

Department of Electrical and Computer Engineering

University of Victoria

ELEC 300 - Linear Circuits II

LABORATORY REPORT

Experiment No.:	3
Title:	Time Domain Responses
Date of experiment:	4 March, 2016
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1 Objective

This lab will create an active realization of a second order system. The output of the circuit will be used to verify the system parameters.

2 Introduction

Inductors in second order systems can be replaced by amplifiers and capacitors. Fig. 1 shows an active second order system with a gain of $G = 1 + \frac{R_a}{R_b}$.

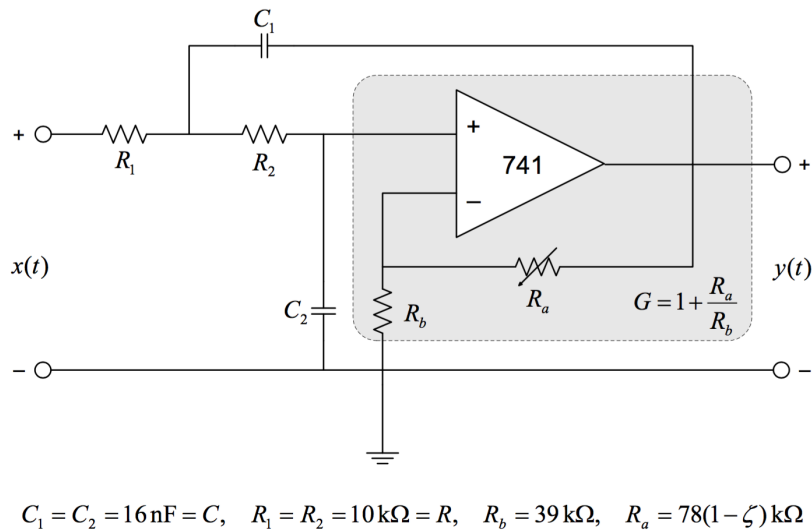


Figure 1: Active realization of a second order system

The transfer function of this system is:

$$H(s) = \frac{G\omega_0^2}{s^2 + 2\zeta\omega_0 s + \omega_0^2} \quad (1)$$

where

$$\omega_0 = \frac{1}{RC} \quad (2)$$

and

$$\zeta = 1 - \frac{R_a}{2R_b}. \quad (3)$$

When the unit step function is applied to Fig. 1 it will produce an output similar to Fig. 2.

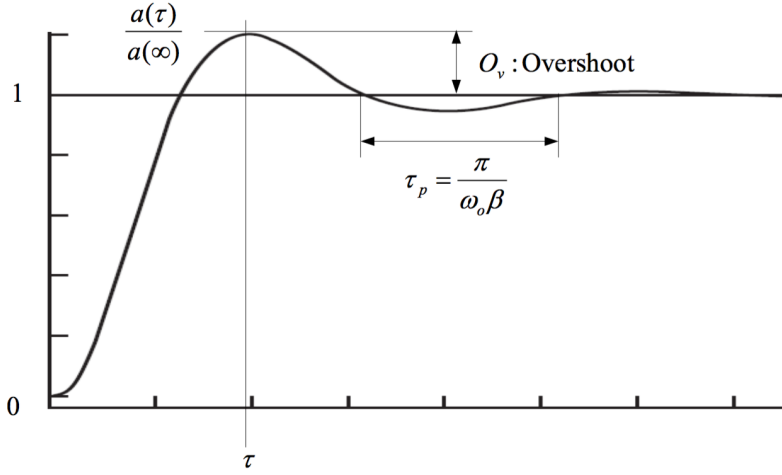


Figure 2: Step response of second order system

The system parameters ζ and ω_0 can be obtained from this graph since:

$$O_v = \exp\left(\frac{-\zeta\pi}{\beta}\right) \quad (4)$$

$$T_p = \frac{\pi}{\omega_0\beta}. \quad (5)$$

3 Results

Fig. 1 was realized with damping factor $\zeta = 0.1$. Using (3), $R_a = 70.2 \text{ k}\Omega$. The opamp supply power was set at $\pm 15 \text{ V}$. An input signal of 1 V_{pp} at 50 Hz square wave was applied to the circuit. One pulse of the square wave will behave locally like a unit step function.

The output of this circuit is shown in Fig. 3. The large overshoot corresponds to significant underdamping, which is consistent with $\zeta = 0.1$.

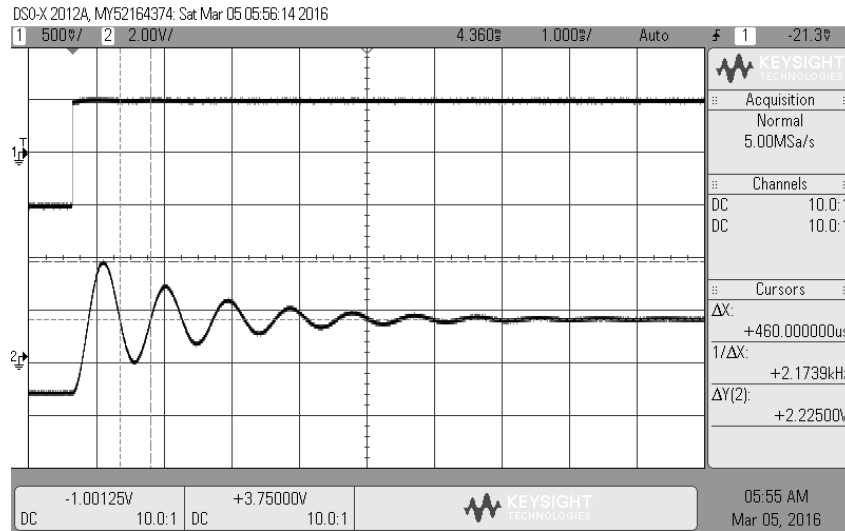


Figure 3: Measured response of second order system

The measured values are $O_v = 2.225 \text{ V}$ and $T_p = 460 \mu\text{s}$. As the transient response is damped, the value of the output settles to 2.8 V . This is consistent with $G = 1.8$.

4 Discussion

Analysis and interpretation of data.

5 Conclusion

Justify conclusions and results.