

Ch. 10 Sinusoidal steady-state analysis

(4) Conversion between "rad" and "deg";

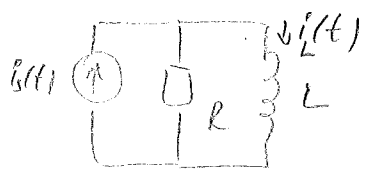
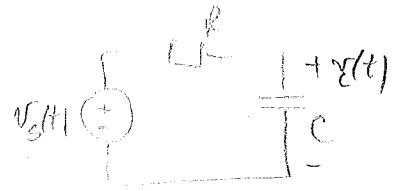
$$(1) \begin{cases} \cos(u \pm v) = \cos u \cdot \cos v \mp \sin u \cdot \sin v \\ \sin(u \pm v) = \sin u \cdot \cos v \pm \cos u \cdot \sin v \end{cases}$$

$$(2) \begin{cases} A \cos(\omega t) + B \sin(\omega t) = M \cdot \cos(\omega t + \phi) \\ M = \sqrt{A^2 + B^2}; \quad A = M \cos \phi \\ \phi = \tan^{-1}\left(\frac{B}{A}\right); \quad B = M \sin \phi \end{cases}$$

$$\omega = 2\pi f = \frac{2\pi}{T}; \quad T = \text{period.}$$

(3) "ELI the ICE man": voltage leads current for L, current leads voltage for C.

Recall that we studied:



General form: $\tau \frac{dy(t)}{dt} + y(t) = x(t)$

$$\begin{cases} y(t) = v_c(t) \\ \tau = RC \end{cases}$$

$$\begin{cases} y(t) = i_L(t) \\ \tau = \frac{L}{R} \end{cases}$$

We derived for $x(t) = X_m \cos \omega t$ as forcing-function, the general (complete) solution:

$$y(t) = \underbrace{y(0) \cdot e^{-\frac{t}{\tau}}}_{= \text{natural}} + \underbrace{\frac{X_m}{1 + (\omega\tau)^2} (\cos \omega t + \omega\tau \sin \omega t - e^{-\frac{t}{\tau}})}_{= \text{forced}}$$

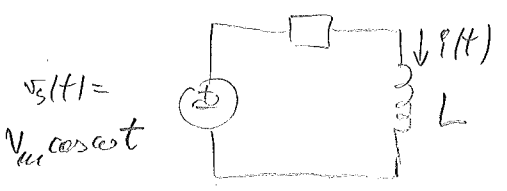
$$y(t) = \underbrace{\left[y(0) - \frac{X_m}{1 + (\omega\tau)^2} \right] e^{-\frac{t}{\tau}}}_{= \text{transient}} + \underbrace{\frac{X_m}{\sqrt{1 + (\omega\tau)^2}} \cdot \cos(\omega t - \tan^{-1} \omega\tau)}_{= \text{ss (steady-state)}} = Y_m \cdot \cos(\omega t + \phi)$$

Today, we are interested in the steady-state response only!

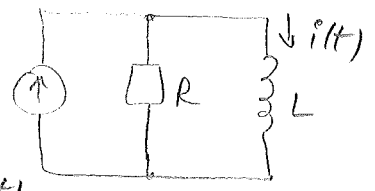
Note: the textbook refers to the steady-state response as the forced-response (we'll tolerate that for the time-being).

Example 1:

R



=>



$$i(t) = \frac{V_m}{\omega L} \cos \omega t = I_m \cos \omega t$$

This is an equivalent circuit for which we know the steady-state solution: $I_m = I_m$; $\phi = \frac{L}{R}$.

$$i_{ss}(t) = \frac{I_m}{\sqrt{1 + (\omega \phi)^2}} \cdot \cos(\omega t - \tan^{-1} \omega \phi) ; \quad \phi = \frac{L}{R}$$

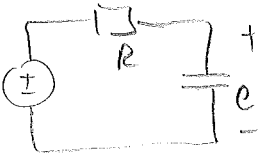
$$i_{ss}(t) = \frac{V_m}{R \sqrt{1 + \omega^2 \frac{L^2}{R^2}}} \cdot \cos(\omega t - \tan^{-1} \frac{\omega L}{R})$$

(1)
$$i_{ss}(t) = \frac{V_m}{\sqrt{R^2 + (\omega L)^2}} \cdot \cos(\omega t - \tan^{-1} \frac{\omega L}{R}) = \underbrace{\frac{V_m}{\sqrt{R^2 + (\omega L)^2}}}_{= I_m^{ss}} \cdot \cos(\omega t + \underbrace{\phi}_{\text{angle or phase}})$$

(cf. Eq. in textbook)

Example 2:

$$v_s(t) = V_m \cos \omega t$$



$$v_C(t) = v_C^{transient}(t) + \boxed{v_C^{ss}(t)}$$

we are interested in today!

