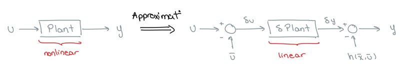
**Modelling CS** $u$: control input, $y$: plant output
**State variable** CS is in state variable form if
$\dot{x}_1 = f_1(t, x_1, \dots, x_n, u), \dots, \dot{x}_n = f_n(t, x_1, \dots, x_n, u)$
$y = h(t, x_1, \dots, x_n, u)$ is a collection of $n$ 1st order ODEs.
**Time-Invariant (TI)** CS is TI if $f_i(\cdot)$ does not depend on $t$.
**State space (SS)** TI CS is in SS form if $\dot{x} = f(x,u)$, $y = h(x,u)$ where $x(t) \in \mathbb{R}^n$ is called the state.
**Single-input-single-output (SISO)** CS is SISO if $u(t), y(t) \in \mathbb{R}$.
**LTI** CS in SS form is LTI if $\dot{x} = Ax + Bu$, $y = Cx + Du$
$A \in \mathbb{R}^{n\times n}$, $B \in \mathbb{R}^{n \times m}$, $C \in \mathbb{R}^{p\times n}$, $D \in \mathbb{R}^{p\times m}$
where $x(t) \in \mathbb{R}^n$, $u(t) \in \mathbb{R}^m$, $y(t) \in \mathbb{R}^p$.
**Input-Output (IO)** LTI CS is in IO form if
$\frac{d^n y}{dt^n} + a_{n-1}\frac{d^{n-1}y}{dt^{n-1}} + \cdot\cdot + a_1\frac{dy}{dt} + a_0 y = b_m \frac{d^m u}{dt^m} + \cdot\cdot + b_1\frac{du}{dt} + b_0 u$
where $m \le n$ (causality)

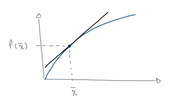
**IO to SS Model** 1. Define $x$ s.t. highest order derivative in $\dot{x}$
2. Write $\dot{x} = Ax + Bu = f(x,u)$ by isolating for components of $\dot{x}$
3. Write $y = Cx + Du = h(x,u)$ by setting measurement output $y$ to component of $x$
**Equilibria** $y_d$ (steady state) b/c if $y(0) = y_d$ at $t = 0$, then $y(t) = y_d$ $\forall t \ge 0$.

**Equilibrium pair** Consider the system $\dot{x} = f(x,u)$. The pair $(\bar{x}, \bar{u})$ is an equilibrium pair if $f(\bar{x},\bar{u}) = 0$.
**Equilibrium point** $\bar{x}$ is an equilibrium point w/ control $u = \bar{u}$.
*If $u = \bar{u}$ and $x(0) = \bar{x}$ then $x(t) = \bar{x}$ $\forall t \ge 0$ (i.e. a system that starts at equilibrium remains at equilibrium).
**Find Equilibrium Pair/Point** 1. Set $f(x,u) = 0$
2. Solve $f(x,u) = 0$ to find $(x,u) = (\bar{x},\bar{u})$.
3. If specific $u = \bar{u}$, then find $x = \bar{x}$ by solving $f(x,\bar{u}) = 0$.

**Linearization of Nonlinear System** Consider system $\dot{x} = f(x,u)$ w/ equ. pair $(\bar{x},\bar{u})$, then error coordinates around equ. pair
$\delta x = x - \bar{x}$, $\delta u = u - \bar{u}$, $\delta y = y - h(\bar{x},\bar{u})$ $\dot{\delta x} = \dot{x} - f(\bar{x},\bar{u})$ w/
$\dot{\delta x} = A\delta x + B\delta u$, $A = \frac{\partial f(\bar{x},\bar{u})}{\partial x} \in \mathbb{R}^{n_1 \times n_1}$, $B = \frac{\partial f(\bar{x},\bar{u})}{\partial u} \in \mathbb{R}^{n_1}$,
$\delta y = C\delta x + D\delta u$, $C = \frac{\partial h}{\partial x}(\bar{x},\bar{u}) \in \mathbb{R}^{1\times n_1}$, $D = \frac{\partial h(\bar{x},\bar{u})}{\partial u} \in \mathbb{R}$
*Only valid at equ. pairs.

