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TECHNICAL REPORT ARLCD-TR-85025

**AN ANALYTICAL MODULARIZED TREATMENT OF AUTOPILOTS
FOR GUIDED PROJECTILE SIMULATIONS**

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20. ABSTRACT (cont)

steps associated with the lower frequencies of airframe dynamics which results in faster simulation execution and considerable savings in cost and execution time.

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INTRODUCTION

A substantial need has been demonstrated within Armament Research and Development Center (ARDC) for a convenient-to-use and computationally efficient flight simulation for smart munitions. The simulation must be easily adaptable to varying projectile designs and especially to changes in autopilots which undergo rapid evolution. During the design cycle of the projectile, a large number of individual flight simulations must be performed. As an example, during the development of the Copperhead projectile, the ARDC scientific computers were overwhelmed by the workload and a substantial amount of the available time on the BRL CDC 7600 supercomputer was dedicated to the computations. In spite of the continuous development and improvement in computer systems, flight simulations will continue to provide a substantial workload which must be accomplished efficiently.

To meet this need, ARDC is formulating methods and writing modular software for rapidly developing autopilot simulations for guided projectiles and munitions. An innovative technique was developed by which exact analytical solutions to the required transfer functions are applied in a piecewise manner within a larger but lower frequency problem which must be solved numerically.

Since the time constants associated with the autopilot components are often small compared with their driving terms, the integration time step is driven to very small values to obtain stable numerical integrations which results in very long computer run times. The use of piecewise analytical solutions to the transfer functions guarantees valid integration of the autopilot transfer functions regardless of the integration time step, provided that the driving terms vary inappreciably over the time step. This is a less stringent requirement than is needed for stable numerical integration since the driving term rates are commensurate with the airframe time constants, which are typically large compared to that of the autopilot.

Five transfer functions were solved in closed form to provide a fast executing computer code. These particular transfer functions were selected since an autopilot can generally be represented by a concatenation of these functions to rate sensors, switches, limiters, and dead zones.

DISCUSSION

Apart from switches, limiters, and dead zones, autopilot transfer functions are Laplace transform representations of differential equations. Incorporated into a digital simulation, transfer functions are converted into differential equations and are usually solved numerically. Sometimes this causes considerably longer run times than simulation of unguided projectiles.

The time step required to perform the integration is driven by two constraints: (1) The driving term or input must not vary appreciably in the time step. (2) The time step must be sufficiently small to insure a stable

integration. If the time constants associated with the autopilot are small compared to those of the airframe (which is typical), the integration time step will be driven to very small values and run times will be very long. Since the driving term is a product of the airframe motion, an inherently slower process, stable integration is a stronger driver to fine integration than the driving term's remaining essentially constant during the integration time step. By analytically solving these transfer functions stepwise with constant driving terms, the second constraint is eliminated. The size of the integration time step is limited only by the first constraint. Therefore, the use of closed form, analytic, stepwise solutions subject only to the first constraint can lead to larger integration time steps and shorter run times.¹

Only five transfer functions are needed to handle the typical autopilot: the first-order lag, the first-order lag with differentiation, the first-order lead/lag, the first-order lag with integrator, and the second-order lag/oscillator. (Guidance and control systems often contain rate sensors. The treatment of rate sensors will be published in a separate report.) These transfer functions are described and solved analytically below; the computer code implementing the solutions is shown in appendix A.²

Throughout this development, the driving term is assumed not to vary appreciably during a time step. Care must be taken to adjust the time step downward as necessary to satisfy this requirement. To take advantage of this technique for reducing run time, the time step should be increased whenever the driving terms are varying slowly.

ANALYSIS

First-Order Lag

A first-order lag is represented by the Laplace operator s as

$$1/(Ts + 1)$$

In differential equation form

$$T \, dy/dt + y = D \tag{1}$$

¹ Michael J. Amoruso and Dennis D. Ladd, "TELUM, A Comprehensive Digital Flight Simulation of the Copperhead Projectile," Special Publication ARLCD-SP-82003, U.S. Army Armament Research and Development Command, Dover, NJ, June 1982.

