Contents

Preface	ix
Notes to the Instructor	xi
Chapter 1: Introduction to Systems	
 1.1 Introduction	1 3 6 15 16 20
Chapter 2: Time-Domain Analysis	
2.1 Eminiation of Variables in Sinultations integroutilerential Equations 2.2 Transfer Operator 2.3 Solution of Linear Differential Equations 2.4 Zero-Input Response 2.5 Some Insight into Zero-Input Behavior of a System 2.6 Zero-State Response 2.7 Unit Impulse Function 2.8 Impulse Response of a System 2.9 The Convolution Integral 2.10 Some Convolution Relationships 2.11 Convolution Integral as a Superposition Integral 2.12 Graphical View of Convolution 2.13 Numerical Techniques of Convolution 2.14 Initial-Condition Generators 2.15 Multiple Inputs 2.16 Response of a System to Exponential Input Signal 2.17 Natural Response and Exponential Input Signal	24 30 36 38 49 52 60 63 64 67 68 70 73 76 77 79 80
2.17 Natural Response and Forced Response	80 81 82 85 86

Chapter 3: Frequency-Domain Analysis

3.1	Introduction	96
3.2	The Exponential Signal in Linear Systems	96
3.3	Response of Linear Systems to Exponential Inputs	101

Foundations of Frequency-Domain Analysis
Exponential Representation of Periodic Inputs: The Fourier Series 107
Response of Linear Systems to Periodic Inputs 116
Limitations on Fourier Series Method of Analysis
Exponential Representation of Nonperiodic Inputs
Time-Domain and Frequency-Domain Representation of a Signal 123
Fourier Transforms of Some Functions
System Analysis Using Exponentials along $j\omega$ -Axis
The Unit Impulse Response
Some Properties of the Fourier Transform
Distortionless Transmission
Ideal Filters
Bandwidth and Rise-Time Relationship
The Sampling Theorem
Some Applications of the Sampling Theorem
Limitations of Fourier Analysis 160
Problems

Chapter 4: Frequency-Domain Analysis Using Generalized Exponentials

4.1	Generalization of Frequency: The Bilateral Laplace Transform 168
4.2	Causal Functions and Unilateral Frequency Transforms
4.3	Existence of the Laplace Transform
4.4	Interpretation of the Laplace Transform
4.5	Transforms of Some Useful Functions
4.6	System Analysis Using Generalized Exponentials
4.7	Comments on the Time-Domain and the Frequency-Domain Analysis 182
4.8	Some Properties of the Laplace Transform
4.9	Frequency-Domain Analysis: Another Point of View
4.10	Multiple Inputs
4.11	Block-Diagram Representation of Systems
4.12	Signal-Flow Graph Representation of Systems
4.13	Analysis of Signal-Flow Graphs
4.14	System Simulation
4.15	Natural Frequencies of a System
4.16	System Stability
4.17	Instability and Oscillations
	Problems

Chapter 5: Feedback and Control

5.1	Introduction
5.2	Analysis of a Simple Control System
5.3	Design Specifications
5.4	A Second-Order System
5.5	Higher-Order Systems
5.6	Root Locus

Contents

Steady-State Errors					•				٠			•	•	,	•	•	276
Compensation																	281
Direct Synthesis															•		289
Multiple-Variable Feedback									•								291
Sensitivity Considerations											•						297
Frequency-Response Method of Synthesis							-				•	•					303
Problems		•			•		•		•	•	•	•	•	•			327
	Steady-State Errors Compensation Compensation Direct Synthesis Direct Synthesis Sensitivity Considerations Sensitivity Considerations Sensitivity Considerations Frequency-Response Method of Synthesis Problems	Steady-State Errors Compensation Compensation Direct Synthesis Direct Synthesis Sensitivity Considerations Sensitivity Considerations Frequency-Response Method of Synthesis Problems Sensitivity	Steady-State Errors														

Chapter 6: State-Space Analysis

6.1	Description of a System
6.2	State Equations of a System
6.3	State Equations from Block Diagram
6.4	Solution of State Equations
6.5	Simulation
6.6	Linear Transformation of a State Vector
6.7	Stability
6.8	State-Variable Feedback
	Problems

Chapter 7: Discrete-Time Systems

7.1	Introduction
7.2	Modeling Discrete-Time Systems
7.3	Transfer Operator of a Discrete-Time System
7.4	Time-Domain Analysis of Discrete-Time Systems 404
7.5	The <i>z</i> -Transform
7.6	Some Properties of the <i>z</i> -Transform
7.7	Transform Analysis of Discrete-Time Systems
7.8	Inverse <i>z</i> -Transform
7.9	Simulation of Discrete-Time Systems
7.10	Digital Processing of Analog Signals
7.11	Digital Filtering
7.12	Sampled-Data (Hybrid) Systems
7.13	Response during Successive Sampling Instants: Modified
	<i>z</i> -Transform
7.14	Design of Sampled-Data Systems
7.15	State-Space Analysis of Discrete-Time Systems
7.16	State-Space Analysis of Sampled-Data Systems
	Problems

Appendix A: Some Properties of Differential Operators

A.1	Cancellation of Common Factors in Operational Equations			 463
A.2	Cancellation of Common Factors in the Numerator and the			
	Denominator of a Rational Fraction Operator	•		 464
A.3	Common Factors in the Numerator and the Denominator of $H(p)$	•	•	 465

Appendix B: Partial-Fraction Expansion

B .1	All Roots Simple (No Multiple Roots)	467
B.2	Complex Roots	469
B.3	Repeated (Multiple) Roots	470

Appendix C: Bode Plots

C.1	Frequency Response	472
C.2	Determination of Transfer Function from the Steady-State Response	486

Appendix D: Vectors and Matrices

D.1 Vectors.	488
D.2 Linear Vector Functions.	489
D.3 Some Definitions and Properties	491
D.4 Matrix Algebra	492
D.5 Derivatives and Integral of a Matrix	499
D.6 Computation of $e^{\mathbf{A}t}$	500
Appendix E: Second-Order System with a Zero	502
Appendix F: Nyquist Criterion for Stability	504
Appendix F: Nyquist Criterion for Stability F.1 Complex Mapping F.2 Graphical Criterion for Stability in Feedback Systems	504 504
Appendix F: Nyquist Criterion for Stability F.1 Complex Mapping F.2 Graphical Criterion for Stability in Feedback Systems (the Nyquist Criterion)	504 504 508
Appendix F: Nyquist Criterion for Stability F.1 Complex Mapping F.2 Graphical Criterion for Stability in Feedback Systems (the Nyquist Criterion) Bibliography	504 504 508