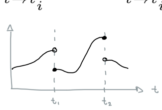



**Linear Approx.** Given a diff. fcn. $f: \mathbb{R} \to \mathbb{R}$, its linear approx. at $\bar{x}$ is $f_{\text{lin}} = f(\bar{x}) + f'(\bar{x})(x - \bar{x})$.
*Remainder Thm: $f(x) = f_{\text{lin}} + r(x)$ where $\lim_{x\to\bar{x}} \frac{r(x)}{x-\bar{x}} = 0$.

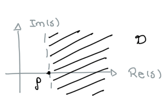


*Note: Can provide a good approx. near $\bar{x}$ but not globally.
*Gen. $f: \mathbb{R}^{n_1} \to \mathbb{R}^{n_2}$, $f(x) = f(\bar{x}) + \frac{\partial f}{\partial x}(\bar{x})(x - \bar{x}) + R(x)$
*Jacobian: $\frac{\partial f}{\partial x}(\bar{x}) = \left[\frac{\partial f}{\partial x_1}(\bar{x}) \quad \cdots \quad \frac{\partial f}{\partial x_{n_1}}(\bar{x})\right] \in \mathbb{R}^{n_2 \times n_1}$
**Linearization Steps** 1. Find equ. pair $(\bar{x},\bar{u})$
2. Derive $A, B, C, D$ and then evaluate at $(\bar{x},\bar{u})$
3. Write $\dot{\delta x} = A\delta x + B\delta u$ and $\delta y = C\delta x + D\delta u$

**Laplace Transform** Given a fcn $f: \mathbb{R}_+ = [0,\infty) \to \mathbb{R}^n$, its Laplace transform is $F(s) = \mathcal{L}\{f(t)\} := \int_{0^-}^{\infty} f(t)e^{-st}\,dt$, $s \in \mathbb{C}$.
*$\mathcal{L}: f(t) \mapsto F(s)$, $t \in \mathbb{R}_+$ (time dom.) & $s \in \mathbb{C}$ (Laplace dom.).
**P.W. CTS:** A fcn $f: \mathbb{R}_+ \to \mathbb{R}^n$ is **p.w. cts** if on every finite interval of $\mathbb{R}$, $f(t)$ has at most a finite # of discontinuity points $(t_i)$ and the limits $\lim_{t\to t_i^+} f(t)$, $\lim_{t \to t_i^-} f(t)$ are finite.



**Exp. Order** A function $f: \mathbb{R}_+ \to \mathbb{R}^n$ is of **exp. order** if ∃ constants $K, \rho, T > 0$ s.t. $\|f(t)\| \le Ke^{\rho t}$, $\forall t \ge T$.
**Existence of LT Thm** If $f(t)$ is p.w. cts and of exp. order w/ constants $K, \rho, T > 0$, then $F(\cdot)$ exists and is defined $\forall\, s \in D := \{s \in \mathbb{C} : \text{Re}(s) > \rho\}$ and $F(\cdot)$ is analytic on $D$.
*Analytic fcn iff differentiable fcn.
*$D$: Region of convergence (ROC), open half plane.




