

Contents

PREFACE XVII

INTRODUCTION 1

Part 1 Overview Of Dynamic Systems

1 INTRODUCTION TO MODELING AND SIMULATION 7

1.1 Dynamic Systems 7

1.1.1 Examples of Dynamic Systems 7

1.1.2 Definitions Related to Dynamic Systems 10

1.2 Modeling of Dynamic Systems 15

1.2.1 Steps in Modeling and Representing Dynamic Systems 15

1.2.2 Utility of Modeling and Simulation 17

1.3 Scope of the Text 18

References 20

Nomenclature 20

Problems 21

3.1.1
3.1.2
3.1.3
3.1.4
3.1.5

2	MODELS FOR DYNAMIC SYSTEMS AND SYSTEMS SIMILARITY	22
2.1	Formulation of Models for Engineering Systems	22
	2.1.1 Conservation Laws of Engineering Systems	22
	2.1.2 Property Laws for Engineering Systems	25
	2.1.3 Reduction of the Modeling Equations	26
2.2	Solution of the Differential Equations	26
	2.2.1 Classical Differential Equations	27
	2.2.2 Transfer Function Format for Differential Equations	31
	2.2.3 State-Space Format for Differential Equations	32
2.3	Typical Inputs or Test Signals	34
	2.3.1 Step Input	34
	2.3.2 Ramp Input	35
	2.3.3 Universal Inputs	36
	2.3.4 Pulse Input	37
	2.3.5 Ramped Step Input	37
	2.3.6 Harmonic Inputs	37
	2.3.7 Common Test Signals	39
2.4	Engineering Systems Similarity	40
	2.4.1 Effort and Flow Variables	42
	2.4.2 Dissipative Elements	42
	2.4.3 Effort Storage Elements	43
	2.4.4 Flow Storage Elements	44
	2.4.5 Summary of the Elements in Engineering Disciplines	45
	References	46
	Nomenclature	47
	Problems	48

Part 2 Modeling of Engineering Systems

3	MECHANICAL SYSTEMS	53
3.1	Introduction	53
3.2	Systems of Units	53
3.3	Translational Systems	55
	3.3.1 Translational Springs	55
	3.3.2 Translational Dampers	57
	3.3.3 Discrete Mass	59
	3.3.4 Modeling Translational Systems	61
3.4	Rotational Systems	67

3.4.1	Rotational Springs	67
3.4.2	Rotational Dampers	68
3.4.3	Discrete Inertias	69
3.4.4	Modeling Rotational Systems	70
3.5	Systems of Combined Translational and Rotational Elements	73
3.6	D'Alembert's Principle	81
3.7	Lagrange's Equation	83
3.8	Three-Dimensional Motion	87
3.9	Summary	88
	References	88
	Nomenclature	88
	Problems	89
4	ELECTRICAL SYSTEMS	99
4.1	Introduction	99
4.2	Basic Elements	99
4.2.1	Resistance	101
4.2.2	Capacitance	102
4.2.3	Inductance	104
4.2.4	Definition of Impedance	105
4.3	Passive Circuit Analysis	109
4.3.1	Kirchhoff's Laws	109
4.3.2	Resistance Circuits	110
4.3.3	Resistance-Capacitance Circuits	114
4.3.4	Resistance-Inductance Circuits	117
4.3.5	Resistance-Inductance-Capacitance Circuits	119
4.3.6	Summary of Passive Circuit Analysis Techniques	121
4.4	Active Circuit Analysis	122
4.4.1	The Operational Amplifier	123
4.4.2	Typical Circuits	124
4.5	Summary	127
	References	127
	Nomenclature	128
	Problems	128

5	FLUID SYSTEMS	135
5.1	Introduction	135
5.2	Properties of Fluids	136
5.2.1	Density	136
5.2.2	Equation of State: Liquids	136
5.2.3	Equation of State: Gases	138
5.2.4	Viscosity	141
5.2.5	Propagation Speed	143
5.2.6	Thermal Properties	143
5.3	Reynolds Number Effects	143
5.4	Derivation of Passive Components	145
5.4.1	Capacitance	145
5.4.2	Inductance	150
5.4.3	Resistance	151
5.5	Summary	161
	References	161
	Nomenclature	162
	Problems	163
6	THERMAL SYSTEMS	169
6.1	Introduction	169
6.2	Basic Effects	169
6.2.1	Thermal Conduction	170
6.2.2	Thermal Convection	178
6.2.3	Thermal Radiation	181
6.2.4	Thermal Capacitance	183
6.3	Circuit Analysis of Static Thermal Systems	183
6.3.1	Thermal Conduction Circuits	183
6.3.2	Thermal Conduction and Convection Circuits	185
6.4	Circuit Analysis of Dynamic Thermal Systems	188
6.4.1	Single-Lumped Capacitance Modeling	189
6.4.2	Multiple-Lumped Capacitance Modeling	190
6.5	Summary	197
	References	197
	Nomenclature	197
	Problems	198

