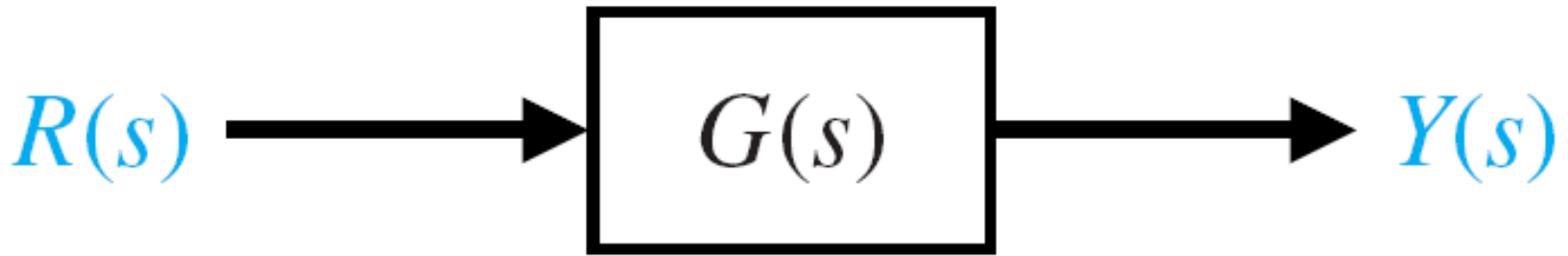


# Steady-state response

- **If the steady-state response of the output does not agree with the steady-state of the input exactly, the system is said to have a steady-state error.**
- **It is a measure of system accuracy when a specific type of input is applied to a control system.**



$$Y(s) = R(s) G(s)$$

# Steady-state error

$$T(s) = 9/(s + 10)$$

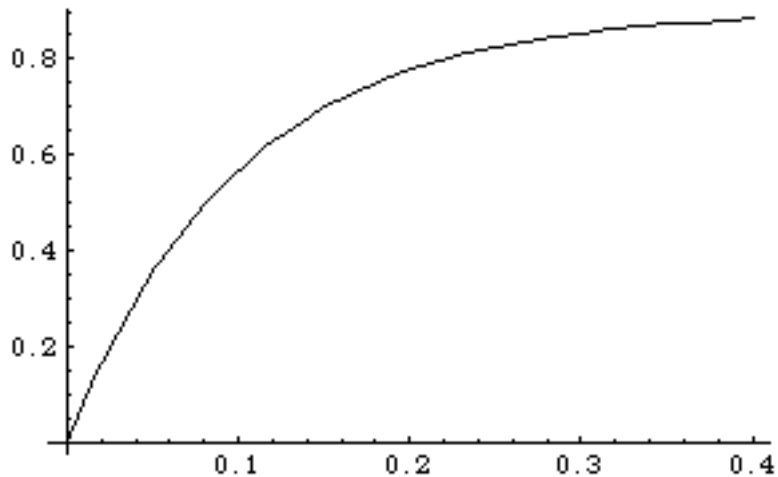
$$Y(s) = 9/s(s+10)$$

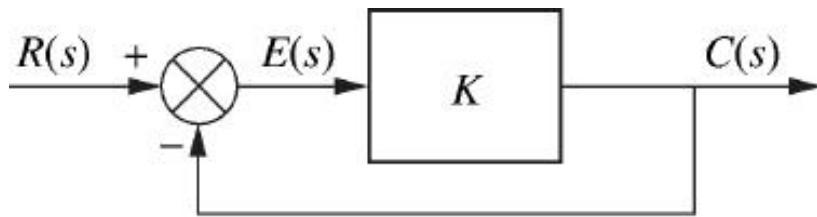
$$y(t) = 0.9(1 - e^{-10t})$$

$$y(\infty) = 0.9$$

$$E(s) = R(s) - Y(s)$$

$$e_{ss} = \lim_{s \rightarrow 0} s E(s) = 0.1$$

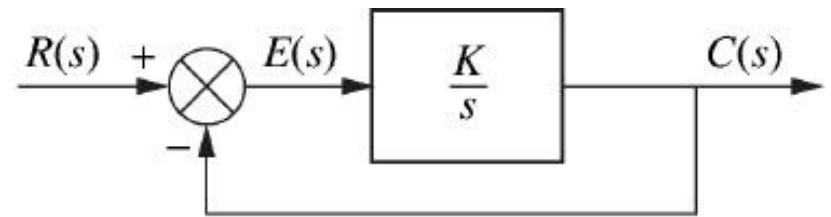




(a)