**Unit Step** $\mathbf{1}(t) := \begin{cases} 1, & \text{if } t \ge 0 \\ 0, & \text{otherwise} \end{cases}$
**Table of Common Laplace Transforms:** $f(t)$ | $F(s)$
$\mathbf{1}(t) \mapsto \frac{1}{s}$ $\quad t\mathbf{1}(t) \mapsto \frac{1}{s^2}$ $\quad t^k\,\mathbf{1}(t) \mapsto \frac{k!}{s^{k+1}}$ $\quad e^{at}\,\mathbf{1}(t) \mapsto \frac{1}{s-a}$
$t^n e^{at}\,\mathbf{1}(t) \mapsto \frac{n!}{(s-a)^{n+1}}$ $\quad \sin(at)\,\mathbf{1}(t) \mapsto \frac{a}{s^2+a^2}$
$\cos(at)\,\mathbf{1}(t) \mapsto \frac{s}{s^2+a^2}$ $\quad \frac{1}{2\omega^3}[\sin(\omega t) - \omega t\cos(\omega t)]\,\mathbf{1}(t) \mapsto \frac{1}{(s^2+\omega^2)^2}$
**Prop. of Laplace Transform Linearity:**
$\mathcal{L}\{cf(t) + g(t)\} = c\mathcal{L}\{f(t)\} + \mathcal{L}\{g(t)\}$, $c \sim$ constant.
**Differentiation:** If the Laplace transform of $f'(t)$ exists, then $\mathcal{L}\{f'(t)\} = s\mathcal{L}\{f(t)\} - f(0^-)$.
If the Laplace transform of $f^{(n)}(t) := \frac{d^n f}{dt^n}(t)$ exists, then $\mathcal{L}\{f^{(n)}(t)\} = s^n\mathcal{L}\{f(t)\} - \sum_{i=1}^n s^{n-i} f^{(i-1)}(0^-)$.
**Integration:** $\mathcal{L}\left\{\int_0^t f(\tau)d\tau\right\} = \frac{1}{s}\mathcal{L}\{f(t)\}$.
**Convolution:** Let $(f * g)(t) := \int_0^t f(\tau)g(t-\tau)d\tau = \int_0^t f(t-\tau)g(\tau)d\tau$, then $\mathcal{L}\{(f*g)(t)\} = \mathcal{L}\{f(t)\}\mathcal{L}\{g(t)\}$.
**Time Delay:** $\mathcal{L}\{f(t-T)\mathbf{1}(t-T)\} = e^{-Ts}\mathcal{L}\{f(t)\}, T \ge 0$.
**Multiplication by $t$:** $\mathcal{L}\{tf(t)\} = -\frac{d}{ds}[\mathcal{L}\{f(t)\}]$.
**Shift in $s$:** $\mathcal{L}\{e^{at}f(t)\} = \mathcal{L}\{f(t)\}|_{s\to s-a} = F(s-a)$, where $F(s) = \mathcal{L}\{f(t)\}$ & $a$ const.

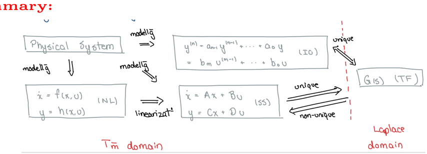
**Trig. Id.** $2\sin(2t) = 2\sin(t)\cos(t)$, $\sin(a-b) = \sin(a)\cos(b) - \cos(a)\sin(b)$, $\cos(a-b) = \cos(a)\cos(b) + \sin(a)\sin(b)$
**Complete the Square:** $ax^2 + bx + c = a(x + \frac{b}{2a})^2 - \frac{b^2}{4a} + c$
**LT Steps:** 1. Write $f(t)$ as a sum and use linearity
*Trig. id. may be useful.
2. Use prop. of LT and common LT to find $F(s)$

