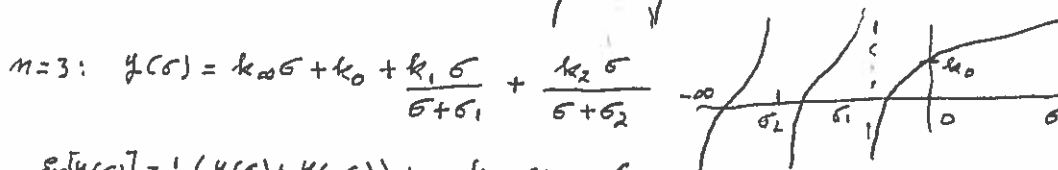
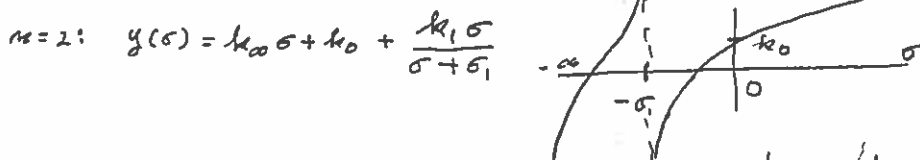
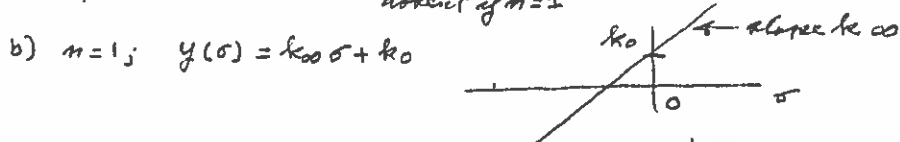
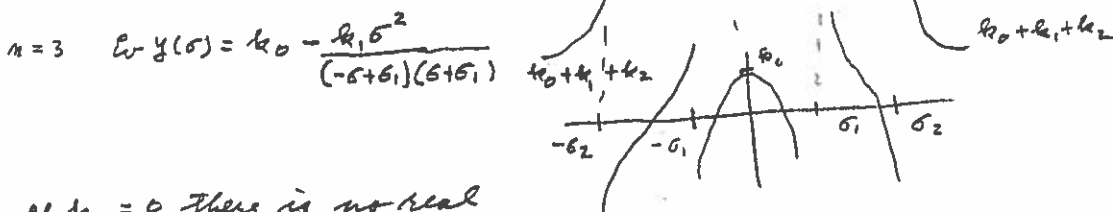
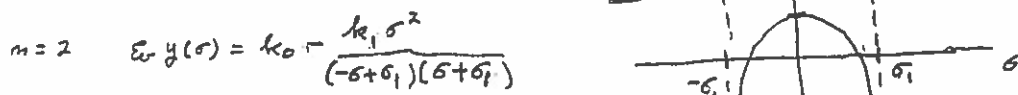
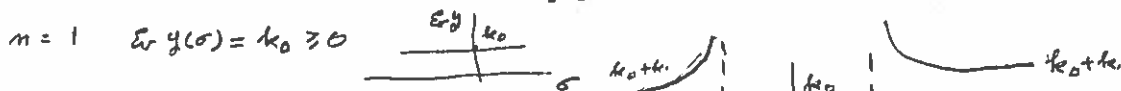


1. a) $y(\sigma) = k_{\infty}\sigma + k_0 + \sum_{i=1}^{m-1} \frac{k_i\sigma}{\sigma + \sigma_i}$; $k_i, \sigma_i > 0$ for $i=1, \dots, m-1, \infty$; $k_0 \geq 0$
 $\sigma_i < \sigma_{i+1}$; $\frac{dy(\sigma)}{d\sigma} > 0$
attract if $m=1$

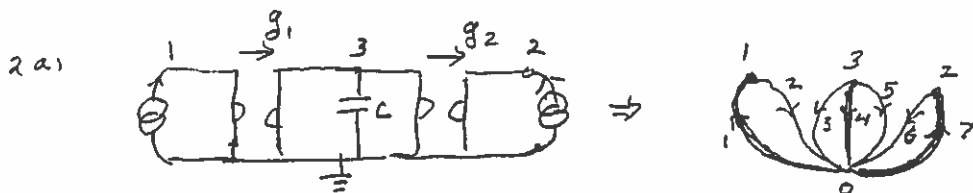


c) $E_r[y(\sigma)] = \frac{1}{2}(y(\sigma) + y(-\sigma))$; k_{∞} cancels
 $= k_0 + \frac{1}{2} \sum_{i=1}^{m-1} \left[\frac{k_i\sigma}{\sigma + \sigma_i} + \frac{-k_i\sigma}{-\sigma + \sigma_i} \right] = k_0 + \sum_{i=1}^{m-1} \frac{-k_i\sigma^2}{(-\sigma^2 + \sigma_i^2)}$



