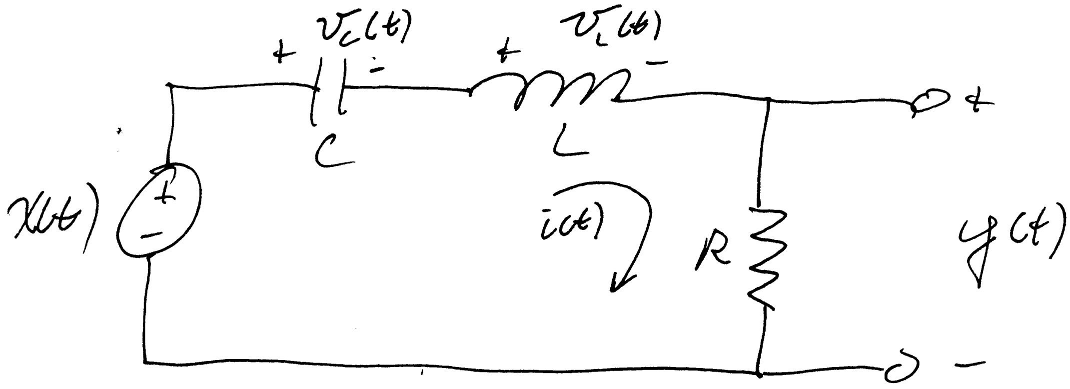
Examples of <u>Finding</u> Differential Equations for Electrical Systems

Example: Determine the Diff. Eq.



Write KVL around loop:

$$x(t) = v_C(t) + v_L(t) + y(t)$$

x(t) is the input so leave it
y(t) is the output so leave it (I screwed up and changed it but I fixed that later)
Now... V_C and V_L are NOT input or output variables so we need to re-write them in terms of the input and/or output!!
a good first step is to use their "device rules" that relate V-I

Should have left this as y(t)!!!

$$= \underbrace{\frac{1}{C}\int_{-\infty}^{t} i(\lambda)d\lambda}_{} + L\frac{di(t)}{dt} + Ri(t)$$

get rid of this by differentiating both sides

Then we notice that we have an integral and we can't have those in a DiffEq so we differentiate get rid of it!!!

Should have this as dy(t)/dt!!!

$$\Rightarrow \frac{dx(t)}{dt} = \boxed{\frac{1}{C}i(t) + L\frac{d^2i(t)}{dt^2}} + R\frac{di(t)}{dt}$$

These are *not* input or output variables so we need to replace them... here there is a simple connection between i(t) and y(t)

Now relate to output variable: $y(t) = i(t)R$

$\Rightarrow$ replace $i(t)$ by $y(t)/R$

$$\Rightarrow \boxed{\frac{L}{R}\frac{d^2y(t)}{dt^2} + \frac{dy(t)}{dt} + \frac{1}{RC}y(t) = \frac{dx(t)}{dt}}$$