**Inverse Laplace Transform** Given $F(s)$, its inverse LT is $f(t) = \mathcal{L}^{-1}\{F(s)\} := \frac{1}{2\pi}\int_{c-j\infty}^{c+j\infty} F(s)e^{st}ds$
$= \lim_{w\to\infty} \frac{1}{2\pi}\int_{c-jw}^{c+jw} F(s)e^{st}ds$, $c \in \mathbb{C}$ is selected s.t. the line $L := \{s \in \mathbb{C} : s = c + j\omega, \omega \in \mathbb{R}\}$ is inside the ROC of $F(s)$.
**Zero:** $z \in \mathbb{C}$ is a zero of $F(s)$ if $F(z) = 0$.
**Pole:** $p \in \mathbb{C}$ is a pole of $F(s)$ if $\frac{1}{F(p)} = 0$.
**Cauchy's Residue THM** If $F(s)$ is analytic (complex diff.) everywhere except at isolated poles $\{p_1, \dots, p_N\}$, then $\mathcal{L}^{-1}\{F(s)\} = \sum_{i=1}^N \text{Res}\left[F(s)e^{st}, s = p_i\right]\mathbf{1}(t)$,
*Res$[F(s)e^{st}, s = p_i]$: Residue of $F(s)e^{st}$ at $s = p_i$.
**Residue Computation** Let $G(s)$ be a complex analytic fcn w/ a pole at $s = p$, $r$ be the multiplicity of the pole $p$. Then
Res$[G(s), s = p] = \frac{1}{(r-1)!}\lim_{s\to p}\frac{d^{r-1}}{ds^{r-1}}[G(s)(s-p)^r]$.
**Inv. LT Partial Frac.:** 1. Factorize $F(s)$ into partial fractions.
2. Find coefficients and use LT table to find inverse LT.
*Complete the square.
**Inv. LT Residue:** 1. Find poles of $F(s)$ and their residues.
2. Use Cauchy's Residue THM to find inverse LT.
*Note: Complex Conjugate (CC) poles → CC residues (use Euler).
**Transfer Function:** Consider a CS in IO form. Assume zero initial conds. $y(0) = \cdots = \frac{d^{(n-1)}y}{dt^{(n-1)}}(0) = 0$ and $u(0) = \cdots = \frac{d^{(m-1)}u}{dt^{(m-1)}}(0) = 0$. Then the TF from $u$ to $y$ is
$G(s) := \frac{y(s)}{U(s)} = \frac{b_m s^m + \cdots + b_0}{s^n + a_{n-1}s^{n-1} + \cdots + a_0}$.
***0 Ini. Conds.:** $y_0(s) = G(s)u(s)$
***∅ Ini. Conds.:** $y_\emptyset(s) = y_0(s) + \frac{\text{poly. based on initial conds.}}{s^n + a_{n-1}s^{n-1} + \cdots + a_0}$

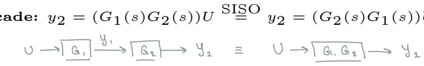
**TF Steps (IO to TF):** 1. Given IO form of CS, assume zero initial conds.
2. Find $G(s)$ by taking LT of IO form and forming $Y(s)/U(s)$.
*Careful: $Y(s)/U(s) = G(s)$ not $U(s)/Y(s) = G(s)$.
**Impulse Response:** Given CS modeled by TF $G(s)$, its IR is $g(t) := \mathcal{L}^{-1}\{G(s)\}$.
*$\mathcal{L}\{\delta(t)\} = 1$, then if $u(t) = \delta(t)$, then $Y(s) = U(s)G(s) = G(s)$.
**SS to TF:** $G(s) = C(sI - A)^{-1}B + D$ s.t. $y(s) = G(s)U(s)$.
*Assume $x(0) = 0 \in \mathbb{R}^n$ (zero initial conds.).
***LTI:** $G(s)$ of an LTI system is always a rational fcn.
***Not Invertible:** Values of $s$ s.t. $sI - A$ not invertible can correspond to poles of $G(s)$.
**Inverse:** 1. For $A \in \mathbb{R}^{n\times n}$, find $[\text{cof}(A)]_{(i,j)} = (-1)^{i+j}\det(A_{(i,j)})$.
*$A_{(i,j)}$: $A$ w/ row $i$ and col. $j$ removed.
2. Assemble cof$(A)$ and find $\det(A) = \sum_{j=1}^n a_{ij}[\text{cof}(A)]_{(i,j)}$ w/ fixed $i$ or $\det(A) = \sum_{i=1}^n a_{ij}[\text{cof}(A)]_{(i,j)}$ w/ fixed $j$.
3. Find $A^{-1} = \frac{1}{\det(A)}\text{adj}(A) = \frac{1}{\det(A)}[\text{cof}(A)]^T$.
*$2 \times 2$: $A^{-1} = \frac{1}{\det(A)}\begin{bmatrix} d & -b \\ -c & a \end{bmatrix}$
**TF (SS to TF):** 1. Given SS form, assume zero initial conds.
2. Solve $G(s) = C(sI - A)^{-1}B + D$.
*If $C = [0\ \cdot\ 1_i\ \cdot\ 0]$ & $B = [0\ \cdot\ 1_j\ \cdot\ 0]$, then only need ith row & jth col. of adj$(sI - A)$ s.t. $G(s) = \frac{[\text{adj}(sI-A)]_{(i,j)}}{\det(sI-A)} + D$.
*Multiple $i, j$ non-zero entries: Work it out using MM.
**TF to SS:** Consider $G(s) = \frac{b_m s^m + \cdots + b_0}{s^n + a_{n-1}s^{n-1} + \cdots + a_0} = \frac{N(s)}{D(s)}$, where $m < n$ (i.e. $G(s)$ is strictly proper). Then the SS form is

