

Lista 4 - CMC-12

$$\begin{aligned} Q1) F(s) &= \frac{3s+5}{s^3+4s^2+5s+2} = \frac{3(s+2)-1}{(s+1)^2(s+2)} \\ &= \frac{3}{(s+1)^2} - \frac{1}{(s+1)^2(s+2)} = \frac{3}{(s+1)^2} + A \end{aligned}$$

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

$$F(s) = \frac{3}{(s+1)^2} + \frac{\overbrace{s}^{(s+1)-1}}{(s+1)^2} - \frac{1}{(s+2)}$$

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

$$\mathcal{L}^{-1}(F(s)) = f(t) = 2 \cdot t \cdot e^{-t} + e^{-t} - e^{-2t}$$

$$f(t) = (1+2t) \cdot e^{-t} - e^{-2t}$$

$$Q2) \ddot{x} + 6\dot{x} + 18x = 18 \cdot 1(t), \quad x(0) = 1 \text{ e } \dot{x}(0) = 3$$

$$\ddot{x} = \mathcal{L}^2 X(s) - s x(0) - \dot{x}(0) = \mathcal{L}^2 X(s) - s - 3$$

$$\dot{x} = s X(s) - x(0) = s X(s) - 1$$

$$\text{Logo: } \mathcal{L}^2 X(s) - s - 3 + 6s X(s) - 6 + 18 X(s) = 18 \cdot \frac{1}{s}$$

$$X(s) [s^2 + 6s + 18] = s + 9 + \frac{18}{s} = \frac{s^2 + 9s + 18}{s}$$

$$X(s) = \frac{s^2 + 9s + 18}{s(s^2 + 6s + 18)} = \frac{(s+3)(s+6)}{s[(s+3)^2 + 3^2]}$$

$$X(s) = \frac{(s+3)}{(s+3)^2 + 3^2} + \frac{6}{s} \cdot \frac{(s+3)}{(s+3)^2 + 3^2}$$

$$\mathcal{L}^{-1}\{X(s)\} = x(t) = e^{-3t} \cdot \cos(3t) + 6 \cdot \int_0^t e^{-3\tau} \cdot \cos(3\tau) d\tau$$

$$x(t) = e^{-3t} \cdot \cos(3t) + \left[e^{-3\tau} \sin(3\tau) - e^{-3t} \cos(3\tau) \right]_0^t$$

$$x(t) = 1 + e^{-3t} \cdot \sin(3t)$$

Q3) EDO para o motor elétrico:

$$\begin{cases} L\ddot{i} + Ri + V_b = V(t), \text{ com } V_b = K_t \cdot \omega \\ J\dot{\omega} + b\omega = K_t \cdot i \rightarrow i = \frac{J\dot{\omega} + b\omega}{K_t} \end{cases}$$

$$L \cdot \left(\frac{J\ddot{\omega} + b\dot{\omega}}{K_t} \right) + R \left(\frac{J\dot{\omega} + b\omega}{K_t} \right) + K_t \omega = V(t)$$

$\omega = \dot{\theta} \rightarrow$ Logo, temos a EDO final:

$$\ddot{\ddot{\theta}} + \left(\frac{b}{J} + \frac{R}{L} \right) \ddot{\theta} + \left(\frac{Rb + K_t^2}{J \cdot L} \right) \dot{\theta} = \frac{K_t}{J \cdot L} V(t)$$

$$\Rightarrow \mathcal{D}^3 \Theta(s) + \left(\frac{b}{J} + \frac{R}{L} \right) \mathcal{D}^2 \Theta(s) + \left(\frac{Rb + K_t^2}{J \cdot L} \right) \mathcal{D} \Theta(s) = \frac{K_t}{J \cdot L} V(s)$$

$$\Theta(s) \left[\mathcal{D}^3 + \left(\frac{b}{J} + \frac{R}{L} \right) \mathcal{D}^2 + \left(\frac{Rb + K_t^2}{J \cdot L} \right) \mathcal{D} \right] = \frac{K_t}{J \cdot L} V(s)$$

$$G(s) = \frac{\Theta(s)}{V(s)} = \frac{K_t K_t}{JL \mathcal{D}^3 + (bL + RJ) \mathcal{D}^2 + (Rb + K_t^2) \mathcal{D}}$$

$$Q4) m \ddot{x} + (b + K_v) \dot{x} + K_p K_v x = K_p K_v \underbrace{x_r(t)}_t$$

$$\Rightarrow m s^2 X(s) + (b + K_v) s X(s) + K_p K_v X(s) = K_p K_v \cdot \frac{1}{s^2}$$

$$X(s) = \frac{K_p K_v}{s^2 (m s^2 + (b + K_v) s + K_p K_v)}$$

$$G(s) = \frac{X(s)}{X_r(s)} = \frac{K_p K_v}{m s^2 + (b + K_v) s + K_p K_v}$$



função de transferência