Solution is:

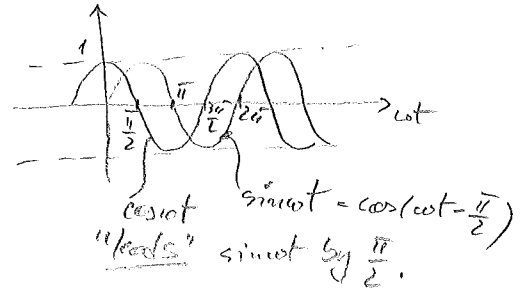
(2)
$$v_C^{ss}(t) = \frac{V_m}{\sqrt{1 + (\omega RC)^2}} \cdot \cos[\omega t - \tan^{-1}(\omega RC)] = \underbrace{V_m^{ss}}_{\text{magnitude}} \cdot \cos[\omega t + \underbrace{\phi}_{\text{phase}}]$$

Observations:

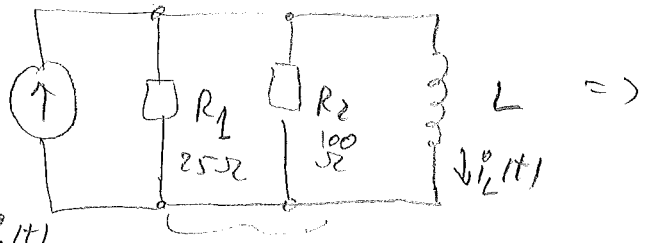
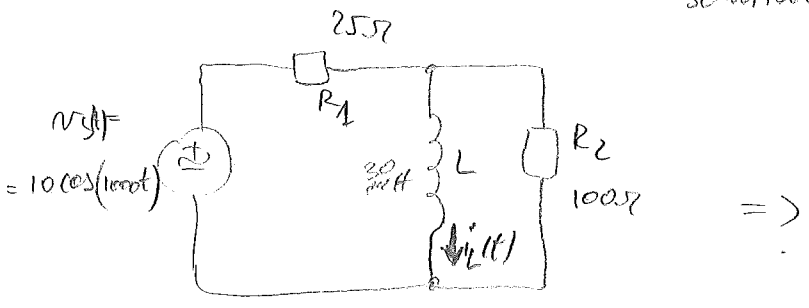
- (1) - Steady-state response has the same functional form as the forcing function
- (2) - Amplitude of the response (steady-state) is proportional to the amplitude of the forcing function!
- (3) - diverges with $R, L, C,$ and $\omega!$

(3) - Response lags the applied forcing function by $\tan^{-1} \omega L = -\phi$

↳ please read details in textbook on lag and lead!

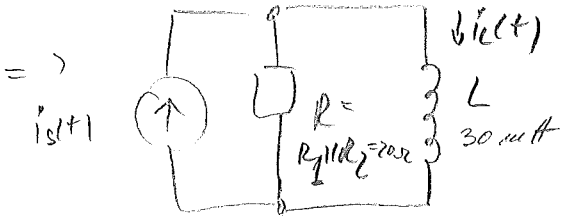


Example 3: (10.1 pp. 374) Find SS (steady-state) solution of $i_L(t)$!



$$i_s(t) = \frac{10}{25} \cos(1000t) = I_m \cos(\omega t) = 0.4 \cos(1000t)$$

$$R_s = R_1 || R_2 = \frac{25 \cdot 100}{25 + 100} = \frac{2500}{125} = 20 \Omega$$



Solution is:

$$i_L(t) = \frac{I_m}{\sqrt{1 + \left(\frac{\omega L}{R}\right)^2}} \cdot \cos\left(\omega t - \tan^{-1}\left(\frac{\omega L}{R}\right)\right) = I_m^{SS} \cdot \cos(\omega t + \phi)$$

$$= \frac{\frac{10}{25} \cdot R_s}{\sqrt{R_s^2 + (\omega L)^2}} \cdot \cos\left(\omega t - \tan^{-1}\left(\frac{30}{20}\right)\right)$$

$$= \frac{8}{\sqrt{1300}} \cdot \cos\left[\omega t - \tan^{-1}\left(\frac{30}{20}\right)\right] = 0.222 \cos\left(\omega t - \tan^{-1}\left(\frac{30}{20}\right)\right) [A]$$