² Analytical methods used in this study were derived from John J. D'Azzo and Constantine H. Houpis, Feedback Control Systems Analysis and Synthesis, McGraw-Hill, New York, 1960; and Murray R. Spiegel, Applied Differential Equations, Prentice-Hall, Englewood Cliffs, NJ, 1958.

where

y = output or dependent variable

t = time or independent variable

T = time constant

D = driving term

The general solution to equation 1 is the sum of a particular solution and a general solution to the homogeneous form. The homogeneous equation was obtained by setting D to zero and can be written as

$$-T \, dy/y = dt$$

which can be verified to yield the solution

$$y = e^{-(t - A)/T} \quad (2)$$

where A is the integration constant determined from the initial conditions $y = y_0$ at $t = t_0$. Using the initial conditions yields the general solution to the homogeneous equation 2.

$$y = y_0 e^{-(t - t_0)/T} \quad (3)$$

For a particular solution to equation 1, the expression is verified by substitution

$$y = \left[1 - e^{-(t - t_0)/T} \right] D \quad (4)$$

Adding equations 3 and 4 gives the complete general solution

$$y(t) = y_0 e^{-(t - t_0)/T} + \left[1 - e^{-(t - t_0)/T} \right] D \quad (5)$$

Note that equation 5 has the correct limit of D as T goes to zero.

First-Order Lag with Differentiation

This transfer function has the Laplace operator representation

$$s/(Ts + 1)$$

or the time domain form

$$T \, dy/dt + y = dD/dt \quad (6)$$

This representation is not desirable since the driving term appears as a time derivative that would generally have to be evaluated numerically. However, equation 6 can be recast as a pair of coupled differential equations that do not contain any derivatives of the driving term D . An auxiliary variable z is introduced and the equation is replaced by the expressions

$$dz/dt = y \quad (7)$$

and

$$y = (D - z)/T \quad (8)$$

Differentiating equation 8 and using equation 7 to eliminate dz/dt verifies that these two equations are equivalent to equation 6. Note that the derivative of D does not appear. By combining equations 7 and 8, the expression for $z(t)$ is obtained,

$$dz/dt + z/T = D/T \quad (9)$$

and, after integration, the results for $z(t)$ substituted into equation 8. Equation 9 can be integrated from equation 5 by noting the identity of equations 1 and 9. Therefore,

$$y(t) = e^{-(t - t_0)/T} (D - z_0)/T \quad (10)$$

where $z_0 = z$ at $t = t_0$. The auxiliary variable z_0 can be eliminated by using equation 8.

$$y(t) = \left\{ \frac{e^{-(t-t_0)/T}}{T} \right\} (D - D_0) + y_0 e^{-(t-t_0)/T} \quad (11)$$

Note that the exponential over T goes to $1/(t - t_0)$ by L'Hospital's rule so that equation 11 has the correct limit dD/dt as T goes to zero.

First-Order Lead/Lag

This transfer function is represented by

$$(T_2 s + 1)/(T_1 s + 1) \quad T_1 \neq 0$$

or

$$T_1 dy/dt + y = T_2 dD/dt + D \quad (12)$$

The derivative of the driving term is usually not available in analytic form. It is eliminated by introducing an auxiliary variable, z , and a pair of coupled equations

$$dz/dt = (D - y)/T_1 \quad (13)$$

and

$$y = (T_2/T_1) D + z \quad (14)$$

The equivalence with equation 14 can be verified by differentiating it and then eliminating dz/dt with equation 13. To obtain an expression for $y(t)$, integrate equation 14 as follows:

$$T_1 dz/dt + z = (1 - T_2/T_1) D \quad (15)$$

This is obtained by substituting equation 14 into equation 13, and then substituting the result for $z(t)$ into equation 14 to obtain $y(t)$. The explicit solution will not be written. Instead, an algorithm will be provided based on the observation that equation 15 is equivalent to equation 1 if the following substitutions are made:

$$T_1 \rightarrow T \quad z \rightarrow y \quad (1 - T_2/T_1)D \rightarrow D \quad (16)$$

Algorithm:

1. Substitute equation 16 into equation 5 to obtain $z(t)$.
2. Save $z(t)$ for use as z_0 in the next integration step.
3. Substitute $z(t)$ into equation 14 to obtain $y(t)$.

Note that the lag time constant cannot be zero in equation 16, but a vanishing lead time constant yields the correct limiting case of a simple first-order lag.

First-Order Lag with Integrator

The representation of this transfer function is

$$1/s (Ts + 1)$$

or

$$T \, d^2y/dt^2 + dy/dt = D \quad (17)$$

Substitution verifies that the following expression is a particular solution to the nonhomogeneous differential equation 17 since, by assumption, D is constant during the integration time step:

$$y = Dt \quad (18)$$

The homogeneous form of equation 17 can be written as the coupled equations

$$T \, dz/dt + z = 0 \quad (19)$$

and

$$z = dy/dt \quad (20)$$

Equation 19 is similar to equation 1 with the substitution of z for y and zero for D ; therefore, the solution can be obtained from equations 2 and 20

$$dy/dt = z(t) = e^{-(t - A)/T}$$

or

$$y(t) = -Te^{-(t - A)/T} + B \quad (21)$$

The complete solution to equation 17 is the sum of the general homogeneous solution (eq 21) and the particular nonhomogeneous solution (eq 18)

