

Contents

Preface	vii
1 The concept of systems	1
1.1 Introduction	1
1.1.1 Definition of 'system'	2
1.1.2 Modelling	2
1.2 System boundary and elementary systems	6
1.2.1 Relations between subsystems and elementary systems	6
1.2.2 Interaction, feedback, most systems in nature	7
1.3 Dynamical systems and Creative Technology	9
1.3.1 Introduction	9
1.3.2 Electronics	10
1.3.3 Understand devices like a Segway	10
2 Dynamical Systems	13
2.1 Effects of actions only observable after some time	13
2.1.1 Introduction	13
2.1.2 Tax measures	13
2.1.3 Pig cycle	14
2.1.4 Foxes and Rabbits	15
2.1.5 Bank account	17
2.1.6 Water Vessel	18
2.1.7 Similarities between these systems	22
2.1.8 Storage	23
2.2 The role of feedback	24
2.2.1 Positive feedback	24
2.2.2 Negative feedback	24
2.2.3 Mechanical and electrical systems	25
3 Integrators in dynamical systems	27
3.1 Physical meaning of integration in the time domain	27
3.1.1 Introduction	27
3.1.2 Hydraulic systems: water tank	27
3.1.3 Mechanical systems: spring and mass	29
3.1.4 Electrical systems: capacitor and inductance	31
3.1.5 Initial conditions	32
3.2 Inverse operation: differentiation	33
3.2.1 Differential operator to represent a differentiator	34
3.3 Differential equations and transfer functions	34
3.3.1 First-order linear system	34
3.4 Overview of the different domains	38

4	Ideal physical models	39
4.1	Basic physical phenomena	39
4.1.1	Introduction	39
4.2	Ideal Physical Models	43
4.2.1	Introduction	43
4.2.2	Mechanical systems	44
4.2.3	Simulations of mechanical systems with IPM's	46
4.2.4	Electrical systems	48
4.2.5	Simulations of electrical systems with 20-sim	50
5	Numerical simulation	53
5.1	The need for numerical simulation	53
5.1.1	Introduction	53
5.2	Numerical integration	58
5.2.1	Difference versus differential equations	59
5.2.2	Euler integration	60
5.2.3	Tustin	64
5.2.4	More advanced methods	65
5.2.5	Sorting the equations	65
5.2.6	Accuracy versus efficiency	66
6	Electrical Circuits	69
6.1	Elementary models	69
6.1.1	Introduction	69
6.1.2	Elements	70
6.1.3	Sources	72
6.2	Computations	76
6.2.1	Kirchhoff's laws	78
6.2.2	Concept of impedance	80
6.2.3	Electrical networks	81
6.3	Computations versus simulations	87
6.4	Summary	87
7	Mechanical Systems	91
7.1	Elementary models	91
7.1.1	Introduction	91
7.1.2	Elements	93
7.1.3	Sources	95
7.2	Computations	96
7.2.1	Impedances	96
7.2.2	D'Alembert's law	96
7.3	Mechanical Systems	99
7.3.1	Cases	101
7.4	Summary	104

8	Domain Independent Descriptions	107
8.1	Introduction	107
8.1.1	Analogies	108
8.2	Power	109
8.2.1	Power ports	109
8.2.2	Graphical representation with power bonds	110
8.2.3	Signals versus power-port connections	113
8.3	Transducers	115
8.3.1	DC-motor	115
8.3.2	Tacho generator	117
8.3.3	Potentiometer	117
8.3.4	Other transducers	117
9	Bond graphs	121
9.1	Introduction	121
9.2	Junctions	122
9.3	Bilateral signal flows and causality	124
9.4	Deriving equations from a causal bond graph	128
9.5	Causality assignment	131
9.5.1	Causal conflicts	133
9.5.2	Causality assignment in 20-sim	135
9.5.3	Summary of this chapter	137
10	Review of Chapters 1-9	139
10.1	Introduction	139
10.2	System descriptions	141
10.2.1	(Causal) Relation diagrams	141
10.2.2	Ideal Physical Models	143
10.2.3	Bond graphs	145
10.2.4	Block diagrams	149
10.3	Physical domains	151
10.3.1	Electrical Systems	151
10.3.2	Mechanical Systems	157
10.3.3	Hydraulic Systems	160
10.3.4	Thermal Systems	161
10.4	Simulation	164
10.4.1	Preparing models for simulation	164
10.4.2	Deriving equations	165
10.5	To conclude	167
11	Feedback Control Systems	169
11.1	Introduction	169
11.2	Feedback as a property of the system	172
11.2.1	Biological and environmental systems	172
11.3	Feedback as a tool for changing a system's behaviour	174
11.4	Basic properties of feedback systems	179

11.4.1	Feedback of first-order systems	180
11.4.2	Feedback of second-order systems	183
11.4.3	Feedback of third-order systems	185
11.4.4	PID-control	185
11.4.5	Control of unstable systems	187
11.5	Conclusion	190
12	Operational amplifiers	193
12.1	Introduction	193
12.2	Ideal operational amplifiers	195
12.2.1	Operational amplifiers with impedances	199
12.2.2	Analogue simulation	202
12.2.3	Multiple views	206
12.2.4	Review	207
13	Embedded control systems	209
13.1	Computers used as controllers	209
13.2	Digital control of continuous-time systems	210
13.2.1	Sampling	210
13.2.2	AD- and DA-conversion	212
13.3	Stability	216
13.4	Theoretical limits of the sampling frequency	218
13.4.1	Noise	220
13.5	Summary	223
A	Tables and symbols	225
A.1	Formulas for several physical domains	225
A.2	Icons	226
A.2.1	Electrical domain	226
A.2.2	Mechanical domain (translation)	227
A.2.3	Mechanical domain (rotation)	228
A.3	Causality assignment	229
A.4	Summary of formulas and representations	231
A.5	Blockdiagrams	233
A.6	Operational amplifiers	234