

Process Dynamics And Control Seborg Solution Manual 3rd

$$\begin{aligned} \mathcal{A}^{11} &= \frac{j}{2\omega} \left[\frac{(-\omega^2 - js_1\omega - js_2\omega + s_1s_2) - (-\omega^2 + js_1\omega + js_2\omega + s_1s_2)}{(s_1^2 + \omega^2)(s_2^2 + \omega^2)} \right] \\ \mathcal{A}^{11} &= \left[\frac{(s_1 + s_2)}{(s_1^2 + \omega^2)(s_2^2 + \omega^2)} \right] \text{ similarly } \mathcal{B}^{11} = \left[\frac{(s_1s_2 - \omega^2)}{\omega(s_1^2 + \omega^2)(s_2^2 + \omega^2)} \right] \\ \text{using } s_1 + s_2 &= -\frac{2\xi}{\tau} s_1s_2 = \frac{1}{\tau^2} \\ &= s_1^2 + s_2^2 = \frac{4\xi^2}{\tau^2} - \frac{2}{\tau^2} = \frac{2(2\xi^2 - 1)}{\tau^2} \\ \mathcal{A}^{11} &= \frac{A\omega}{\tau^2} \left[\frac{-\frac{2\xi}{\tau}}{\frac{1}{\tau^4} + \frac{2\omega^2}{\tau^2}(2\xi^2 - 1) + \omega^4} \right] \\ &= \frac{-\frac{2A\omega\xi}{\tau^2}}{(\omega^2 - \frac{1}{\tau^2})^2 + (\frac{2\xi\omega}{\tau})^2} = \frac{-2A\omega\xi\tau}{(1 - (\omega\tau)^2)^2 + (2\xi\omega\tau)^2} \\ \text{and } \mathcal{B}^{11} &= \frac{A\overline{\omega}}{\tau} \left[\frac{\left(\frac{1}{\tau^2} - \omega^2\right)}{\omega\left(\left(\frac{1}{\tau^2} - \omega^2\right)^2 + \left(\frac{2\xi\omega}{\tau}\right)^2\right)} \right] \\ &= \frac{A(1 - (\omega\tau)^2)}{(1 - (\omega\tau)^2)^2 + (2\xi\omega\tau)^2} \end{aligned}$$

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