7	MIXED DISCIPLINE SYSTEMS	203
7.1	Introduction	203
7.2	Electromechanical Systems	203
7.2.1	DC Motor Speed Control	204
7.2.2	DC Motor Position Control	209
7.3	Fluid-Mechanical Systems	211
7.3.1	Hydraulic Position Servo	212
7.3.2	Pneumatic Position Servo	214
7.4	Electrohydraulic Position Servo	221
7.5	Summary	223
	References	223
	Nomenclature	224
	Problems	225

Part 3 System Dynamic Response Analysis

8	FREQUENCY RESPONSE	231
8.1	Introduction	231
8.2	Preliminaries	232
8.3	First-Order Systems	233
8.3.1	Introduction	233
8.3.2	Classical Solution	234
8.3.3	Frequency Response	235
8.3.4	Frequency Response Simulation	238
8.3.5	Low-Pass Filter	238
8.3.6	A First-Order Mechanical System	239
8.4	Second-Order Systems	241
8.4.1	Classical Solution	241
8.4.2	Frequency Response	246
8.5	Higher Order Systems	247
8.5.1	Introduction	247
8.5.2	Pneumatic Servo System	247
8.5.3	Torsional System	249
8.6	Alternative Forms of System Description	250
8.7	Summary	252

References 253

Nomenclature 253

Problems 254

9 TIME RESPONSE AND DIGITAL SIMULATION 259

9.1 Introduction 259

9.2 Analytical Methods 259

9.2.1 First-Order Systems 259

9.2.2 Second-Order Systems 261

9.2.3 Higher-Order Systems 263

9.3 Digital Simulation 265

9.3.1 Introduction 265

9.3.2 Euler's Method 265

9.3.3 More Accurate Methods 270

9.3.4 Runge-Kutta Methods 270

9.4 Systems of Equations 272

9.5 Selection of the Step Size 273

9.5.1 Selection of a Fixed Step Size 273

9.5.2 Selection of Output Interval and Final Time 276

9.6 Variable-Step-Size Methods 279

9.7 Solution of Nonlinear Differential Equations 283

9.8 Stiff Equations 288

9.9 Summary 290

References 290

Nomenclature 290

Problems 291

Part 4 Engineering Applications

10 SYSTEM DESIGN AND SELECTION OF COMPONENTS 301

10.1 Introduction 301

10.2 Voltage Power Supply Filter 302

10.3 Automotive Brake System 306

10.3.1 Foot Pedal Geometry and Forces 308

10.3.2 Brake Hydraulics and Pad Friction 310

10.3.3 Braking Forces on the Car 311

10.3.4	Weight Transfer with Deceleration	313
10.3.5	Tire Adhesion	315
10.3.6	Optimum Brake Distribution	316
10.3.7	Engineering Sizing for a Specific Application	318
10.4	DC Motor Speed Servo Control System	323
10.4.1	Equations and Criteria for Sizing and Selection of Components	324
10.4.2	Selection of Numeric Values	327
10.5	Pneumatic Position Servo System	331
10.5.1	Static Operation Criteria	333
10.5.2	Dynamic Response Criteria	335
10.5.3	Dynamic Response Simulation	340
10.6	Summary	341
	References	341
	Problems	341
APPENDIX A	UNITS AND CONVERSIONS	347
APPENDIX B	PROPERTIES OF MECHANICAL SYSTEM COMPONENTS	352
B.1	Elastic and Area Properties	352
B.1.1	Torsion of Rods	352
B.1.2	Bending of Beams	354
B.2	Mass Properties	355
B.2.1	Common Shapes	355
B.2.2	Parallel Axis Theorem	357
B.3	Material Properties	358
	References	358
APPENDIX C	VECTOR AND MATRIX ALGEBRA	359
C.1	Vectors	359
C.1.1	Definitions	359
C.1.2	Operations	360
C.2	Matrices	362
C.2.1	Definitions	362
C.2.2	Operations	362
C.2.3	Properties	364
C.2.4	Special Types of Matrices	364

