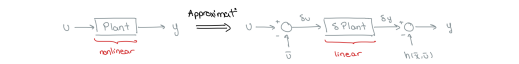


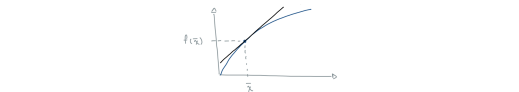
Modeling CS: control input, y : plant output
State variable CS is in state variable form if
 $\dot{x}_1 = f_1(t, x_1, \dots, x_n, u), \dots, \dot{x}_n = f_n(t, x_1, \dots, x_n, u)$
 $y = h(t, x_1, \dots, x_n, u)$ is a collection of n 1st order ODEs.
Time-Invariant (TI) CS is TI if $f_i(\cdot)$ does not 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 $\dot{x} = Ax + Bu, y = Cx + Du$
 $A \in \mathbb{R}^{n \times n}, B \in \mathbb{R}^{n \times m}, C \in \mathbb{R}^{p \times n}, D \in \mathbb{R}^{p \times m}$
 $*A = \mathbb{R}^{n \times n}, B \in \mathbb{R}^{n \times m}, C \in \mathbb{R}^{p \times n}, D \in \mathbb{R}^{p \times m}$
 $*SISO: p = 1, m = 1$
 $*x(t) \in \mathbb{R}^n, u(t) \in \mathbb{R}, y(t) \in \mathbb{R}^p$.
Input-Output (IO) LTI CS is in IO form if
 $\frac{d^n y}{dt^n} + a_{n-1} \frac{d^{n-1} y}{dt^{n-1}} + \dots + a_1 \frac{dy}{dt} + a_0 y = b_m \frac{d^m u}{dt^m} + \dots + b_1 \frac{du}{dt} + b_0 u$
 $*m \leq n$ (causality)
IO to SS Model 1. Define x s.t. highest order derivative in \dot{x}
 2.1 If LTI, then
 $*Write \dot{x} = Ax + Bu = f(x, u)$ by isolating for components of \dot{x}
 $*Write y = Cx + Du = h(x, u)$ by setting measurement output y to component of x
 2.2 If not LTI, then
 $*Write \dot{x} = f(x, u)$ by isolating for components of \dot{x}
 $*Write y = h(x, u)$ 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 $y(t) = y_d \forall t \geq 0$.

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 $x(t) = \bar{x} \forall t \geq 0$ (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 $(x, u) = (\bar{x}, \bar{u})$.
 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 $\delta x = x - \bar{x}, \delta u = u - \bar{u}, \delta y = y - h(\bar{x}, \bar{u})$ $\delta \dot{x} = \dot{x} - f(\bar{x}, \bar{u})$ w/
 $\delta \dot{x} = A\delta x + B\delta u, A = \frac{\partial f(\bar{x}, \bar{u})}{\partial x} \in \mathbb{R}^{n_1 \times n_1}, B = \frac{\partial f(\bar{x}, \bar{u})}{\partial u} \in \mathbb{R}^{n_1, 1},$
 $\delta y = C\delta x + D\delta u, C = \frac{\partial h(\bar{x}, \bar{u})}{\partial x} \in \mathbb{R}^{1 \times n_1}, D = \frac{\partial h(\bar{x}, \bar{u})}{\partial u} \in \mathbb{R}$
 $*Only valid at equ. pairs.$

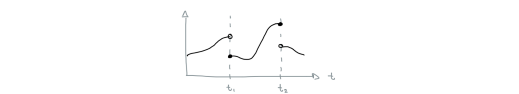


Linear Approx. Given a diff. fcn. $f: \mathbb{R} \rightarrow \mathbb{R}$, its linear approx. at \bar{x} is $f_{lin} = f(\bar{x}) + f'(\bar{x})(x - \bar{x})$.
 $*Remainder$ Thm: $f(x) = f_{lin} + r(x)$ where $\lim_{x \rightarrow \bar{x}} \frac{r(x)}{x - \bar{x}} = 0$.

