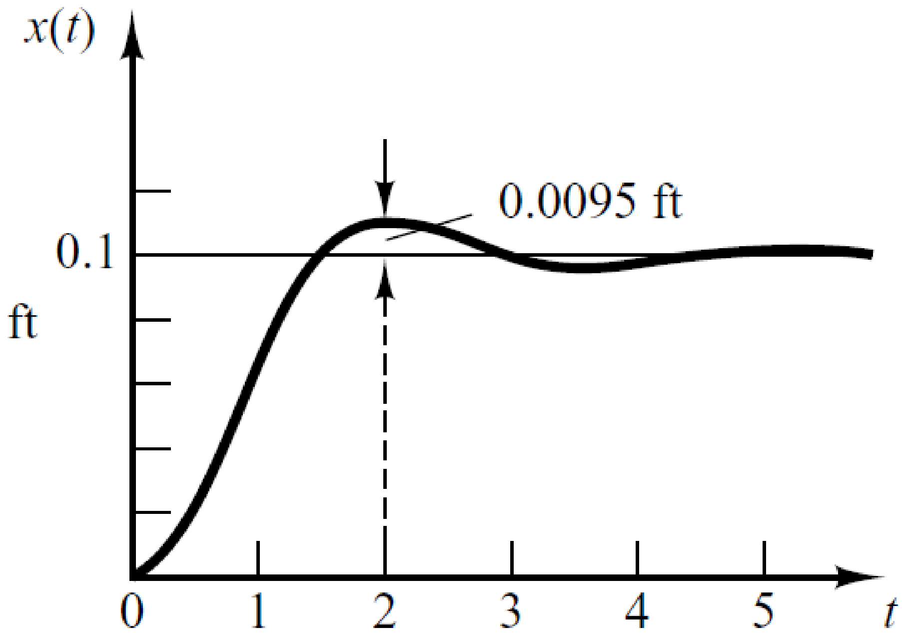
(b)

Example#8

Figure (a) shows a mechanical vibratory system. When 2 lb of force (step input) is applied to the system, the mass oscillates, as shown in Figure (b). Determine m, b, and k of the system from this response curve.



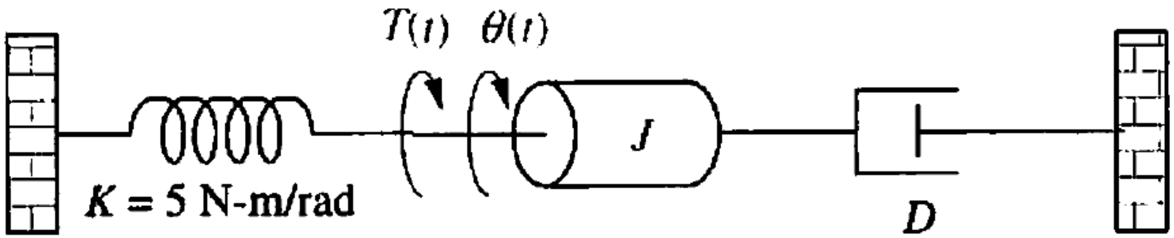
(a)



(b)

Example#9

Given the system shown in following figure, find *J and D to yield 20%* overshoot and a settling time of 2 seconds for a step input of torque *T(t).*



$$G(s) = \frac{1/J}{s^2 + \frac{D}{J}s + \frac{K}{J}}$$

$$2\zeta\omega_n = 4$$

$$\omega_n = \sqrt{\frac{K}{J}}$$

$$\zeta = \frac{4}{2\omega_n} = 2\sqrt{\frac{J}{K}}$$

$$T_s = 2 = \frac{4}{\zeta\omega_n}$$

Example#9

$$\omega_n = \sqrt{\frac{K}{J}} \qquad \zeta = 2\sqrt{\frac{J}{K}}$$

20% overshoot implies $\zeta = 0.456$. Therefore,

$$\zeta = 2\sqrt{\frac{J}{K}} = 0.456$$

Hence,

$$\frac{J}{K} = 0.052$$

From the problem statement, $K = 5$ N-m/rad.

$$J = 0.26 \text{ kg-m}^2$$

Example#9

$$G(s) = \frac{1/J}{s^2 + \frac{D}{J}s + \frac{K}{J}}$$

$$2\zeta\omega_n = \frac{D}{J}$$

$$D = 1.04 \text{ N-m-s/rad}$$

Step Response of critically damped System ($\zeta = 1$)

$$\frac{C(s)}{R(s)} = \frac{\omega_n^2}{(s+\omega_n)^2} \xrightarrow{\text{Step Response}} C(s) = \frac{\omega_n^2}{s(s+\omega_n)^2}$$

- The partial fraction expansion of above equation is given as

$$\frac{\omega_n^2}{s(s+\omega_n)^2} = \frac{A}{s} + \frac{B}{s+\omega_n} + \frac{C}{(s+\omega_n)^2}$$