$$y(t) = -Te^{-(t - A)/T} + Dt + B \quad (22)$$

$$dy/dt = e^{-(t - A)/T} + D \quad (23)$$

The integration constants A and B can be determined by invoking the initial conditions $y = y_0$ and $dy/dt = y'$ at $t = t_0$

$$y_0 = -Te^{-(t_0 - A)/T} + Dt_0 + B \quad (24)$$

$$y' = e^{-(t_0 - A)/T} + D \quad (25)$$

The integration constant A can be eliminated from equation 24 by using equation 25 to eliminate the exponential term and solving for B

$$B = y_0 + T (y' - D) - Dt_0 \quad (26)$$

Taking the natural logarithm of equation 25 yields

$$A = T \ln (y' - D) + t_0 \quad (27)$$

The explicit solution is therefore

$$y(t) = y_0 + T (y' - D) \left[1 - e^{-(t - t_0)/T} \right] + D (t - t_0) \quad (28)$$

and

$$dy/dt = (y' - D) e^{-(t - t_0)/T} + D \quad (29)$$

Note that equations 28 and 29 go to the correct limits if T goes to zero.

Second-Order Lag/Oscillator

This transfer function can be represented in the form

$$1/(Is^2 + Ds + K) \quad K \neq 0, I \neq 0$$

or

$$I \, d^2y/dt^2 + dy/dt + Ky = T \quad (30)$$

The homogeneous solution to equation 30 can be verified to be

$$y(t) = e^{Lt} \quad (31)$$

by substituting into the homogeneous form of equation 30 to obtain the characteristic equation

$$IL^2 + DL + K = 0 \quad (32)$$

which has the following roots:

$$M = \left[-D + (D^2 - 4 IK)^{1/2} \right] / 2I \quad (33)$$

$$N = \left[-D - (D^2 - 4 IK)^{1/2} \right] / 2I \quad (34)$$

The following three cases are treated separately according to whether the radicand is positive, negative, or zero.

Case 1. Positive radicand, damped solution

The homogeneous and nonhomogeneous particular solutions can be verified to be

$$y_H(t) = Ae^{Mt} + Be^{Nt} \quad (35)$$

$$y_P(t) = T/K \quad (36)$$

The complete solution is

$$y(t) = Ae^{Mt} + Be^{Nt} + T/K \quad (37)$$

$$dy/dt = MAe^{Mt} + NBe^{Nt} \quad (38)$$

The initial conditions $y_0 = y$ at t_0 and $y' = dy/dt$ at t_0 determine the constants A and B.

$$y_0 = Ae^{Mt_0} + Be^{Nt_0} + T/K \quad (39)$$

$$y' = MAe^{Mt_0} + NBe^{Nt_0} \quad (40)$$

Solving simultaneously gives

$$B = (y_0 - y'/M - T/K)e^{-Nt_0} / (1 - N/M) \quad (41)$$

$$A = (y_0 - y'/N - T/K)e^{-Mt_0} / (1 - M/N) \quad (42)$$

Case 2. Zero radicand, critically damped

The characteristic equation has only one distinct root

$$L = -D/2I \quad (43)$$

The homogeneous general solution and nonhomogeneous particular solution can be verified to be

$$y_H(t) = Ae^{Lt} + Bte^{Lt} \quad (44)$$

$$y_H(t) = T/K \quad (45)$$

The complete solution is

$$y(t) = (A + Bt)e^{Lt} + T/K \quad (46)$$

$$dy/dt = (LA + B + LBt)e^{Lt} \quad (47)$$

Using the initial conditions $y_0 = y$ at t_0 and $y' = dy/dt$ at t_0 , the integration constant can be determined as follows:

$$y_0 = (A + Bt_0)e^{Lt_0} + T/K \quad (48)$$

$$y' = (LA + B + LBt_0)e^{Lt_0} \quad (49)$$

$$B = e^{-Lt_0} [y' + L(T/K - y_0)] \quad (50)$$

$$A = [(y_0 - t/K)(1 + Lt_0) - t_0 y']e^{-Lt_0} \quad (51)$$

Case 3. Negative radicand, oscillation

The roots of the characteristic equation become complex numbers

$$\omega = \left[(K/I) - (D/2I)^2 \right]^{1/2} \quad (52)$$

The homogeneous and nonhomogeneous particular solutions are

$$y_H(t) = Ae^{Lt} \sin(\omega t + \phi) + T/K \quad (53)$$

$$y_H(t) = T/K \quad (54)$$

where A and ϕ are integration constants. The complete solution is

$$y = Ae^{Lt} \sin(\omega t + \phi) + T/K \quad (55)$$

$$dy/dt = LAe^{Lt} \sin(\omega t + \phi) + \omega Ae^{Lt} \cos(\omega t + \phi) \quad (56)$$

