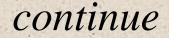
# Test input signals

#### Main content

- Test input signals
- Response of a first-order system
- Performance of a second-order system
- Effects of a third pole and a zero on system response
- Root location and the transient response



#### Main content

- Steady-state error analysis
- Performance indices
- The simplification of linear systems
- Examples and simulation
- Summary

## Introduction

- Transient response
- Steady-state response
- Design specifications
- How to get compromise?

A distinct advantage of feedback control system is the ability to adjust the transient and steady-state response

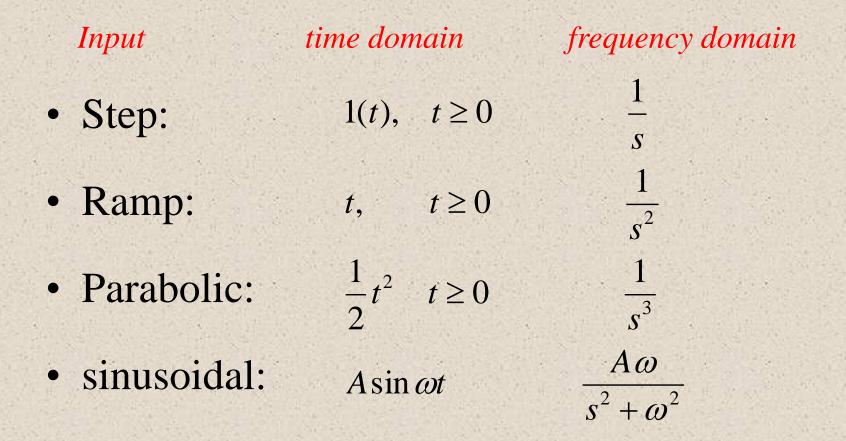
# 3.1 Test input signals

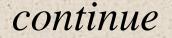
The standard test input signals commonly used are:

- Step input
- Ramp input
- Parabolic input
- Sinusoidal input
- Unit impulse input

continue

# Representation of test signals





## Unit impulse response

Unit impulse:  $\delta(t) = \begin{cases} \frac{1}{\varepsilon}, \\ 0, \end{cases}$ 

$$-\frac{\varepsilon}{2} \le t \le \frac{\varepsilon}{2}$$
  
otherwise

System impulse response:

 $g(t) = L^{-1}[G(s)]$ 

System response is the convolution integral of g(t) and r(t):

$$y(t) = \int_{-\infty}^{t} g(t-\tau)r(\tau)d\tau = L^{-1}[G(s)R(s)]$$

#### continue

# Standard test signal

The standard test signals are of the general form:

$$r(t) = t^n$$

And its Laplace transform is:

$$R(s) = \frac{n!}{s^{n+1}}$$

# Performance indices

(viewpoint from engineering)

Transient Performance:

- Time delay  $t_d$
- Rise time  $t_r$
- Peak time t p
- Settling time t<sub>s</sub>
- Percent overshoot  $\sigma\%$

Steady-state Performance: Steady-state error

# 3.2 Response of a first-order system

The model of first-order system

 $T\dot{c}(t) + c(t) = r(t)$ 

or

$$T(s) = \frac{C(s)}{R(s)} = \frac{1}{Ts+1}$$

For example, temperature or speed control system and water level regulating system.

#### Response of first-order system

- Unit step response (No steady-state error)
- Unit ramp response (Constant steady-state error)
- Unit parabolic response (Infinite steady-state error)

#### Important conclusion (for n-order LTI system)

From above analysis, we can see that impulse response of a system is the 1st-order derivative of step response or 2nd-order derivative of ramp response of the system.

#### **Conclusion:**

System response for the derivative of a certain input signal is equivalent to the derivative of the response for this input signal.

3.3 Response and performance of a second-order system

Model of 2nd-order system

$$T(s) = \frac{Y(s)}{R(s)} = \frac{\omega^2}{s^2 + 2\zeta\omega s + \omega^2}$$

• Roots of characteristic equation (Poles)

$$s_{1,2} = -\zeta \omega_n \pm \omega_n \sqrt{\zeta^2 - 1}$$

The response depends on  $\zeta$  and  $\omega_n$ 

#### Unit step response of 2nd-order system

- If  $\zeta < 0$ , 2 positive real-part roots, *unstable*
- If  $0 < \zeta < 1$ , 2 negative real-part roots, *underdamped*
- If  $\zeta = 1$ , 2 equal negative real roots, *critically damped*
- If  $\zeta > 1$ , 2 distinct negative real roots, *overdamped*
- If  $\zeta = 0$ , 2 complex conjugate roots, *undamped*

#### Case 1: underdamped

- Oscillatory response
- No steady-state error

## Case 2: critically damped

- Mono-incremental response
- No Oscillation
- No steady-state error

#### Case 3: overdamped

- Mono-incremental response
- slower than critically damped
- No Oscillation
- No steady-state error

# Performance evaluation

(underdamped condition)

- Performance indices evaluation
  - 1 Time delay
  - 2 Rise time
  - 3 Peak time
  - 4 Percent overshoot
  - 5 Settling time
- An example of performance evaluation

3.4 Effects of a third pole and a zero on 2nd-order system response

• Effect of a third pole

• Effect of a third zero

• Dominant poles

#### 3.5 Root location and transient response

• Characteristic roots (modes)

• Effects of Zeros on response

## STEADY STATE ERROR

 $ess = \lim sE(s)$  $s \rightarrow 0$ 

# $ess = \lim_{s \to 0} sR(s) \frac{1}{1 + G(S)H(S)}$