

## Question 1

Consider the state-space form:

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} 2 & -1 \\ -12 & \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 2 \\ 0 \end{bmatrix} u$$

$$y = \begin{bmatrix} 0 & 3 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

With the the initial conditions:

$$\begin{bmatrix} x_1(0) \\ x_2(0) \end{bmatrix} = \begin{bmatrix} -1 \\ 1 \end{bmatrix}$$

$$u(t) = 1_+(t)$$

In Assignment #2, you found that

$$A = \begin{bmatrix} 2 & -1 \\ -12 & 2 \end{bmatrix} \implies e^{At} = \frac{1}{2} \begin{bmatrix} e^t + e^{3t} & e^t - e^{3t} \\ e^t - e^{3t} & e^t + e^{3t} \end{bmatrix}$$

- Find the zero-input trajectory  $x_{z-i}(t)$  and response  $y_{z-i}(t)$  using hand calculations
- Find the zero-state trajectory  $x_{z-s}(t)$  and response  $y_{z-s}(t)$  using hand calculations
- Find the trajectory  $x(t)$  and response  $y(t)$  of the system using hand calculations
- Redo (a)-(c) using only MATLAB's symbolic toolbox, and ensure your solutions match. Provide the input commands that you used.

**(a)**

The zero-input trajectory problem is given by:

$$\dot{x} = Ax$$

$$x(0) = x_0$$

The solution to this matrix differential equation is similar to the scalar case. The solution is given by  $x(t) = e^{At}x_0$ . Bashing out the calculations gives:

$$\begin{aligned} x(t) &= e^{At}x_0 \\ &= \frac{1}{2} \begin{bmatrix} e^t + e^{3t} & e^t - e^{3t} \\ e^t - e^{3t} & e^t + e^{3t} \end{bmatrix} \begin{bmatrix} -1 \\ 1 \end{bmatrix} \\ &= \begin{bmatrix} -e^{3t} \\ e^{3t} \end{bmatrix} \end{aligned}$$

The zero-input response is given by:

$$\begin{aligned} y(t) &= Cx(t) \\ &= \begin{bmatrix} 0 & 3 \end{bmatrix} \begin{bmatrix} -e^{3t} \\ e^{3t} \end{bmatrix} \\ &= 3e^{3t} \end{aligned}$$

The zero-input trajectory is therefore

$$\boxed{\begin{aligned} x_{z-i}(t) &= \begin{bmatrix} -e^{3t} \\ e^{3t} \end{bmatrix} \\ y_{z-i}(t) &= 3e^{3t} \end{aligned}}$$

(b)

The zero-state trajectory problem is given by:

$$\begin{aligned} \dot{x} &= Ax + Bu \\ x(0) &= 0 \end{aligned}$$

The solution to this matrix differential equation is similar to the scalar case where an integrating factor approach is used. The solution is given by  $x(t) = \int_0^t e^{A(t-\tau)} Bu(\tau) d\tau$ .

First step to evaluating this *garbage* is to evaluate the integrand:

$$e^{A(t-\tau)} Bu(\tau) = \frac{1}{2} \begin{bmatrix} e^{t-\tau} + e^{3(t-\tau)} & e^{t-\tau} - e^{3(t-\tau)} \\ e^{t-\tau} - e^{3(t-\tau)} & e^{t-\tau} + e^{3(t-\tau)} \end{bmatrix} \begin{bmatrix} 2 \\ 0 \end{bmatrix} u(\tau)$$

Conveniently,  $u(\tau) = 1_+(\tau)$ , so the integrand becomes:

$$\begin{aligned} e^{A(t-\tau)} Bu(\tau) &= \frac{1}{2} \begin{bmatrix} e^{t-\tau} + e^{3(t-\tau)} & e^{t-\tau} - e^{3(t-\tau)} \\ e^{t-\tau} - e^{3(t-\tau)} & e^{t-\tau} + e^{3(t-\tau)} \end{bmatrix} \begin{bmatrix} 2 \\ 0 \end{bmatrix} \\ &= \begin{bmatrix} e^{t-\tau} + e^{3(t-\tau)} \\ e^{t-\tau} - e^{3(t-\tau)} \end{bmatrix} \end{aligned}$$

