## Chalmers University of Technology Department of Signals and Systems

## **ESS101** Modelling and simulation

Examination date 081021

*Time:* 14.00 – 18.00

**Teacher:** Paolo Falcone, 772 1803

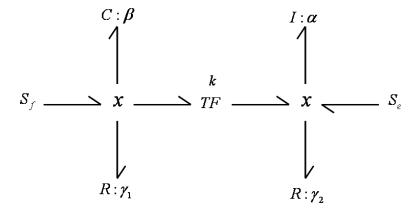
Allowed material during the exam: Mathematics Handbook.

The exam consists of 5 exercises of a total of 25 points. Nominal grading according to 12/17/21 points, you need 12 points to pass the course with grade 3, 17 points to pass with grade 4 and 21 to pass the course with grade 5. Solutions and answers should be written in English and be unambiguous and well motivated, but preferably short and concise.

Results are announced on the notice board at the latest Nov 4. You can check the grading of your exam on Nov 5 at 12.30-13.15 at the Department of Signals and Systems.

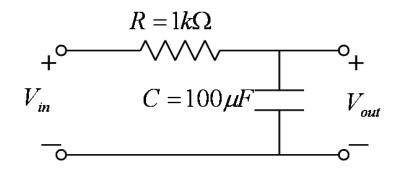
Exercise 1 
$$(5 p)$$

Consider the bond graph in the figure below.



- (a) Specify the two junctions 'x' in order to have a conflict-free graph and mark the casuality. Motivate the answer. (2p)
- (b) Derive a state space model from the obtained graph. (2p)
- (c) How does the answer to a) change if the flow source on the left is replaced by an effort source? (1p)

Consider the RC filter in the figure below.



- (a) Compute the spectrum of the signal  $V_{out}$ , when  $V_{in}$  is a white noise with variance 1. (3p)
- (b) Sketch a diagram of the spectrum of  $V_{out}$  versus the frequency. (1p)
- (c) How does the diagram at point b) change when C decreases? Motivate the answer. (1p)

Exercise 3 
$$(5 p)$$

A system is given as

$$y(t) = u(t-1) + 0.5u(t-2) + e(t)$$

where  $\{e(t)\}$  is white noise with variance 1. Assume an ARX(1,1) model is used to identify the system.

What is the value of the estimated parameters when the number of observations approaches infinity and

- (a)  $\{u(t)\}$  is white noise with variance 1.
- **(b)**  $\{u(t)\}$  has covariance function

$$R_u(0) = 1,$$
  
 $R_u(1) = 0.5,$   
 $R_u(2) = 0.25,$   
 $R_u(3) = 0.125,$   
and so on.

The input signal can be assumed to be independent of the disturbance.

(a) What is the (differentiation) index of the following DAE? (2p)

$$\dot{x}_1 = -x_1 + x_2 x_1 
\dot{x}_2 = -x_1^2 + x_2 x_3 
0 = x_1^2 + x_2 + x_3^2.$$

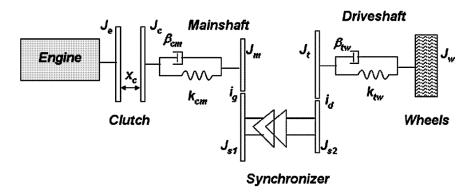
Motivate the answer.

$$\begin{bmatrix} 6 & 0 & 0 & 0 \\ 0 & 6 & 0 & 0 \\ 0 & 0 & 0 & 12 \\ 0 & 0 & 0 & 0 \end{bmatrix} \dot{x} + \begin{bmatrix} 12 & 6 & 0 & 0 \\ 18 & 18 & 0 & 0 \\ 0 & 0 & 6 & 0 \\ 0 & 0 & 0 & 6 \end{bmatrix} x = \begin{bmatrix} 1 \\ 2 \\ 3 \\ 4 \end{bmatrix}$$

Suggestion. The index can be computed by using well-known theoretical results.

Exercise 5 
$$(5 p)$$

A vehicle driveline can be described according to the figure below, where  $J_e$  is the engine inertia,  $x_c$  is the clutch position,  $J_c$  is the clutch inertia,  $\beta_{cm}$  and  $k_{cm}$  are the damping and the stiffness coefficients, respectively, of the axle connecting the main shaft and the clutch,  $J_m$  is the inertia of the main shaft,  $i_g$  and  $i_d$  are the gear and the differential ratios, respectively,  $J_{s1}$  and  $J_{s2}$  are the inertias of the two disks connected to the synchronizer,  $J_t$ ,  $\beta_{cm}$  and  $k_{cm}$  are the inertia, the damping and the stiffness coefficients of the drive shaft, respectively, and  $J_w$  is the wheel inertia. The two inertias connected to the synchronizer have the same angular speed.



Assume a rigid main shaft (i.e., the clutch position and speed equal to the main shaft position and speed, respectively) and that the transmitted torque to the clutch  $T_c$  is a known function of the clutch position  $x_c$ , i.e.,  $T_c = T_c(x_c)$ .

Determine a state space representation for the driveline. Let the engine torque, the clutch position  $x_c$  be the input signals, the wheel (vehicle) longitudinal velocity be the output and the load to the wheel an external disturbance.

*Help.* In the state equation describing the clutch speed dynamics, the inertia is equal to  $J_c + J_m + \frac{1}{i_g^2} \left( J_{s1} + J_{s2} + \frac{J_t}{i_d^2} \right)$ .