$$E(s) = \frac{R(s)}{1 + K}$$

$$e(t) = \frac{1}{1 + K}$$



(b)

$$E(s) = \frac{R(s)}{1 + \frac{K}{s}}$$

$$e(t) = e^{-K t}$$

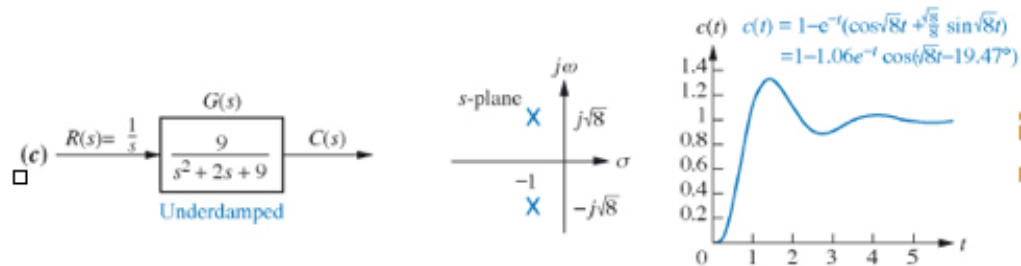
$$\text{InverseLaplaceTransform}\left[\left\{\frac{1}{s+a}, \frac{a}{s+a}\right\}, s, t\right]$$

$$\left\{E^{-(a t)}, \frac{a}{E^{a t}}\right\}$$

$$\text{InverseLaplaceTransform}\left[\left\{\frac{1}{s} * \frac{1}{s+a}, \frac{1}{s} * \frac{a}{s+a}\right\}, s, t\right]$$

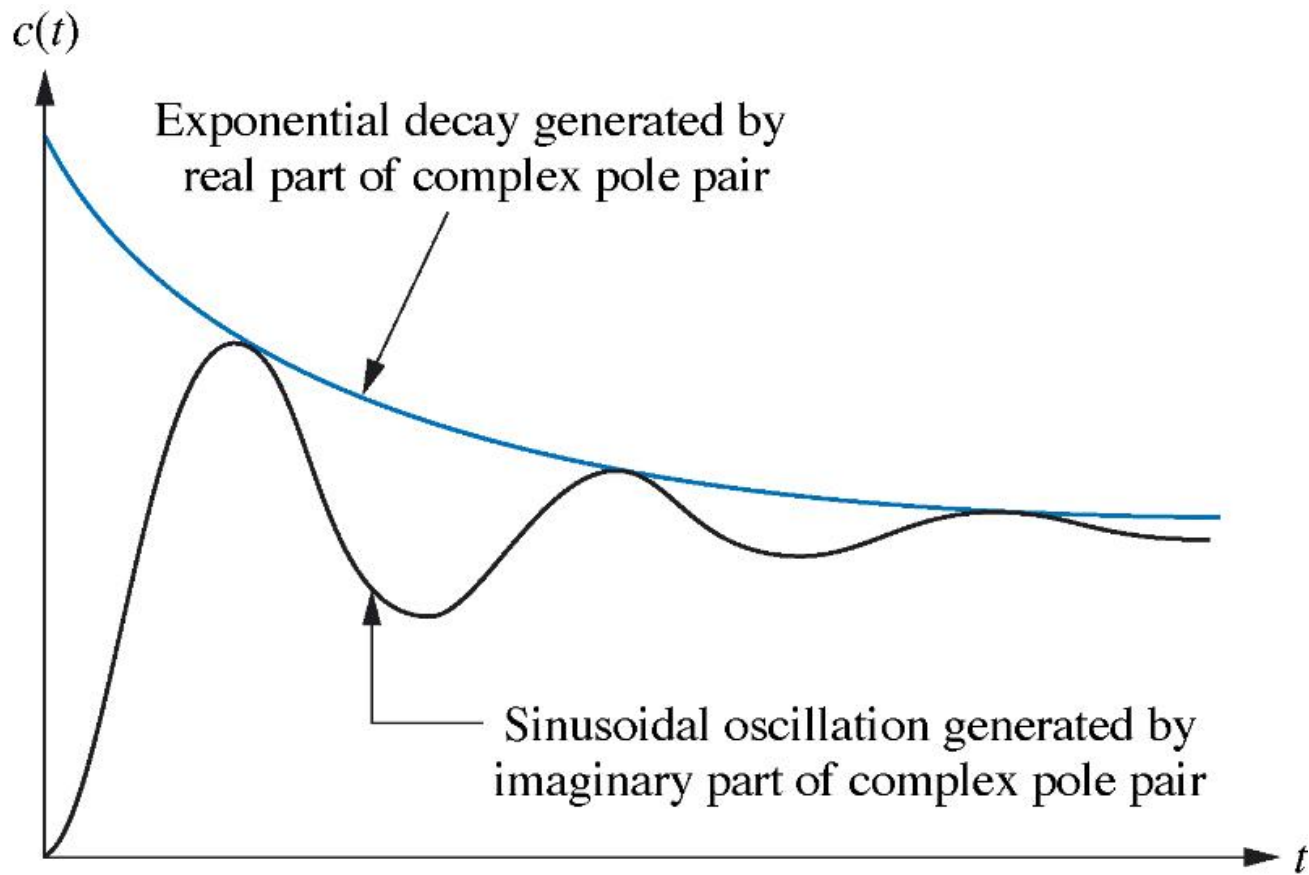
$$\left\{\frac{1 - E^{-(a t)}}{a}, 1 - E^{-(a t)}\right\}$$