Example #1

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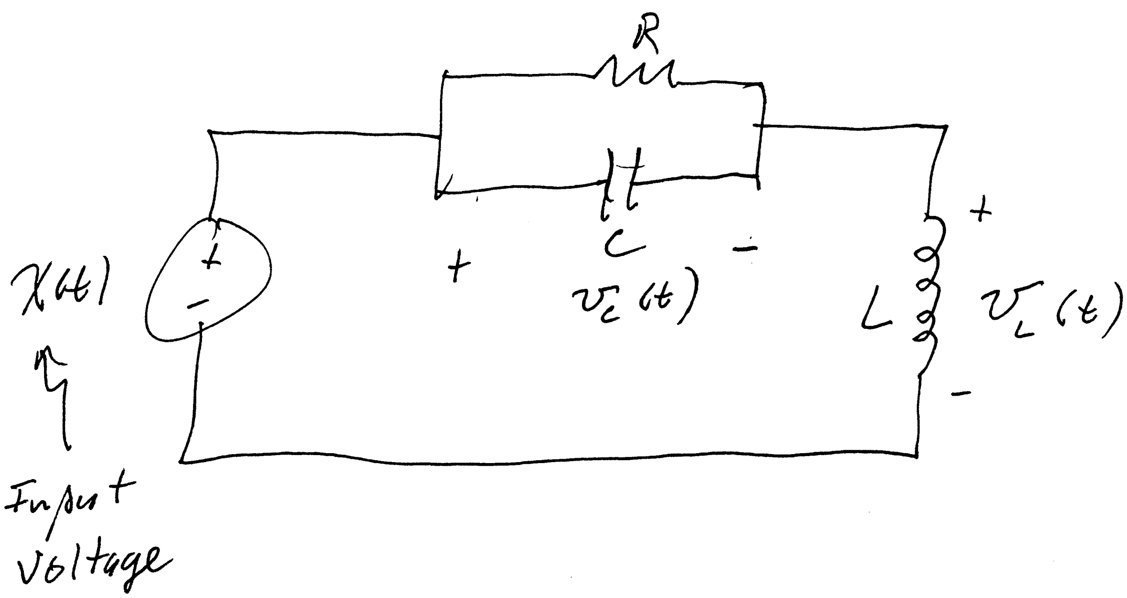
Determine the differential equation for this circuit ....



(a) ... when $v_L(t)$ is taken as the output

(b) ... when $v_c(t)$ is taken as the output

(B-1)

(a) From KVL: $v_R(t) + v_L(t) = x(t)$

or $v_R(t) = x(t) - v_L(t)$

or $i_R(t) = \dfrac{x(t) - v_L(t)}{R}$

or $v_C(t) = x(t) - v_L(t)$

because $v_C(t) = v_R(t)$ here

From KCL:

Could really start here w/ KCL:

$$i_L(t) = i_R(t) + i_C(t)$$

Now we use KVL and device rules to write as much as we can in terms of input & output

$$i_R(t) = \frac{x(t) - v_L(t)}{R}$$

From KVL above

$$i_C(t) = C\frac{dv_C(t)}{dt}$$

Device Rule

$$i_C(t) = C\left[\frac{dx(t)}{dt} - \frac{dv_L(t)}{dt}\right]$$

$$i_L(t) = \underbrace{\frac{x(t) - v_L(t)}{R} + C\frac{dx(t)}{dt} - C\frac{dv_L(t)}{dt}}_{\text{in terms of in's \& outs}} \quad (\star)$$

Now we have something that is almost completely in terms of in's & out's so we are almost there!!!

We need one more device rule...

Must relate to In's/outs

Device Rule

$$\frac{di_L(t)}{dt} = \frac{1}{L}v_L(t)$$

so diff. Right side of $(\star)$

We do this differentiation so we can plug this device rule in!!! When we do that we get the equation below

$$\frac{1}{L}v_L(t) = \frac{1}{R}\frac{dx(t)}{dt} - \frac{1}{R}\frac{dv_L(t)}{dt} + C\frac{d^2x(t)}{dt^2} - C\frac{d^2v_L(t)}{dt^2}$$

(c)

Re arrange to get:

$$\boxed{\frac{d^2 v_L(t)}{dt^2} + \frac{1}{RC}\frac{d v_L(t)}{dt} + \frac{1}{LC} v_L(t) = \frac{d^2 x(t)}{dt^2} + \frac{1}{RC}\frac{d x(t)}{dt}}$$

(b) From KVL: $v_c(t) + v_L(t) = x(t) \Rightarrow v_L(t) = x(t) - v_c(t)$

From device Rule for L:

$$v_L(t) = L\frac{di_L(t)}{dt}$$

use KCL: $i_L(t) = i_R(t) + i_c(t)$

$$= L\left[\frac{di_R(t)}{dt} + \frac{di_c(t)}{dt}\right]$$

$$\Rightarrow x(t) - v_c(t) = L\frac{d\overbrace{i_R(t)}}{dt} + L\frac{d\overbrace{i_c(t)}}{dt}$$

$$i_R(t) = \frac{v_R(t)}{R} = \frac{v_c(t)}{R} \qquad i_c(t) = C\frac{dv_c(t)}{dt}$$