$$*A = \begin{bmatrix} 0 & 1 & 0 & \cdots & 0 \\ 0 & 0 & 1 & \cdots & 0 \\ \vdots & \vdots & \vdots & \ddots & \vdots \\ 0 & 0 & 0 & 0 & 1 \\ -a_0 & -a_1 & -a_2 & \cdots & -a_{n-1} \end{bmatrix}, \quad B = \begin{bmatrix} 0 \\ \vdots \\ 0 \\ 1 \end{bmatrix},$$

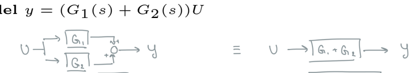
$C = [b_0 \ \cdots \ b_m \ | \ 0 \ \cdots \ 0]$, $D = 0$.
***Unique:** State space of a TF is not unique.
**Summary:**



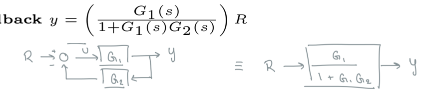

**Block Diagram Types of Blocks:**
**Cascade:** $y_2 = (G_1(s)G_2(s))U \overset{\text{SISO}}{=} y_2 = (G_2(s)G_1(s))U$



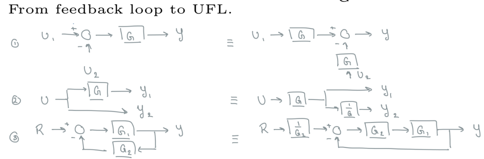
**Parallel** $y = (G_1(s) + G_2(s))U$



**Feedback** $y = \left(\frac{G_1(s)}{1 + G_1(s)G_2(s)}\right)R$

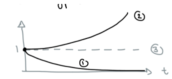


***SC:** Unity Feedback Loop (UFL) if $G_2(s) = 1$.
**Manipulations:** 1. $y = G(U_1 - U_2) = GU_1 + GU_2$
2. $y_1 = GU \quad y_2 = U$ | $y_1 = GU \quad y_2 = G\frac{1}{G}U$
3. From feedback loop to UFL.

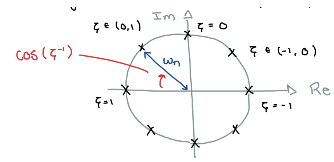


**Find TF from Block Diagram:** 1. Start from in → out, making simplifications using block diagram rules.
2. Simplify until you get the form $U(s) \to \boxed{G(s)} \to Y(s)$.
**Time Response of Elementary Terms:** $\mathbf{1}(t) \leftarrow$ pole @ 0
$t^n\mathbf{1}(t) \leftarrow$ pole @ 0 w/ mult. $n$ | $e^{at}\mathbf{1}(t) \leftarrow$ pole @ $a$
$\sin(\omega t + \phi)\mathbf{1}(t) \leftarrow$ pole @ $\pm j\omega$ | $\cos(\omega t + \phi)\mathbf{1}(t) \leftarrow$ pole @ $\pm j\omega$

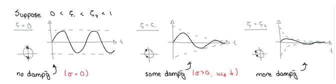
**Real Pole:** $y(s) = \frac{1}{s+a}$, real pole at $s = -a$, then $y(t) = e^{-at}\mathbf{1}(t)$
1. $a > 0 \implies \lim_{t\to\infty} y(t) = 0$ | 2. $a < 0 \implies \lim_{t\to\infty} y(t) = \infty$.
3. $a = 0 \implies y(t) = \mathbf{1}(t)$ is constant.