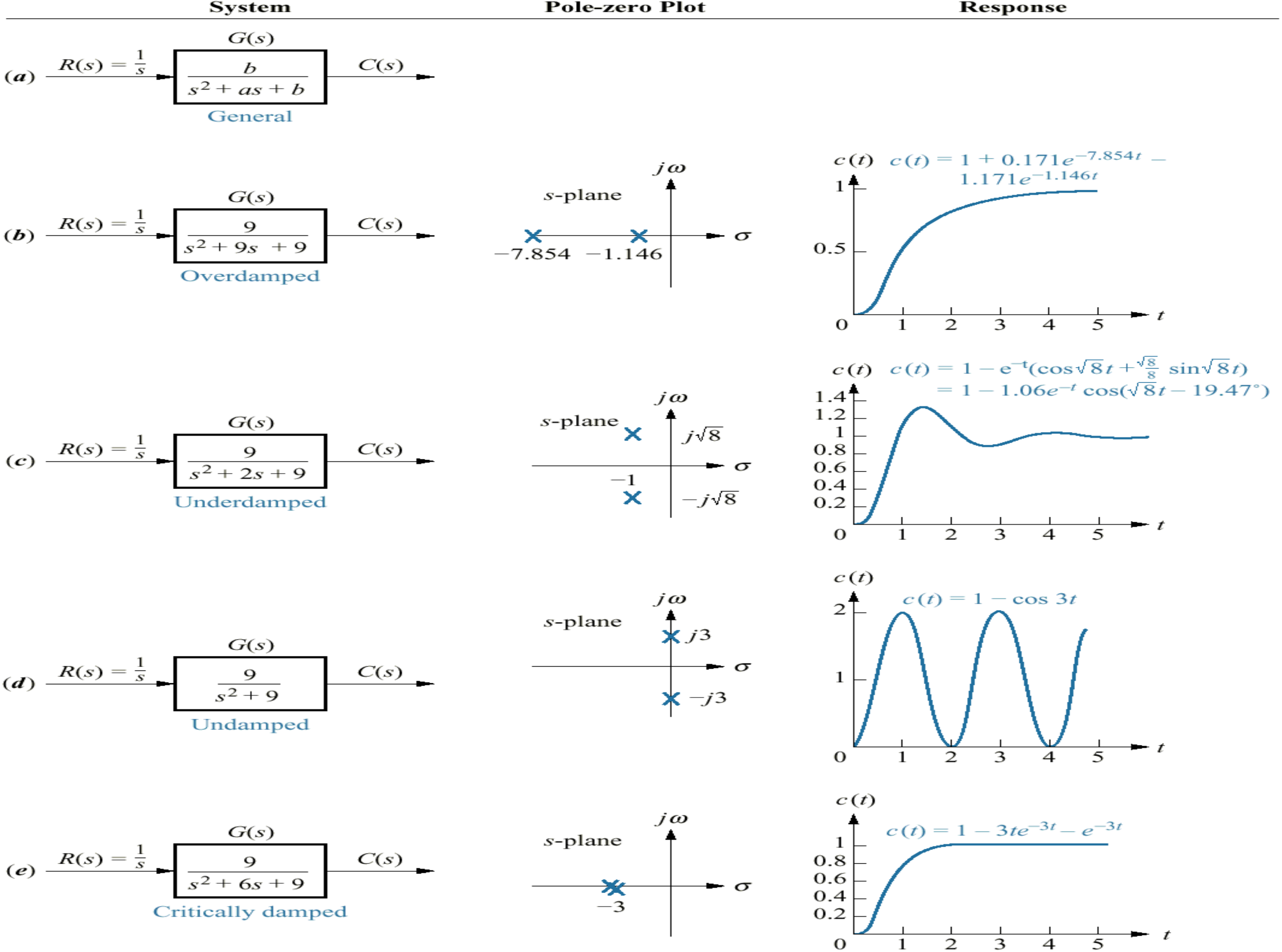
$$C(s) = \frac{1}{s} - \frac{1}{s+\omega_n} - \frac{\omega_n}{(s+\omega_n)^2}$$

$$c(t) = 1 - e^{-\omega_n t} - \omega_n e^{-\omega_n t} t$$

$$c(t) = 1 - e^{-\omega_n t}(1 + \omega_n t)$$

Step Response of overdamped and undamped Systems

- Home Work


System
Pole-zero Plot
Response
(a)
R(s) = 1/s
G(s)
b / (s^2 + as + b)
C(s)
General
(b)
R(s) = 1/s
G(s)
9 / (s^2 + 9s + 9)
C(s)
Overdamped
jω
s-plane
σ
−7.854
−1.146
c(t)
c(t) = 1 + 0.171e^−7.854t − 1.171e^−1.146t
1
0.5
0
1
2
3
4
5
t
(c)
R(s) = 1/s
G(s)
9 / (s^2 + 2s + 9)
C(s)
Underdamped
jω
s-plane
j√8
σ
−1
−j√8
c(t)
c(t) = 1 − e^−t(cos√8t + √8/8 sin√8t)
= 1 − 1.06e^−t cos(√8t − 19.47°)
1.4
1.2
1
0.8
0.6
0.4
0.2
0
1
2
3
4
5
t
(d)
R(s) = 1/s
G(s)
9 / (s^2 + 9)
C(s)
Undamped
jω
s-plane
j3
σ
−j3
c(t)
c(t) = 1 − cos 3t
2
1
0
1
2
3
4
5
t
(e)
R(s) = 1/s
G(s)
9 / (s^2 + 6s + 9)
C(s)
Critically damped
jω
s-plane
σ
−3
c(t)
c(t) = 1 − 3te^−3t − e^−3t
1
0.8
0.6
0.4
0.2
0
1
2
3
4
5
t

Second – Order System

Example 10: Describe the nature of the second-order system response via the value of the damping ratio for the systems with transfer function

1. $G(s) = \dfrac{12}{s^2 + 8s + 12}$

2. $G(s) = \dfrac{16}{s^2 + 8s + 16}$

Do them as your own revision

3. $G(s) = \dfrac{20}{s^2 + 8s + 20}$