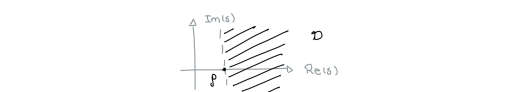


$*Note:$ Can provide a good approx. near \bar{x} but not globally.
 $*Gen. f: \mathbb{R}^{n_1} \rightarrow \mathbb{R}^{n_2}, f(x) = f(\bar{x}) + \frac{\partial f}{\partial x}(\bar{x})(x - \bar{x}) + R(x)$
 $*Jacobian: \frac{\partial f}{\partial x}(x) = \begin{bmatrix} \frac{\partial f}{\partial x_1} & \dots & \frac{\partial f}{\partial x_{n_1}} \end{bmatrix}(\bar{x}) \in \mathbb{R}^{n_2 \times n_1}$
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 $\delta \dot{x} = A\delta x + B\delta u$ and $\delta y = C\delta x + D\delta u$

Laplace Transform Given a fcn $f: \mathbb{R}_+ = [0, \infty) \rightarrow \mathbb{R}$, its Laplace transform is $F(s) = \mathcal{L}\{f(t)\} := \int_0^\infty f(t)e^{-st} dt, s \in \mathbb{C}$.
 $*\mathcal{L}: f(t) \mapsto F(s), t \in \mathbb{R}_+ \text{ (time dom.)} \ \& \ s \in \mathbb{C} \text{ (Laplace dom.)}.$
P.W. CTS: A fcn $f: \mathbb{R}_+ \rightarrow \mathbb{R}^n$ 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 $\lim_{t \rightarrow t_i^+} f(t), \lim_{t \rightarrow t_i^-} f(t)$ are finite.



Exp. Order A function $f: \mathbb{R}_+ \rightarrow \mathbb{R}^n$ is of **exp. order** if \exists constants $K, \rho, T > 0$ s.t. $\|f(t)\| \leq Ke^{\rho t}, \forall t \geq T$.
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 $1(t) := \begin{cases} 1, & \text{if } t \geq 0 \\ 0, & \text{otherwise} \end{cases}$
Table of Common Laplace Transforms: $f(t) \mapsto F(s)$
 $1(t) \mapsto \frac{1}{s}, t1(t) \mapsto \frac{1}{s^2}, t^k 1(t) \mapsto \frac{k!}{s^{k+1}}, e^{at} 1(t) \mapsto \frac{1}{s-a}, t^n e^{at} 1(t) \mapsto \frac{n!}{(s-a)^{n+1}}, \sin(at) 1(t) \mapsto \frac{a}{s^2+a^2}, \cos(at) 1(t) \mapsto \frac{s}{s^2+a^2}, \frac{1}{2\omega} [\sin(\omega t) - \omega t \cos(\omega t)] 1(t) \mapsto \frac{1}{(s^2+\omega^2)^2}$

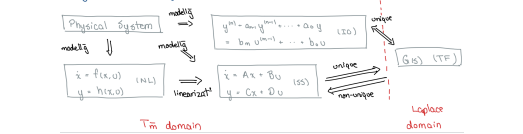
Prop. of Laplace Transform Linearity: $\mathcal{L}\{cf(t) + g(t)\} = c\mathcal{L}\{f(t)\} + \mathcal{L}\{g(t)\}, c \sim \text{constant}.$
Differentiation: If the Laplace transform of $f'(t)$ exists, then $\mathcal{L}\{f'(t)\} = s\mathcal{L}\{f(t)\} - f(0^-)$.
 If the Laplace transform of $f^{(n)}(t)$ 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: $\mathcal{L}\{\int_0^t f(\tau) d\tau\} = \frac{1}{s} \mathcal{L}\{f(t)\}.$
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: $\mathcal{L}\{f(t - T)1(t - T)\} = e^{-Ts} \mathcal{L}\{f(t)\}, T \geq 0$.
Multiplication by t: $\mathcal{L}\{tf(t)\} = -\frac{d}{ds} [\mathcal{L}\{f(t)\}].$
Shift in s: $\mathcal{L}\{e^{at} f(t)\} = \mathcal{L}\{f(t)\}_{s \rightarrow s-a} = F(s - a)$, where $F(s) = \mathcal{L}\{f(t)\}$ & a const.
Trig. Id. $2 \sin(t) = 2 \sin(t) \cos(t), \sin(a - b) = \sin(a) \cos(b) - \cos(a) \sin(b), \cos(a - b) = \cos(a) \cos(b) + \sin(a) \sin(b)$
Complete the Square: $ax^2 + bx + c = a(x + \frac{b}{2a})^2 - \frac{b^2}{4a} + c$

