

Computer-controlled systems - theory and design

Prentice-Hall International - 9780133148992: Computer

$\frac{1}{s(s^2 + \omega_n^2)}$	$1 - e^{-\omega_n t}$
$\frac{1}{s(s^2 + T_1^2)}$	$1 - \frac{1}{T_1} e^{-t/T_1}$
$\frac{\omega}{(s^2 + \omega^2)^2}$	$e^{-\omega t} \sin \omega t$
$\frac{(s + a)}{(s^2 + \omega^2)^2}$	$e^{-at} \cos \omega t$
$\frac{\omega^2}{s^2(s^2 + 2\zeta\omega_n s + \omega_n^2)}$	$1 - \frac{e^{-\zeta\omega_n t}}{\sqrt{1 - \zeta^2}} \sin(\omega_n \sqrt{1 - \zeta^2} t + \theta)$
$\frac{\omega^2}{s^2(s^2 + 2\zeta\omega_n s + \omega_n^2)}$	where $\cos \theta = \zeta$
$\frac{s}{(s^2 + \omega_n^2)^2}$	$t - \frac{2\zeta}{\omega_n} + \frac{1}{\omega_n \sqrt{1 - \zeta^2}} e^{-\zeta\omega_n t} \sin(\omega_n \sqrt{1 - \zeta^2} t + \theta)$
$\frac{s}{(s^2 + \omega_n^2)^2}$	where $\theta = 2 \tan^{-1} \frac{\sqrt{1 - \zeta^2}}{\zeta}$
$\frac{s}{(s^2 + \omega_n^2)^2}$	$\frac{1}{(1 + \zeta^2 \omega_n^2)^2} e^{-\zeta\omega_n t} + \frac{1}{\sqrt{1 + \zeta^2 \omega_n^2}} \cos(\omega_n t - \theta)$
$\frac{s}{(s^2 + \omega_n^2)^2}$	where $\theta = \tan^{-1} \omega_n T$
$\frac{s}{(s^2 + \omega_n^2)^2}$	$\frac{1}{2\omega_n} \sin \omega_n t$
$\frac{s}{(s^2 + \omega_n^2)^2}$	$\frac{e^{-\zeta\omega_n t}}{(b - a^2 + \omega^2)^2} + \frac{e^{-\zeta\omega_n t} \sin(\omega_n t - \theta)}{\sqrt{(b - a^2 + \omega^2)^2 + \omega^2}}$
$\frac{s}{(s^2 + \omega_n^2)^2}$	where $\theta = \tan^{-1} \frac{\omega}{b - a^2}$
$\frac{2\omega s}{[s^2 + (a + b)^2][s^2 + (a - b)^2]}$	$\sin at \sin bt$
$\frac{1 + as + bs^2}{s^2(1 + T_1 s)(1 + T_2 s)}$	$t + (a - T_1 - T_2) + \frac{b - aT_1 + T_1^2}{T_1 - T_2} e^{-at} - \frac{b - aT_2 + T_2^2}{T_1 - T_2} e^{-bt}$

Description: -

-Computer-controlled systems - theory and design

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