$$\Downarrow$$

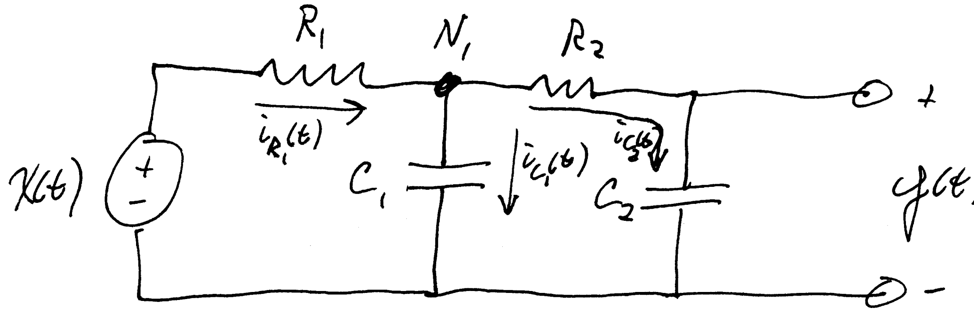
$$x(t) - v_c(t) = \frac{L}{R}\frac{dv_c(t)}{dt} + LC\frac{d^2 v_c(t)}{dt^2}$$

Re-Arrange:

$$\boxed{\frac{d^2 v_c(t)}{dt^2} + \frac{1}{RC}\frac{dv_c(t)}{dt} + \frac{1}{LC}v_c(t) = \frac{1}{LC}x(t)}$$

Example #2

Write the Diff. Eq. for the following "2-stage" RC circuit:



Node Eq. at N_1: (Node Equations are a form of KCL)

$$\underbrace{i_{R_1}(t)}_{\downarrow} = \underbrace{i_{C_1}(t)}_{\downarrow} + i_{C_2}(t)$$

$$\frac{x(t) - v_{C_1}(t)}{R_1} = C_1 \frac{dv_{C_1}(t)}{dt} + C_2 \frac{dy(t)}{dt} \qquad (\star)$$

Almost have what we want... need to get $v_{C_1}(t)$ out of the equation!

KVL around 2nd Mesh

$$v_{C_1}(t) = \underbrace{v_{R_2}(t)}_{} + y(t)$$

$$= R_2 i_{C_2}(t) = R_2 \left[C_2 \frac{dy(t)}{dt} \right]$$

$(\star\star)$

Use all this to eliminate $v_{C_1}(t)$

Put (★★) into (★) to get: (E)

First re-write (★):

$$C_2 \frac{dy(t)}{dt} + C_1 \frac{dv_{c_1}(t)}{dt} + \frac{1}{R_1} v_{c_1}(t) = \frac{1}{R_1} x(t)$$

From (★★) we get:

$$v_{c_1}(t) = R_2 C_2 \frac{dy(t)}{dt} + y(t)$$

and

$$\frac{dv_{c_1}(t)}{dt} = R_2 C_2 \frac{d^2 y(t)}{dt^2} + \frac{dy(t)}{dt}$$

We get:

$$C_1 R_2 C_2 \frac{d^2 y(t)}{dt^2} + \left(C_1 + \frac{R_2 C_2}{R_1} + C_2\right)\frac{dy(t)}{dt} + \frac{1}{R_1} y(t) = \frac{1}{R_1} x(t)$$

which could then be normalized by multiplying by $1/C_1 R_2 C_2$

DC Motor Example ("Armature Control")