# Underdamped



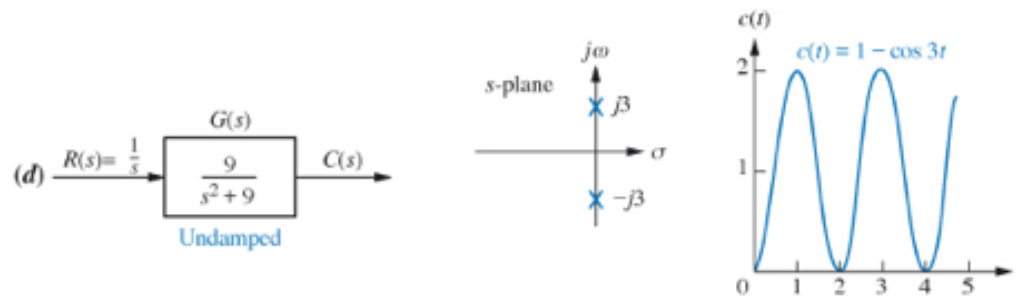
$$C(s) = \frac{9}{s(s^2 + 2s + 9)} = \frac{9}{s(s + 1 - j\sqrt{8})(s + 1 + j\sqrt{8})}$$

$$c(t) = 1 - e^{-t} \left( \cos \sqrt{8}t + \frac{\sqrt{8}}{8} \sin \sqrt{8}t \right)$$



$$c(t) = 1 - e^{-t} \left( \cos \sqrt{8}t + \frac{\sqrt{8}}{8} \sin \sqrt{8}t \right)$$