Taking the integral term-by-term gives:

$$\begin{aligned}
 \int_0^t e^{A(t-\tau)} Bu(\tau) d\tau &= \begin{bmatrix} \int_0^t e^{t-\tau} + e^{3(t-\tau)} d\tau \\ \int_0^t e^{t-\tau} - e^{3(t-\tau)} d\tau \end{bmatrix} \\
 &= \begin{bmatrix} \int_0^t e^{t-\tau} d\tau + \int_0^t e^{3(t-\tau)} d\tau \\ \int_0^t e^{t-\tau} d\tau - \int_0^t e^{3(t-\tau)} d\tau \end{bmatrix} \\
 1.51.5 \quad &= - \begin{bmatrix} e^{t-\tau} \Big|_0^t + \frac{1}{3} e^{3(t-\tau)} \Big|_0^t \\ e^{t-\tau} \Big|_0^t - \frac{1}{3} e^{3(t-\tau)} \Big|_0^t \end{bmatrix} \\
 &= - \begin{bmatrix} (1 - e^t) + \left(\frac{1}{3} - \frac{1}{3} e^{3t}\right) \\ (1 - e^t) - \left(\frac{1}{3} - \frac{1}{3} e^{3t}\right) \end{bmatrix} \\
 &= \begin{bmatrix} e^t + \frac{e^{3t}}{3} - \frac{4}{3} \\ e^t - \frac{e^{3t}}{3} - \frac{2}{3} \end{bmatrix}
 \end{aligned}$$

The zero-state response is given by  $y_{z-s} = Cx_{z-s} + Du$ . Since  $D = 0$ , the output is simply:

$$\begin{aligned}
 y_{z-s}(t) &= Cx_{z-s}(t) \\
 &= \begin{bmatrix} 0 & 3 \end{bmatrix} \begin{bmatrix} e^t + \frac{e^{3t}}{3} - \frac{4}{3} \\ e^t - \frac{e^{3t}}{3} - \frac{2}{3} \end{bmatrix} \\
 &= 3e^t + e^{3t} - 2
 \end{aligned}$$

The zero-state trajectory is therefore

$$\boxed{
 \begin{aligned}
 x_{z-s}(t) &= \begin{bmatrix} e^t + \frac{e^{3t}}{3} - \frac{4}{3} \\ e^t - \frac{e^{3t}}{3} - \frac{2}{3} \end{bmatrix} \\
 y_{z-s}(t) &= 3e^t + e^{3t} - 2
 \end{aligned}
 }$$

(c)

Lastly, summing the zero-input and zero-state trajectories gives the full trajectory:

$$\boxed{
 \begin{aligned}
 x(t) &= x_{z-i}(t) + x_{z-s}(t) \\
 &= \begin{bmatrix} -e^{3t} \\ e^{3t} \end{bmatrix} + \begin{bmatrix} e^t + \frac{e^{3t}}{3} - \frac{4}{3} \\ e^t - \frac{e^{3t}}{3} - \frac{2}{3} \end{bmatrix} \\
 &= \begin{bmatrix} e^t - \frac{2e^{3t}}{3} - \frac{4}{3} \\ e^t + \frac{2e^{3t}}{3} - \frac{2}{3} \end{bmatrix}
 \end{aligned}
 }$$

The full response is given by  $y(t) = Cx(t) + Du(t)$ . Since  $D = 0$ , the output is simply:

$$\begin{aligned} y(t) &= Cx(t) \\ &= \begin{bmatrix} 0 & 3 \end{bmatrix} \begin{bmatrix} e^t - \frac{2e^{3t}}{3} - \frac{4}{3} \\ e^t + \frac{2e^{3t}}{3} - \frac{2}{3} \end{bmatrix} \\ &= 3e^t + 2e^{3t} - 2 \end{aligned}$$

(d)

The code is given by:

```
clc; clear all; close all;

A = [2 -1; -1 2];
B = [2; 0];
C = [0 3];
D = [0];
x0 = [-1; 1];

syms t tau

% Part (a)
x_zi = expm(A*t)*x0;
y_zi = C*x_zi;

disp('Part (a)')
disp('x_zi(t) = ')
disp(x_zi)
disp('y_zi(t) = ')
disp(y_zi)

% Part (b)
x_zs = int(expm(A*(t-tau))*B, tau, 0, t);
y_zs = C*x_zs;

disp('Part (b)')
disp('x_zs(t) = ')
disp(expand(x_zs))
disp('y_zs(t) = ')
disp(expand(y_zs))

% Part (c)
x = x_zi + x_zs;
y = C*x;

disp('Part (c)')
```

```

disp('x(t) = ')
disp(expand(x))
disp('y(t) = ')
disp(expand(y))

