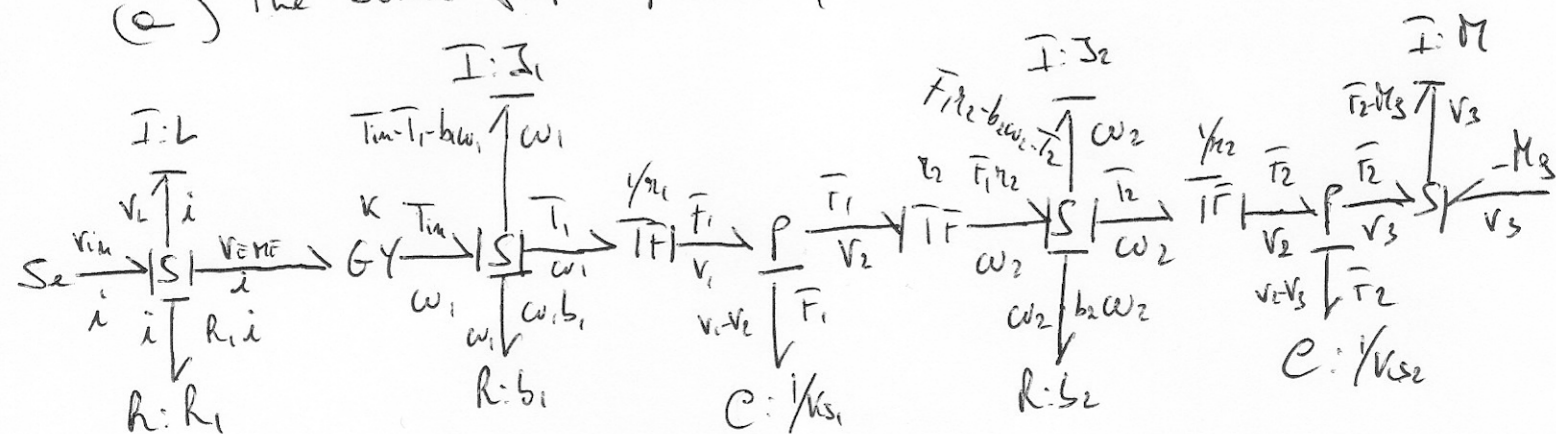


# PROBLEM 1

(1)

(a) The bond graph of the system is:



(b) Since the bond graph of (a) does not have any causality conflict the state space model will be an ODE.

Define

$$x_1 = i, \quad x_2 = \int_0^t \omega_2(\tau) d\tau, \quad x_3 = \omega_1, \quad x_4 = \int_0^t \omega_2(\tau) d\tau, \quad x_5 = \omega_2$$

$$x_6 = \int_0^t x_4, \quad x_7 = \dot{x}_4, \quad u = v_{in}$$

$$\dot{x}_1 = -\frac{r_1}{L} x_1 - \frac{\kappa}{L} x_2 + \frac{1}{L} u$$

$$\dot{x}_2 = x_3$$

$$\dot{x}_3 = \frac{\nu_1}{J_1} x_1 - \frac{b_1}{J_1} x_3 - \kappa \nu_1 (\nu_1 x_2 - \nu_2 x_4)$$

$$\dot{x}_4 = x_5$$

$$\dot{x}_5 = \frac{\nu_2 \kappa \nu_1}{J_2} (\nu_1 x_2 - \nu_2 x_4) - \frac{b_2}{J_2} x_5 - \kappa \nu_2 (\nu_2 x_4 - \nu_3 x_6)$$

$$\dot{x}_6 = x_7$$

$$\dot{x}_7 = \frac{\kappa \nu_2}{\nu_3 M} (\nu_2 x_4 - x_6) - \dots$$

(e) If the two elastic springs are removed, the state variables are constrained as follows:

$$\omega_1 = \frac{r_1}{r_2} \omega_2 \quad \text{and} \quad \omega_2 r_2 = \dot{x}$$

These additional algebraic equations, with the previous constitutive laws, form a system of DAE.

## PROBLEM 2

For a system, which is linear in the vector of parameters to estimate:

$$y(t) = \theta^T \varphi(t) + e(t)$$

the least squares formula is:

$$\hat{\theta} = \left[ \frac{1}{N} \sum_{t=1}^N \varphi(t) \varphi^T(t) \right]^{-1} \frac{1}{N} \sum_{t=1}^N \varphi(t) \cdot y(t)$$

Hence, in order to apply the LS formula to our system, we can rewrite it as follows:

$$\tilde{y}(t) = \theta^T \varphi(t) + e(t) \quad \text{with} \quad \tilde{y}(t) = y(t) - 0.1y(t-1)$$

$$\theta = \begin{bmatrix} \theta_1 \\ \theta_2 \end{bmatrix}$$

$$\varphi(t) = \begin{bmatrix} \cos y(t-2) \\ u(t) \end{bmatrix}$$

### PROBLEM 3

(3)

The system considered in this problem has transfer function:

$$G(s) = \frac{\omega(s)}{T(s)} = \frac{1/b}{1 + J/b \cdot s}$$

where  $\omega(s)$  and  $T(s)$  are the Laplace transforms of the rotational speed and the input torque, respectively.

The spectrum  $\overline{\Phi}_\omega(\omega)$  of  $\omega$  is:

$$\overline{\Phi}_\omega(\omega) = |G(j\omega)|^2 \overline{\Phi}_T(\omega) = |G(j\omega)|^2 = \frac{1/b^2}{1 + J^2/b^2 \omega^2}$$

### PROBLEM 4

1. TRUE
2. FALSE
3. FALSE
4. FALSE
5. FALSE