Inverse Laplace Transform Given $F(s)$, its inverse LT is $f(t) = \mathcal{L}^{-1}\{F(s)\} := \frac{1}{2\pi j} \int_{c-j\infty}^{c+j\infty} F(s)e^{st} ds$
 $= \lim_{w \rightarrow \infty} \frac{1}{2\pi j} \int_{c-jw}^{c+jw} F(s)e^{st} ds, c \in \mathbb{C}$ 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 $\mathcal{L}^{-1}\{F(s)\} = \sum_{i=1}^N \text{Res}[F(s)e^{st}, s = p_i] 1(t),$
 $*\text{Res}[F(s)e^{st}, s = p_i]:$ 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 $\text{Res}[G(s), s = p] = \frac{1}{(r-1)!} \lim_{s \rightarrow p} \frac{d^{r-1}}{ds^{r-1}} [G(s)(s - p)^r].$
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 \rightarrow CC residues (use Euler).
 $*\cos(x) = \frac{e^{jx} + e^{-jx}}{2}, \sin(x) = \frac{e^{jx} - e^{-jx}}{2j}$
Transfer Function: Consider a CS in IO form. Assume zero initial conds. $y(0) = \dots = \frac{d^{(m-1)} y}{dt^{(m-1)}}(0) = 0$ and $u(0) = \dots = \frac{d^{(m-1)} u}{dt^{(m-1)}}(0) = 0$. Then the TF from u to y is $G(s) := \frac{Y(s)}{U(s)} = \frac{b_m s^m + \dots + b_0}{s^n + a_{n-1} s^{n-1} + \dots + a_0}.$
 $*0$ Ini. Conds.: $y_0(s) = G(s)u(s)$
 $*\emptyset$ Ini. Conds.: $y_\emptyset(s) = y_0(s) + \frac{\text{poly. based on initial conds.}}{s^n + a_{n-1} s^{n-1} + \dots + a_0}.$

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. $y(s) = G(s)U(s)$.
 $*Assume u(0) = 0 \in \mathbb{R}^n$ (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 $\text{cof}(A)$ 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 $A^{-1} = \frac{1}{\det(A)} \text{adj}(A) = \frac{1}{\det(A)} [\text{cof}(A)]^T.$
 $*2 \times 2: A^{-1} = \frac{1}{\det(A)} \begin{bmatrix} d & -b \\ -c & a \end{bmatrix}$

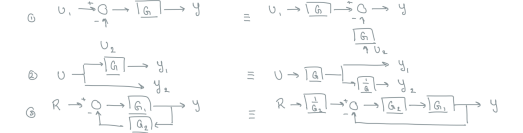
TF (SS to TF): 1. Given SS form, assume zero initial conds.
 2. Solve $G(s) = C(sI - A)^{-1}B + D$.
 $*If C = [0 \ \dots \ 1 \ \dots \ 0]$ & $B = [0 \ \dots \ 1 \ \dots \ 0]$, then only need i th row & j th col. of $\text{adj}(sI - A)$ s.t. $G(s) = \frac{[\text{adj}(sI - A)]_{(i,j)}}{\det(sI - A)} + D$.
 $*Multiple i, j$ non-zero entries: Work it out using MM.

TF to SS: Consider $G(s) = \frac{b_m s^m + \dots + b_0}{s^n + a_{n-1} s^{n-1} + \dots + a_0} = \frac{N(s)}{D(s)},$ where $m < n$ (i.e. $G(s)$ is strictly proper). Then the SS form is $A = \begin{bmatrix} 0 & 1 & 0 & \dots & 0 \\ 0 & 0 & 1 & \dots & 0 \\ \vdots & \vdots & \vdots & \ddots & \vdots \\ 0 & 0 & 0 & \dots & 1 \\ -a_0 & -a_1 & -a_2 & \dots & -a_{n-1} \end{bmatrix}, B = \begin{bmatrix} 0 \\ \vdots \\ 0 \\ 1 \end{bmatrix}, C = [b_0 \ \dots \ b_m \ 0 \ \dots \ 0], D = 0.$
 $*Unique:$ State space of a TF is not unique.
Summary:



