CHAPTER 5

B-5-1. Time constant = 0.25 min. The steady-state error is 2.5 degrees.

<u>B-5-2</u>. Rise time = 2.42 sec Peak time = 3.63 sec

Maximum overshoot = 0.163

Settling time = 8 sec (2 % criterion)

B-5-3. The maximum overshoot of 5% corresponds to 5 = 0.69. Hence

B-5-4.

$$\frac{C(s)}{R(s)} = \frac{K(Ts+I)}{Js^2 + KTs + K}$$

Since T = 3, K/J = 2/9, we have

$$\frac{C(s)}{R(s)} = \frac{\frac{2}{s}(3s+1)}{s^{2} + (\frac{2}{s})(3s + \frac{2}{s})}$$

Hence, $2 \le \omega_n = 6/9$ and $\omega_n^2 = 2/9$. Thus

B-5-5. When the mass m is set into motion by a unit-impulse force, the system equation becomes

$$m\ddot{z} + kx = \delta(t)$$

Define another impulse force to stop the motion as λ δ (t-T), where λ is the undetermined magnitude of the impulse force and t=T is the undetermined instant that this impulse is to be given to the system. Then, the equation for the system when the two impulse forces are given is

$$m\ddot{x} + kx = \delta(t) + A\delta(t-T)$$
, $x(0-) = 0$, $\dot{x}(0-) = 0$

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Bingen Yang

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of life management The theme Glocalized Solutions for Sustainability in Manufacturing addresses the need for engineers to develop solutions which have the potential to address global challenges by providing products services and processes taking into account local capabilities and constraints to achieve an economically socially and environmentally sustainable society in a global perspective Glocalized Solutions for Sustainability in Manufacturing do not only involve products or services that are changed for a local market by simple substitution or the omitting of functions Products and services need to be addressed that ensure a high standard of living everywhere Resources required for manufacturing and use of such products are limited and not evenly distributed in the world Locally available resources local capabilities as well as local constraints have to be drivers for product and process innovations with respect to the entire life cycle The 18th CIRP International Conference on Life Cycle Engineering LCE 2011 serves as a platform for the discussion of the resulting challenges and the collaborative development of new scientific ideas **Advanced Mechatronics: Monitoring And Control Of Spatially Distributed Systems** Dan S Necsulescu, 2008-11-06 This unique book extends mechatronics to spatially distributed systems Issues regarding remote measurements and indirect monitoring and control of distributed systems is presented in the general framework of the recently developed ill posed inverse problems The book starts with an overview of the main results in the inverse problem theory and continues with the presentation of basic results in discrete inverse theory. The second part presents various forward and inverse problems resulting from modeling monitoring and controlling mechanical acoustic fluid and thermal systems Finally indirect and remote monitoring and control issues are analyzed as cases of ill posed inverse problems Numerous numerical examples illustrate current approaches used for solving practical inverse problems

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