C.3	Determinants	365	
	C.3.1	Definitions	365
	C.3.2	Evaluation by Cofactors	367
	C.3.3	Properties	367
C.4	Matrix Inversion	368	
	C.4.1	Definitions	368
	C.4.2	Properties	369
	Problems	370	
APPENDIX D SYSTEMS OF ALGEBRAIC EQUATIONS			378
D.1	Introduction	378	
D.2	Nonhomogeneous Algebraic Equations	378	
	D.2.1	Matrix Inversion	378
	D.2.2	Cramer's Rule	379
	D.2.3	Gaussian Elimination	380
D.3	Homogeneous Equations	382	
D.4	Linearity, Singularity, and Rank	383	
D.5	Matrix Eigenvalue Problems	388	
	D.5.1	Eigenvalues and Eigenvectors	388
	D.5.2	Reduction to Diagonal Form	390
D.6	Systems of Nonlinear Algebraic Equations	391	
	Problems	396	
APPENDIX E SOLUTIONS OF DIFFERENTIAL EQUATIONS BY CLASSICAL METHODS			400
E.1	Introduction	400	
E.2	First-Order Systems	400	
	E.2.1	Initial-Condition Response	401
	E.2.2	Step Input Response	402
	E.2.3	Ramp Input Response	404
	E.2.4	Sinusoidal Input Response	405
E.3	Second-Order Systems	409	
	E.3.1	Free Response	410
	E.3.2	Response to a Step Input	414
	E.3.3	Response to a Ramp Input	415
	E.3.4	Response to a Harmonic Excitation	416
E.4	Summary	420	
	Reference	420	

APPENDIX F	LAPLACE TRANSFORM SOLUTION OF DIFFERENTIAL EQUATIONS	426
F.1	Introduction	426
F.2	The Laplace Transform	426
F.3	Mathematical Properties of the Laplace Transform	428
F.4	The Inverse Laplace Transform	428
F.5	Solution of Differential Equations by Laplace Transform Techniques	432
	F.5.1 Step Input to a First-Order System	432
	F.5.2 Ramp Input to a First-Order System	433
F.6	General Approach to the Solution of Differential Equations	434
F.7	Partial Fraction Expansion	434
	F.7.1 Partial Fractions with Distinct Real Roots	435
	F.7.2 Partial Fractions with Repeated Real Roots	437
	F.7.3 Partial Fractions with Combined Distinct and Repeated Real Roots	438
	F.7.4 Partial Fractions with Distinct Complex Roots	439
	F.7.5 Partial Fractions with Repeated Complex Roots	441
	F.7.6 Partial Fractions with Combined Distinct and Repeated Complex Roots	442
	F.7.7 Partial Fractions with Combined Real and Complex Roots	443
F.8	Solution of Differential Equations with Partial Fraction Expansion	443
	References	445
	Problems	445
APPENDIX G	STATE-SPACE REPRESENTATION OF DYNAMIC SYSTEMS	448
G.1	Concept of State Space	448
G.2	State-Space Formulation	449
G.3	Conversion from Classical to State Variables	450
G.4	Conversion from Classical to State Variables with Input Derivatives	453
G.5	Conversion From State-Space to Classical Format	457
G.6	Transfer Functions	459
	Problems	460

APPENDIX H	DIGITAL SIMULATION USING MATLAB	463
H.1	Introduction	463
H.2	MATLAB Environment	464
H.3	Variables and Statements	464
H.4	Script Files and Functions	465
H.5	Fourth-Order Runge-Kutta Procedure	466
H.6	Plotting Your Results	467
H.7	Signals and Systems Toolbox	469
H.8	HELP!	471
	References	471
APPENDIX I	ANALOG SIMULATION	472
I.1	Introduction	472
I.2	Computing Components	473
	I.2.1 Inverter or Sign Change	474
	I.2.2 Scaler or Fixed-Gain Amplifier	474
	I.2.3 Potentiometer	476
	I.2.4 Summing Junction	476
	I.2.5 Integrator	476
	I.2.6 Differentiator	477
I.3	Classical Analog Computer Diagrams	477
I.4	State-Space Analog Computer Diagrams	478
I.5	Magnitude and Time Scaling	481
	I.5.1 Magnitude Scaling	481
	I.5.2 Time Scaling	483
I.6	Selection of Magnitude and Time Scale Factors	484
	I.6.1 Selection of Magnitude Scale Factors	484
	I.6.2 Selection of Time Scale Factors	486
I.7	Summary	490
	References	490
	Problems	491
APPENDIX J	QUESTIONS ABOUT THE MATERIAL IN THE BOOK	493
	ANSWERS TO SELECTED PROBLEMS	496
	INDEX	515