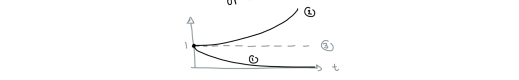
Block Diagram Types of Blocks:
Cascade: $y_2 = (G_1(s)G_2(s))U \stackrel{\text{SISO}}{=} y_2 = (G_2(s)G_1(s))U$
 $U \mapsto \boxed{G_1} \xrightarrow{y_1} \boxed{G_2} \xrightarrow{y_2} \dots$
Parallel $y = (G_1(s) + G_2(s))U$
 $U \mapsto \boxed{G_1} \xrightarrow{y_1} \dots \xrightarrow{y_2} \boxed{G_2} \xrightarrow{y_2} y$
Feedback $y = \left(\frac{G_1(s)}{1 + G_1(s)G_2(s)} \right) R$
 $R \mapsto \boxed{G_1} \xrightarrow{y_1} \boxed{G_2} \xrightarrow{y_2} y$
 $R \mapsto \boxed{G_1} \xrightarrow{y_1} \boxed{G_2} \xrightarrow{y_2} y$

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

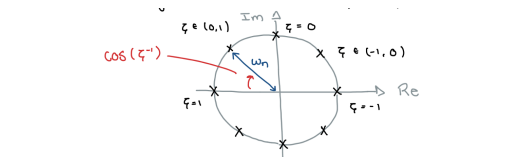


Find TF from Block Diagram: 1. Start from in \rightarrow out, making simplifications using block diagram rules.
 2. Simplify until you get the form $U(s) \rightarrow \boxed{G(s)} \rightarrow Y(s)$.
Time Response of Elementary Terms: $1(t) \leftarrow$ pole @ 0
 $t^n 1(t) \leftarrow$ pole @ 0 w/ mult.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

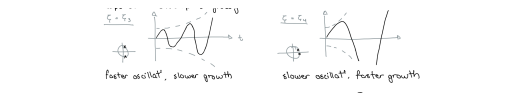
Real Pole: $y(s) = \frac{1}{s+a}$, real pole at $s = -a$, then $y(t) = e^{-at} 1(t)$
 1. $a > 0 \implies \lim_{t \rightarrow \infty} y(t) = 0 \mid 2. a < 0 \implies \lim_{t \rightarrow \infty} y(t) = \infty$
 3. $a = 0 \implies y(t) = 1(t)$ is constant.



Time Constant: $\tau = \frac{1}{a}$ of the pole $s = -a$ for $a > 0$
Pair of Comp. Conj. Poles:
 $y(s) = \frac{\omega_d^2}{s^2 + 2\zeta\omega_n s + \omega_n^2} = \frac{\omega_d^2}{(s + \sigma)^2 + \omega_d^2}, |\zeta| < 1$, then $y(t) = \frac{\omega_n}{\sqrt{1 - \zeta^2}} e^{-\sigma t} \sin(\omega_d t) 1(t)$
 $*Poles: s_{1,2} = -\zeta\omega_n \pm j\omega_n \sqrt{1 - \zeta^2} = -\sigma \pm j\omega_d$
 $*\zeta = \frac{\sigma}{\omega_n}$: Damping ratio (or damping coefficient)
 $*\sigma = \zeta\omega_n$: Decay/growth rate $\mid \omega_d$: 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 ω_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 \uparrow)
 Graphs showing the effect of damping ratio on the step response: underdamped (oscillatory), critically damped (fastest non-oscillatory), overdamped (slowest non-oscillatory).

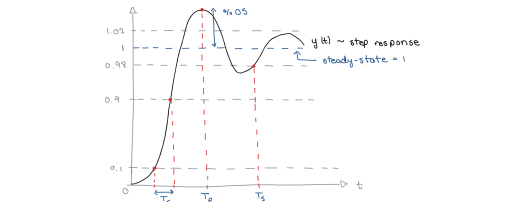


Class. of 2nd Order Sys.: $y(s) = \frac{\omega_n^2}{s^2 + 2\zeta\omega_n s + \omega_n^2}$, w/ $|\zeta| < 1$
 Graphs showing the effect of damping ratio on the step response: underdamped (oscillatory), critically damped (fastest non-oscillatory), overdamped (slowest non-oscillatory).

Loc. of Poles and Behavior:
 Graph showing the location of poles in the complex plane and the resulting system behavior: faster oscillat'ns, faster exp. decay, constant, faster exp. growth, faster oscillat'ns.

Control Spec. of 2nd Order Sys.: Step Response: Given a TF $G(s)$, its SR is $y(t)$ resulting from applying the input $u(t) = 1(t)$, i.e. $\mathcal{L}^{-1}\{G(s)\frac{1}{s}\}.$
Control Spec. A control spec. is a criterion specifying 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).