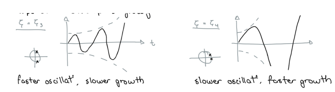
**Time Constant:** $\tau = \frac{1}{a}$ of the pole $s = -a$ for $a > 0$
**Pair of Comp. Conj. Poles:**
$y(s) = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} = \frac{\omega_n^2}{(s+\sigma)^2 + \omega_d^2}$, $|\zeta| < 1$, then
$y(t) = \frac{\omega_n}{\sqrt{1-\zeta^2}}e^{-\sigma t}\sin(\omega_d t)\mathbf{1}(t)$
*Poles: $s_{1,2} = -\zeta\omega_n \pm j\omega_n\sqrt{1-\zeta^2} = -\sigma \pm j\omega_d$
*$\zeta = \frac{\sigma}{\omega_n}$: Damping ratio (or damping coefficient)
*$\sigma = \zeta\omega_n$: Decay/growth rate | $\omega_d$: Freq. of oscillation
*$\omega_n = \sqrt{\sigma^2 + \omega_d^2}\left[\frac{\text{radians}}{\text{seconds}}\right]$: Undamped natural freq.
*$\omega_d = \omega_n\sqrt{1-\zeta^2}\left[\frac{\text{radians}}{\text{seconds}}\right]$: Damped natural freq.
*$|s_{1,2}|^2 = \omega_n^2$: Mag. of poles is $\omega_n$.
*$\cos^{-1}(\zeta)$: Angle of $s_1$ on complex plane CW from -ve Re axis.



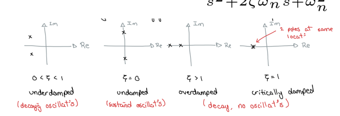

**Damping Ratio Effect:** $0 < \zeta_1 < \zeta_2 < 1$, then



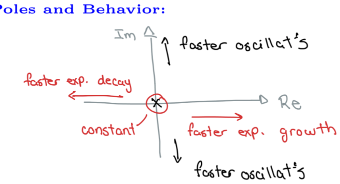

$-1 < \zeta_4 < \zeta_3 < 0$, then $\sigma = \zeta\omega_n < 0$, (exp. envelop ↑)



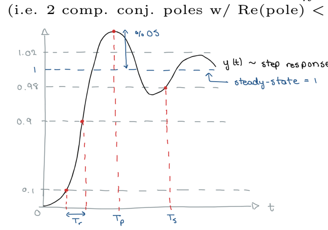

**Class. of 2nd Order Sys.:** $y(s) = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$, w/ $|\zeta| < 1$




**Loc. of Poles and Behavior:**



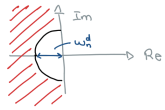

**Control Spec. of 2nd Order Sys.: Step Response:** Given a TF $G(s)$, its SR is $y(t)$ resulting from applying the input $u(t) = \mathbf{1}(t)$, i.e. $\mathcal{L}^{-1}\left\{G(s)\frac{1}{s}\right\}$.
**Control Spec.** A control spec. is a criterion specifiying how we would like a CS to behave.
**2nd Order Sys. Metrics:** $G(s) = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$ w/ $U(s) = \frac{1}{s}$
*$0 < \zeta < 1$ (i.e. 2 comp. conj. poles w/ Re(pole) < 0).



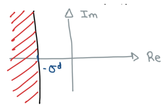

**Rise Time (RT):** $T_r$ is the time it takes $y(t)$ to go from 10% to 90% of its steady-state value.
**RT:** 1. Find $t_1 > 0$ s.t. $y(t_1) = 0.1$, $t_2 > 0$ s.t. $y(t_2) = 0.9$.
3. Compute $T_r = t_2 - t_1$. $\boxed{T_r \approx \frac{1.8}{\omega_n}}$.
**Settling Time (ST):** $T_s$ is the time required to reach and stay w/in 2% of the steady-state value.
**ST:** 1. Find when it's first that $|y(t) - 1| \le 0.02$. $\boxed{T_s \approx \frac{4}{\zeta\omega_n}}$.
**Peak Time:** $T_p$ is time req'd to reach the max (peak) value.
**Peak Time:** 1. Find the first time when $\dot{y}(t) = 0$.
* $\boxed{T_p = \frac{\pi}{\omega_d} = \frac{\pi}{\omega_n\sqrt{1-\zeta^2}}}$
**% Overshoot:** $\%OS = \frac{[\text{peak value}] - [\text{steady-state value}]}{[\text{steady-state value}]} \times 100\%$
*% OS = OS × 100%.
* $\boxed{\%OS = \exp\left(-\frac{\pi\zeta}{\sqrt{1-\zeta^2}}\right) \iff \zeta = \frac{-\ln(\text{OS})}{\sqrt{\pi^2 + (\ln(\text{OS}))^2}}}$.