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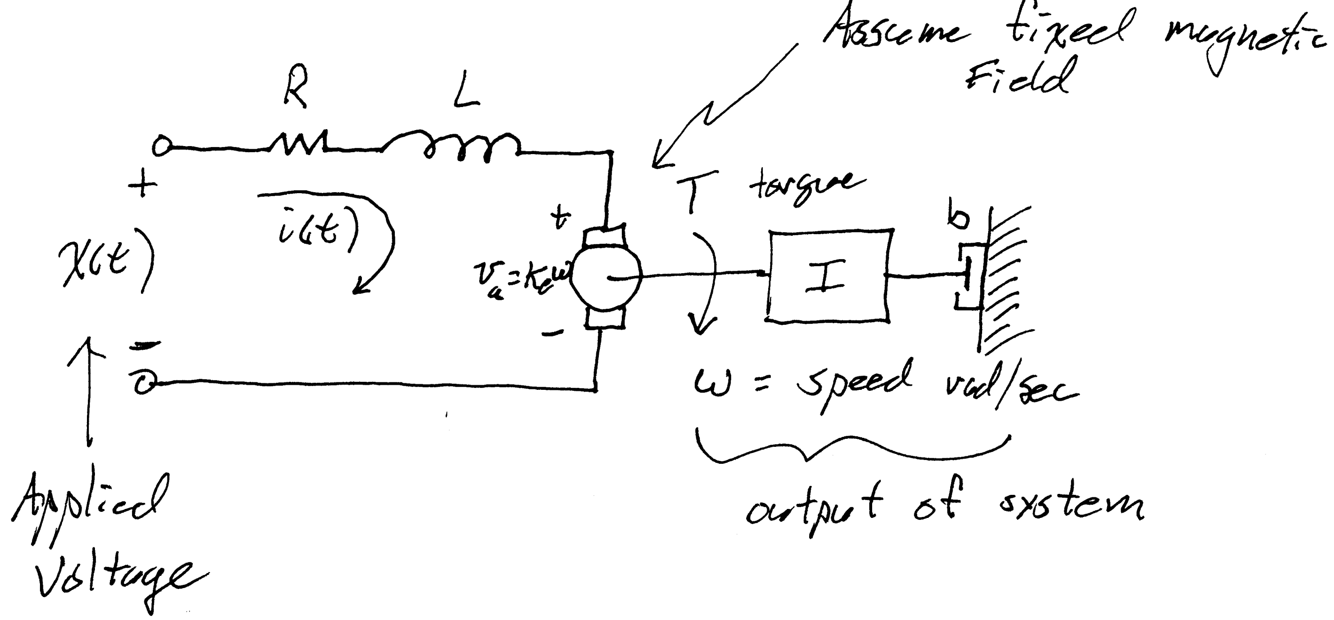

- DC Motor consists of $\underbrace{\text{lots of wire wound}}$ on an "armature"

  $\Rightarrow$ motor has "parasitic" R & L

- As motor armature turns, the coils cut magnetic flux lines $\Rightarrow$ $\underbrace{\text{induces voltage}}_{\text{proportional to speed}}$

$$v_a(t) = K_e\,\omega(t)$$

Now write KVL around the armature circuit:

$$x(t) = R\,i(t) + L\frac{di(t)}{dt} + K_e\,\omega(t) \qquad (*)$$

- The current $i(t)$ in the windings interacts w/ the magnetic field to create a force which provides the motor torque $T(t)$

$$T(t) = K_t\,i(t) \qquad (**)$$

Finally, rotational mechanics provides

$$T(t) = \underbrace{I\frac{d\omega(t)}{dt}}_{\substack{\text{Torque}\\ \text{due to}\\ \text{mass } I}} + \underbrace{b\,\omega(t)}_{\substack{\text{Torque}\\ \text{due to}\\ \text{friction}}} \qquad (\star\star\star)$$

Putting $(\star\star\star)$ into $(\star\star)$ and dividing by K_t gives:

$$i(t) = \frac{I}{K_t}\frac{d\omega(t)}{dt} + \frac{b}{K_t}\omega(t)$$

Now put this in $(\star)$ to get:

$$\boxed{\frac{LI}{K_t}\frac{d^2\omega(t)}{dt} + \left(\frac{RI + Lb}{K_t}\right)\frac{d\omega(t)}{dt} + \left(K_e + \frac{Rb}{K_t}\right)\omega(t) = x(t)}$$

$\Rightarrow$ Second-Order Diff. Eq.

$\Rightarrow$ <u>Could</u> be Oscillatory!