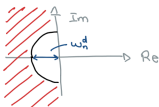
Rise Time (RT): T_r is the time it takes $y(t)$ to go from 10% to 90% of its steady-state value.
RT: 1. Find $t_1 > 0$ s.t. $y(t_1) = 0.1, t_2 > 0$ s.t. $y(t_2) = 0.9$.
 3. Compute $T_r = t_2 - t_1, T_r \approx \frac{1.8}{\omega_n}.$
Settling Time (ST): T_s is the time required to reach and stay w/in 2% of the steady-state value.
ST: 1. Find when it's first that $|y(t) - 1| \leq 0.02. T_s \approx \frac{4}{\zeta\omega_n}.$

Peak Time: T_p is time req'd to reach the max (peak) value.
Peak Time: 1. Find the first time when $\dot{y}(t) = 0$.
 $*T_p = \frac{\pi}{\omega_d} = \frac{\pi}{\omega_n \sqrt{1 - \zeta^2}}.$
% Overshoot: $\%OS = \frac{[\text{peak value}] - [\text{steady-state value}]}{[\text{steady-state value}]} \times 100\%$
 $*\%OS = OS \times 100\%.$
 $*OS = \exp\left(-\frac{\pi\zeta}{\sqrt{1 - \zeta^2}}\right) \iff \zeta = \frac{-\ln(OS)}{\sqrt{\pi^2 + (\ln(OS))^2}}.$

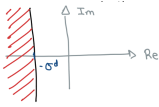
LT Steps: 1. Write $f(t)$ as a sum and use linearity
*Trig. id. may be useful.
2. Use prop. of LT and common LT to find $F(s)$

Transient Performance Sat.: Given performance spec. $T_r \leq T_r^d, T_s \leq T_s^d, OS \leq OS^d$, 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.

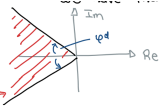
Rise Time: $T_r \approx \frac{1.8}{\omega_n} \leq T_r^d \stackrel{\text{APP}}{\Leftrightarrow} \omega_n \geq \frac{1.8}{T_r^d} \equiv \omega_n^d$



Settling Time: $T_s \approx \frac{4}{\zeta \omega_n} = \frac{4}{\sigma} \leq T_s^d \stackrel{\text{APP}}{\Leftrightarrow} \sigma \geq \frac{4}{T_s^d} \equiv \sigma^d$



OS: $\exp\left(\frac{-\pi \zeta}{\sqrt{1-\zeta^2}}\right) \leq OS^d \stackrel{\text{APP}}{\Leftrightarrow} \zeta \geq \frac{-\ln(OS^d)}{\sqrt{\pi^2 + (\ln(OS^d))^2}} \equiv \zeta^d$



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 Stability: $\dot{x} = Ax$ is

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

Asymptotic Stability 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 λ of A w/ $\text{Re}(\lambda) > 0$, then $\dot{x} = Ax$ is unstable.

Fact: Zeros of $s^2 + a_1s + a_0$ 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 $\text{eig}(A) \subseteq \mathbb{C}^-$ for asymptotic stability

4. Check if $\text{Re}(\text{eig}(A)) > 0$ for instability.

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 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:** $\text{eig}(A)$ 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 $a(s) = s^n + a_{n-1}s^{n-1} + \dots + a_0$.

* s^n | 1 a_{n-2} a_{n-4} a_{n-6} \dots 0

* s^{n-1} | a_{n-1} a_{n-3} a_{n-5} a_{n-7} \dots 0

* s^{n-2} | b_1 b_2 b_3 \dots

* s^{n-3} | c_1 c_2 \dots

.

.

* 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, Routh array cannot be completed.

FVT v1: Suppose $Y(s) = \mathcal{L}\{y(t)\}$ is a proper rational fcn. If $y(\infty) := \lim_{t \rightarrow \infty} y(t)$ exists and is finite, then $y(\infty) = \lim_{s \rightarrow 0} sY(s)$

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 $y(\infty) := \lim_{t \rightarrow \infty} y(t)$ exists and is finite and satisfies $y(\infty) = \lim_{s \rightarrow 0} sY(s)$.

FVT 1. Does $y(\infty)$ exist? Check if pole at $s = 0$, then compute

Routh Array to see if poles are in \mathbb{C}^- .

2. Compute $\lim_{s \rightarrow 0} sY(s)$ if it exists.