**Transient Performance Sat.:** Given performance spec. $T_r \le T_r^d$, $T_s \le T_s^d$, $\text{OS} \le \text{OS}^d$, find loc. of poles of $G(s)$.
*Admissible region for the poles of $G(s)$ s.t. the step response meets all three spec. is the intersection of the above three regions.

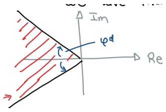
**Rise Time:** $T_r \approx \frac{1.8}{\omega_n} \le T_r^d \overset{\text{app.}}{\Longleftrightarrow} \omega_n \ge \frac{1.8}{T_r^d} \equiv \omega_n^d$



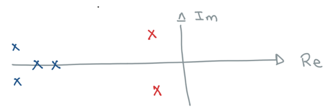

**Settling Time:** $T_s \approx \frac{4}{\zeta\omega_n} = \frac{4}{\sigma} \le T_s^d \overset{\text{app.}}{\Longleftrightarrow} \sigma \ge \frac{4}{T_s^d} \equiv \sigma^d$




**OS:** $\exp\left(\frac{-\pi\zeta}{\sqrt{1\text{-}\zeta^2}}\right) \le \text{OS}^d \overset{\text{app.}}{\Longleftrightarrow} \zeta \ge \frac{-\ln(\text{OS}^d)}{\sqrt{\pi^2+(\ln(\text{OS}^d))^2}} \equiv \zeta^d$




**Add. Poles & Zeros:** The analysis remains approx. correct under the following assumptions:
1. Any add. poles of $G(s)$ have much more -ve real part (5-10 times) than the real part of the dom. complex conjugate poles.




*dominant poles, additional poles.
2. Real part of zeros are -ve & very diff. from the real part of the two dom. poles.

**Internal Stablity:** $\dot{x} = Ax$ is
1. **Stable** if $\forall x(0) \in \mathbb{R}^n$, the soln. $x(t)$ is bdd; that is, $\exists M > 0$ s.t. $\|x(t)\| \le M\ \forall t \ge 0$.
2. **Asymp. Stable** if it's stable & $\forall x(0) \in \mathbb{R}^n$, the soln. $x(t)$ converges to the origin; that is, $\lim_{t\to\infty} x(t) = 0$.
3. **Unstable** if it's not stable; that is, $\exists x(0) \in \mathbb{R}^n$ s.t. $x(t)$ is not bdd.

**Asymptotic Stablity Thm.** $\dot{x} = Ax$ is A.S. iff $\text{eig}(A) \subseteq \mathbb{C}^- \equiv \{s \in \mathbb{C} \mid \text{Re}(s) < 0\}$, i.e. open left half plane (OLHP).
**Instability Thm.** If $\exists$ an eigenvalue $\lambda$ of $A$ w/ $\text{Re}(\lambda) > 0$, then $\dot{x} = Ax$ is unstable.
**Fact:** Zeros of $s^2 + a_1 s + a_0$ are in $\mathbb{C}^-$ iff $a_1, a_0 > 0$.
**Internal Stability** 1. Linearize around $(\bar{x}, \bar{u})$ w/ $\bar{u} = 0$.
2. Find $A$ and determine $\text{eig}(A) = \lambda$ s.t. $\det(sI - A) = 0$.
3. Check if $\text{eig}(A) \subseteq \mathbb{C}^- \mid \text{Re}(\text{eig}(A)) > 0$.
**BIBO Stability:** An LTI system w/ 0 i.c. is Bounded Input Bounded Output (BIBO) stable if for any bdd input $u(t)$, the output $y(t)$ is also bdd.
**BIBO Unstable:** An LTI system w/ 0 i.c. is BIBO unstable if it's not BIBO stable; that is, $\exists$ a bdd $u(t)$ s.t. $y(t)$ is not bdd.
**BIBO Stable Thm.** A system $y(s) = G(s)U(s)$ is BIBO stable iff $\text{poles}(G(s)) \subseteq \mathbb{C}^-$.
**Lemma:** If $p$ is a pole of $G(s)$, then $p$ is an $\text{eig}(A)$. I.e. $\text{poles}(G(s)) := \{p \in \mathbb{C} \mid p \text{ is a pole of } G(s)\} \subseteq \text{eig}(A)$.
***Pole-0 Cancellation:** $\text{eige}(A)$ need not be a pole of $G(s)$.
**Thm.** If $\text{eig}(A) \subseteq \mathbb{C}^-$, then $\forall B, C, D$ the TF $G(s)$ is BIBO stable. That is, internal asymptotic stability $\Rightarrow$ BIBO stability.
**BIBO Stability** 1. Find $G(s)$ from SS form and determine poles.
2. Check if $\text{poles}(G(s)) \subseteq \mathbb{C}^-$. 1. Check if $\text{eig}(A) \subseteq \mathbb{C}^-$ since internal asymptotic stability $\Rightarrow$ BIBO stability.
**Routh-Hurwitz:** Consider $a(s) = s^n + a_{n-1}s^{n-1} + \cdots + a_0$.