if $k_0 = 0$ there is no real zero between $\sigma = 0$ & $\sigma = \sigma_1$
 (in the case of $m=1$, $E_r y(\sigma) \equiv 0$)

d) if $k_0 > 0$ there is a finite real zero for all $m > 1$
 but if $k_0 = 0$ not for $m=1$, i.e. Richards sections
 can proceed with real c-gyator sections for all $m > 2$
 and if $k_0 > 0$ also for $m=1$



b) cut set: $Q_z = E i_b \Rightarrow E = \begin{bmatrix} 1 & -1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & -1 \end{bmatrix}$

tree set: $Q_x = T v_b \Rightarrow T = \begin{bmatrix} 1 & 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & -1 & 0 & 0 & 0 \\ 0 & 0 & 0 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 & 1 \end{bmatrix}$

c) $Y_{\text{node}}(s) = \begin{bmatrix} 0 & 0 & g_1 & -g_1 \\ 0 & 0 & -g_2 & g_2 \\ -g_1 & g_2 & sC & g_1 - g_2 - sC \\ g_1 & -g_2 & -g_1 + g_2 - sC & sC \end{bmatrix}$ (last row & column by sum of others)

d) grounding node 1 $\Rightarrow Y_{\text{node}}(s) = \begin{bmatrix} 0 & 0 & g_1 \\ 0 & 0 & -g_2 \\ -g_1 & g_2 & sC \end{bmatrix}$; to eliminate node 3 set $i_3 = 0$

$i_3 = 0 \Rightarrow \begin{bmatrix} -g_1 & g_2 & sC \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \end{bmatrix} = 0 \Rightarrow v_3 = -\frac{1}{sC} \begin{bmatrix} -g_1 & g_2 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \end{bmatrix}$

$\Rightarrow \begin{bmatrix} i_1 \\ i_2 \end{bmatrix} = \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \end{bmatrix} - \begin{bmatrix} g_1 \\ -g_2 \end{bmatrix} \frac{1}{sC} \begin{bmatrix} -g_1 & g_2 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \end{bmatrix}$

$\Rightarrow Y_{\text{port}}(s) = \frac{1}{sC} \begin{bmatrix} g_1^2 & -g_1 g_2 \\ -g_2 g_1 & g_2^2 \end{bmatrix}$ (note this is of rank 1 = degree 1 \Rightarrow one h & a transformer)

e) $y_{in} = y_{11} - y_{12} \frac{L}{y_{22} + y_L} \cdot g_{21} = \frac{\Delta y + y_{11} y_L}{y_{22} + y_L} = \frac{0 + \frac{g_1^2}{sC} \cdot sC_2}{\frac{g_2^2}{sC} + sC_2} = \frac{g_1^2}{sC_2 + g_2^2/sC}$
 $= \frac{g_1^2 sC}{g_2^2 + (s^2 C C_2)}$

f) this is RC only when either $C_2 = 0$ (or trivially if $C = 0$)

$$x_3, a) \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} -3 & 0 \\ 0 & -6 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 3u_1 = 3u \\ 2u_2 = 2y_1 = 2x_1 \end{bmatrix}, y = y_2 = \begin{bmatrix} 0 & 5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

which is

$$\begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} -3 & 0 \\ 2 & -6 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 3 \\ 0 \end{bmatrix} u, y = \begin{bmatrix} 0 & 5 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}; x = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

$$b) T(a) = \begin{bmatrix} 0 & 5 \end{bmatrix} \begin{bmatrix} a+3 & 0 \\ -2 & a+6 \end{bmatrix}^{-1} \begin{bmatrix} 3 \\ 0 \end{bmatrix}; (aI_2 - A)^{-1} = \frac{1}{(a+3)(a+6)} \begin{bmatrix} a+6 & 0 \\ 2 & a+3 \end{bmatrix}$$

$$= 5 \cdot \frac{2}{(a+3)(a+6)} \cdot 3 = \frac{30}{(a+3)(a+6)}$$

$$c) \left[\begin{array}{c|c} i = u & C \\ -ic_1 & -A \\ -ic_2 & \end{array} \right] = \left[\begin{array}{c|c} 0 & C \\ -B & -A \end{array} \right] \quad \left[\begin{array}{c} u=v \\ v_{c1} \\ v_{c2} \end{array} \right] = Y_C \begin{bmatrix} v \\ x \end{bmatrix}$$

$$\Rightarrow Y_C = \left[\begin{array}{c|cc} 0 & 0 & 5 \\ -3 & 3 & 0 \\ 0 & -2 & 6 \end{array} \right]$$