# Undamped

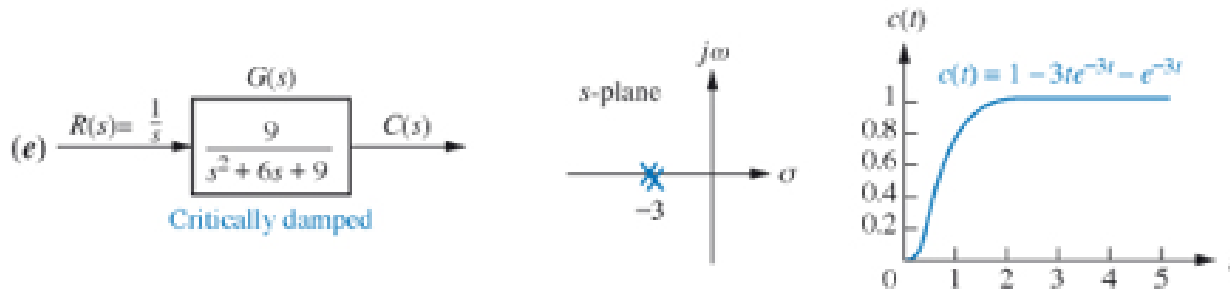


$$C(s) = \frac{9}{s(s^2 + 9)}$$

$$c(t) = 1 - \cos 3t$$



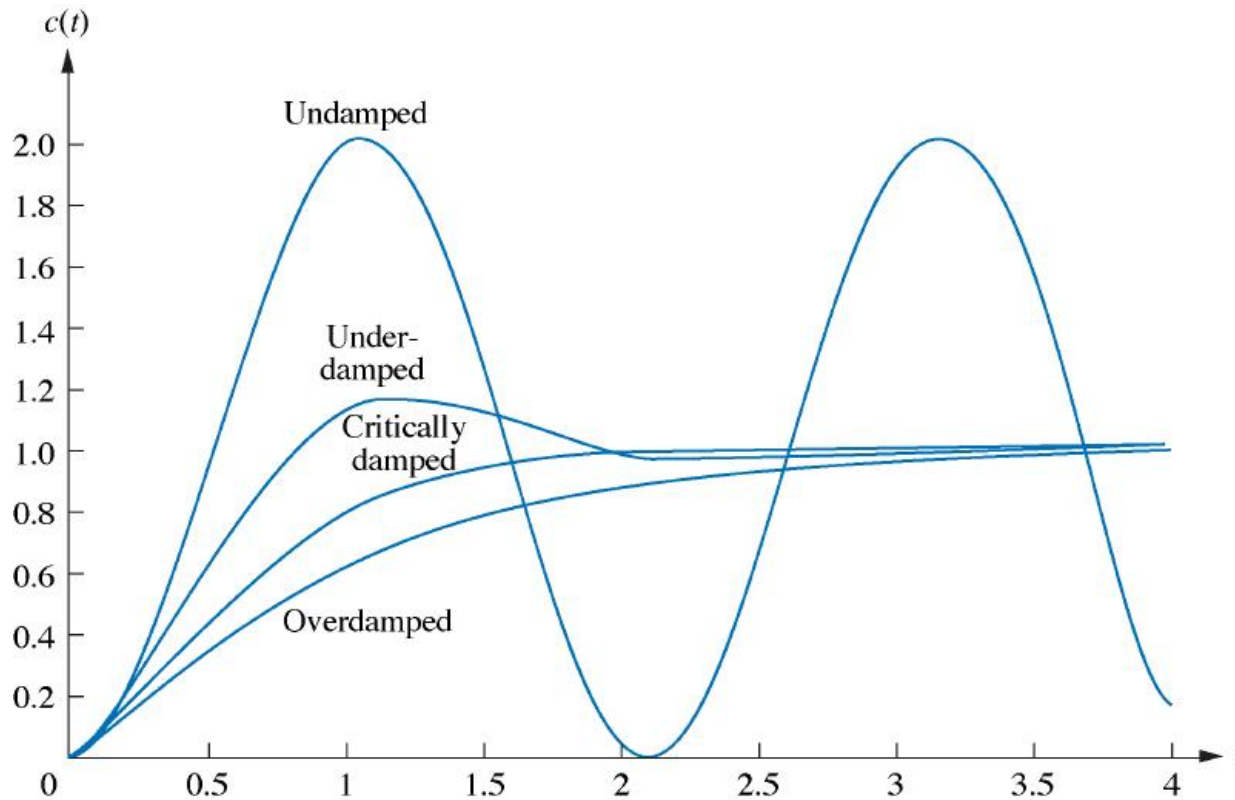
# Critically damped

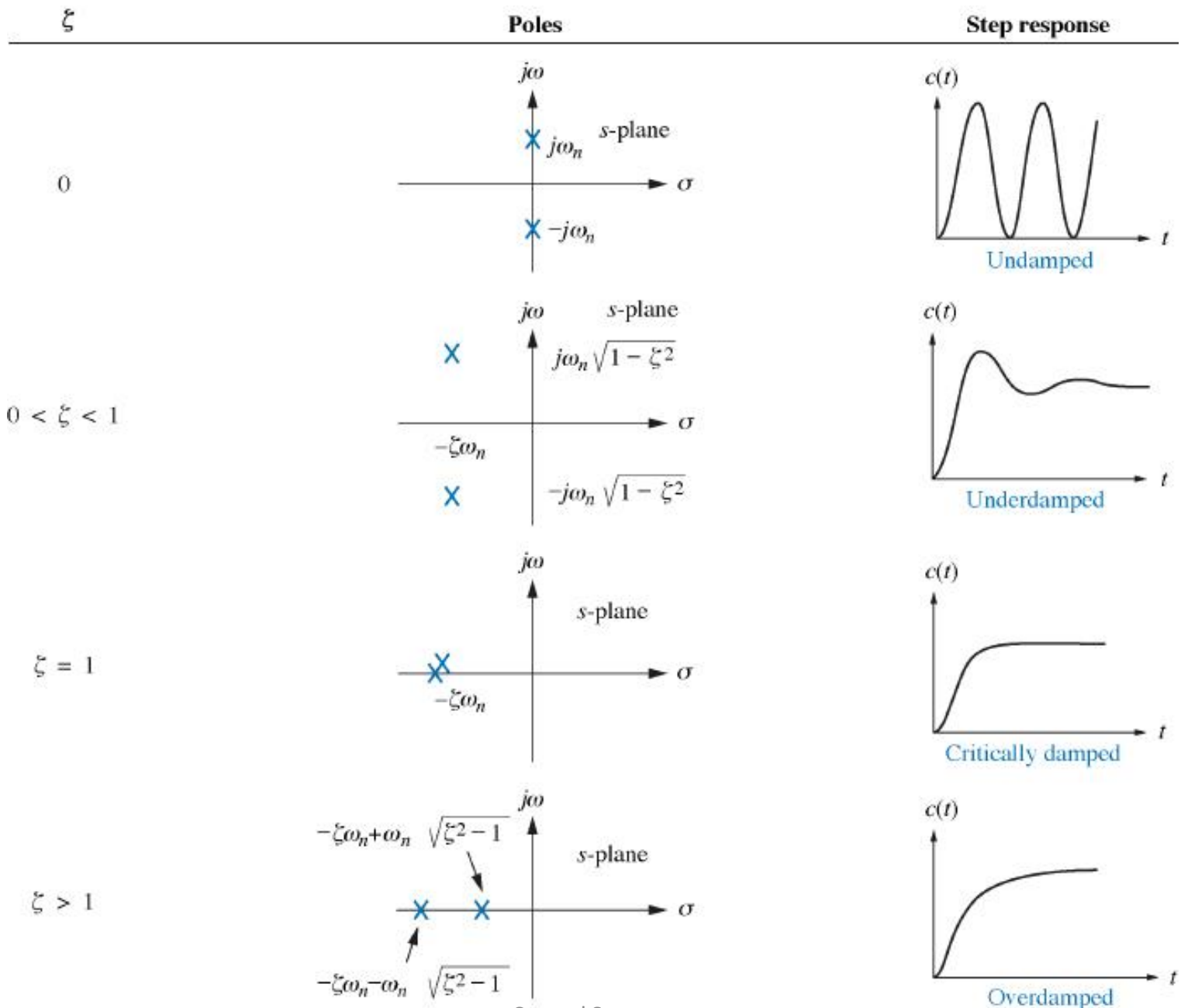


$$C(s) = \frac{9}{s(s^2 + 6s + 9)} = \frac{9}{s(s + 3)^2}$$

$$c(t) = 1 - 3te^{-3t} - e^{-3t}$$

# Step response for second order system damping cases





# Summary

- **Overdamped**

Poles: Two real at  $-\sigma_1, -\sigma_2$

- **Underdamped**

Poles: Two complex at  $-\sigma_d + j\omega_d, -\sigma_d - j\omega_d$

- **Undamped**

Poles: Two imaginary at  $+j\omega_1, -j\omega_1$

- **Critically damped**

Poles: Two real at  $-\sigma_1,$