| | | | | | | |
|---|---|---|---|---|---|---|
| $*s^n$ | 1 | $a_{n-2}$ | $a_{n-4}$ | $a_{n-6}$ | $\cdots$ | 0 |
| $*s^{n-1}$ | $a_{n-1}$ | $a_{n-3}$ | $a_{n-5}$ | $a_{n-7}$ | $\cdots$ | 0 |
| $*s^{n-2}$ | $b_1$ | $b_2$ | $b_3$ | $\cdots$ | | |
| $*s^{n-3}$ | $c_1$ | $c_2$ | $\cdots$ | | | |
| $\vdots$ | | | | | | |
| $*s$ | $*$ | 0 | | | | |
| $*1$ | $*$ | 0 | | | | |

$b_1 = -\frac{1}{a_{n-1}} \det \begin{bmatrix} 1 & a_{n-2} \\ a_{n-1} & a_{n-3} \end{bmatrix}$ $b_2 = -\frac{1}{a_{n-1}} \det \begin{bmatrix} 1 & a_{n-4} \\ a_{n-1} & a_{n-5} \end{bmatrix}$

$b_3 = -\frac{1}{a_{n-1}} \det \begin{bmatrix} 1 & a_{n-6} \\ a_{n-1} & a_{n-7} \end{bmatrix}$ $c_1 = -\frac{1}{b_1} \det \begin{bmatrix} a_{n-1} & a_{n-3} \\ b_1 & b_2 \end{bmatrix}$

$c_2 = -\frac{1}{b_1} \det \begin{bmatrix} a_{n-1} & a_{n-5} \\ b_1 & b_3 \end{bmatrix}$

**Routh-Hurwitz Stability Criterion:** The roots of $a(s)$ are in $\mathbb{C}^-$ iff the 1st col of Routh array has no sign changes. The # of sign changes is equal to the # of roots of $a(s) \in \mathbb{C}^+ := \{s \in \mathbb{C} : \text{Re}(s) > 0\}$.
*If 1st element of a row is 0, Rooth array cannot be completed.
**FVT v1:** Suppose $Y(s) = \mathcal{L}\{y(t)\}$ is a proper rational fcn. If $y(\infty) := \lim_{t\to\infty} y(t)$ exists and is finite, then $y(\infty) = \lim_{s\to 0} sY(s)$
**FVT v2:** Suppose $Y(s) = \mathcal{L}\{y(t)\}$ is a proper rational fcn. Moreover, suppose either:
1. $\text{poles}(Y(s)) \subseteq \mathbb{C}^-$
2. $Y(s)$ has only one pole at $s = 0$ and all other poles are in $\mathbb{C}^-$.
Then $y(\infty) := \lim_{t\to\infty} y(t)$ exists and is finite and satisfies $y(\infty) = \lim_{s\to 0} sY(s)$.
**FVT** 1. Does $y(\infty)$ exist? Check if pole at $s = 0$, then compute Rooth Array to see if poles are in $\mathbb{C}^-$.
2. Compute $\lim_{s\to 0} sY(s)$ if it exists.