```

## Question 2

Using the Laplace transform integral, show that the transform of  $f(t) = \cos \Omega t$  is  $F(s) = s/(s^2 + \Omega^2)$ , and that the associated region of convergence (the values of  $s$  for which the integral converges) is  $\Re\{s\} > 0$ . Hint: start by using the identity

$$\cos \Omega t = \frac{1}{2} (e^{j\Omega t} + e^{-j\Omega t})$$

(a)

Using the exponential form of the cosine function and the definition of the Laplace transform, we have:

$$\begin{aligned}
 \mathcal{L}(\cos \Omega t) &= \int_0^\infty e^{-st} \cos \Omega t dt = \int_0^\infty e^{-st} \frac{1}{2} (e^{j\Omega t} + e^{-j\Omega t}) dt \\
 &= \frac{1}{2} \int_0^\infty e^{-(s-j\Omega)t} + e^{-(s+j\Omega)t} dt \\
 &= \frac{1}{2} \left( \frac{-1}{s-j\Omega} e^{-(s-j\Omega)t} + \frac{-1}{s+j\Omega} e^{-(s+j\Omega)t} \right) \Big|_0^\infty \\
 &= \frac{1}{2} \left( \frac{-1}{s-j\Omega} (0-1) + \frac{-1}{s+j\Omega} (0-1) \right) \\
 &= \frac{1}{2} \left( \frac{1}{s-j\Omega} + \frac{1}{s+j\Omega} \right) \\
 &= \frac{1}{2} \left( \frac{s-j\Omega}{s^2 + \Omega^2} + \frac{s+j\Omega}{s^2 + \Omega^2} \right) \\
 &= \frac{1}{2} \left( \frac{s-j\Omega + s+j\Omega}{s^2 + \Omega^2} \right) \\
 &= \frac{1}{2} \left( \frac{2s}{s^2 + \Omega^2} \right) \\
 &= \frac{s}{s^2 + \Omega^2}
 \end{aligned}$$

## Question 3

Consider the Laplace Transform of  $f(t)$  given by

$$F(s) = \frac{16s^2 + 23s + 13}{(s+1)^2(s+2)}$$

- (a) What are the poles of  $F(s)$ ?
- (b) Using the Final Value Theorem, predict the behaviour of  $f(t)$  as  $t \rightarrow \infty$
- (c) By hand, obtain the partial fraction expansion of  $F(s)$
- (d) Use MATLAB's `partfrac` to confirm your result; provide the input commands you used.
- (e) Obtain  $f(t)$ , and confirm the prediction from (b) holds. Hint:  $\lim_{t \rightarrow \infty} te^{-t} = 0$

**(a)**

The poles of  $F(s)$  are  $s = -1$  and  $s = -2$ . The pole at  $s = -1$  has a multiplicity of 2.

**(b)**

Using the Final Value Theorem, we can see the contribution of each pole.

1.  $s = -1$  has a multiplicity of 2, so the contribution will be  $e^{-t}$  and  $te^{-t}$ .
2.  $s = -2$  has a multiplicity of 1, so the contribution will be  $e^{-2t}$ .

Therefore, as  $t \rightarrow \infty$ ,  $f(t) \rightarrow 0$ . This is statement 3 of the Final Value Theorem in the course notes.

**(c)**

By the Heaviside Cover-up Method, we can obtain the partial fraction expansion of  $F(s)$ .

$$\begin{aligned}
 F(s) &= \frac{16s^2 + 23s + 13}{(s+1)^2(s+2)} \\
 &= \frac{A}{s+1} + \frac{B}{(s+1)^2} + \frac{C}{s+2} \\
 &= \frac{A(s+1)(s+2) + B(s+2) + C(s+1)^2}{(s+1)^2(s+2)} \\
 &= \frac{(A+C)s^2 + (3A+2B+2C)s + (2A+B+C)}{(s+1)^2(s+2)}
 \end{aligned}$$

By cover-up,

$$\begin{aligned} B &= \left. \frac{16s^2 + 23s + 13}{(s + 2)} \right|_{s=-1} \\ &= \frac{16(-1)^2 + 23(-1) + 13}{(-1 + 2)} \end{aligned}$$

Solving this system of equations, we get  $A = 3$ ,  $B = 2$ , and  $C = 13$ .

(d)

Using MATLAB's `partfrac` command, we get the following result.

```
>> partfrac(16*s^2 + 23*s + 13, (s + 1)^2*(s + 2))
```

```
ans =
```

$$3/(s + 1) + 2/(s + 1)^2 + 13/(s + 2)$$

(e)

Using the inverse Laplace Transform, we get the following result.