Using the initial conditions y_0 and y' and solving for A in the expression for y_0 gives

$$A = (y_0 - T/K)e^{-Lt_0} / \sin(\omega t_0 + \phi) \quad (57)$$

where

$$\sin(\omega t_0 + \phi) \neq 0 \quad (58)$$

If equation 58 fails, A can be obtained from the expression for y'

$$A = y'e^{-Lt_0} / [L \sin(\omega t_0 + \phi) + \omega \cos(\omega t_0 + \phi)] \quad (59)$$

Since ω in equation 52 is always positive definite and the sine and cosine are orthogonal, either equation 57 or 59 is always defined. Note that the expressions still contain the phase angle ϕ . Solving for ϕ yields the same result whether equation 57 is substituted into the initial condition on dy/dt or equation 59 into the initial condition on y .

$$\phi = \tan^{-1} \left[\frac{\omega (y_0 - T/K)}{[y' - L(y_0 - T/K)]} \right] - \omega t_0 \quad (60)$$

The phase ϕ can be eliminated in equation 57 or 59 by substituting equation 60. Equation 60 shows that equation 58 is equivalent to

$$y_0 - T/K = 0 \quad (61)$$

The imposition in equation 30 of the requirement that parameters K and I not vanish was necessary for the validity of the solutions. For example, equations 36, 45, and 54 become singular when K vanishes. Similarly, the roots of the characteristic equation are singular if I is zero (eqs 33, 45, and 52). This is not a limitation since equation 30 reduces to a first-order lag with integrator when K vanishes and to a simple first-order lag when I vanishes.

However, the parameter D in equation 30 may be zero. If D vanishes, the characteristic equation 32 degenerates to

$$IL^2 + K = 0$$

$$M = \pm \left(-K/L \right)^{1/2} = \pm i \omega$$

Therefore, the roots are imaginary corresponding to a pure oscillation with no damping. Only case 3 should be considered. Nowhere does D appear in the denominator of any expression; therefore, the solution remains valid if D is zero.

RESULTS

The exact saving resulting from this piecewise analytical technique depends on the speed of execution of the competing numerical method. A sample run is included in appendix B so that comparisons can be made with other preferred numerical integration techniques. For comparison, the last case (KTFID=13) was run analytically with time steps of 0.01 and 0.005 second and run numerically using Advanced Continuous Simulation Language (ACSL).³ Whereas the analytical method gave the same results for time steps 0.001 and 0.005 second, ACSL could not operate with a time step of 0.001 second. ACSL was able to obtain nearly converged results with a time step of 0.00001 second but failed after the third second. These results are compared as follows:

Time (sec)	Analytical		Numerical (ACSL) DT=0.00001 sec
	DT=0.01 sec	DT=0.005 sec	
0	10.00000	10.00000	10.00000
1	1.54640	1.54640	1.54381
2	-9.52188	-9.52188	-9.52327
3	-4.49206	-4.49206	-4.48494

³ Advanced Continuous Simulation Language, User Guide/Reference Manual, Mitchell and Gauthier Associates, Inc., Concord, MA, 1981.

In this particular case, the analytical technique resulted in at least two orders of magnitude improvement in integration step size.

CONCLUSIONS

The modular, piecewise analytical technique presented in this report can result in considerable savings in analysis and associated computer time.

APPENDIX A
PROGRAM LISTING AND SAMPLE EXECUTION

PROGRAM LISTING

```

PROGRAM TFMAIN(INPUT,OUTPUT,TAPE5=INPUT,TAPE6=OUTPUT)
C   MAIN PROGRAM TO DRIVE TRANSFER FUNCTION SUBROUTINE.
C   FOR TEST PURPOSES ONLY.
COMMON/TRNSF/TAU1(50),TAU2(50),TAU3(50),TFTIME(50),TFAUX(50),
+ TFAUX2(50),KTFTYP(50),GAIN(50)
OPEN(8)
WRITE(8,11)
C   READ INPUT DATA AND INITIALIZE.
CALL TRNF IO
WRITE(8,11)
C 200 DEFINE INTEGRATION TIME STEP DT.
DT = .005
DT2= DT/2.
WRITE(8,13) DT
DO 2 J=1,13
WRITE(8,12)
C 100 DEFINE INITIAL TIME T AND FINAL TIME TMAX.
T=0.0
TMAX = 5.0
KMAX = IFIX(TMAX/DT)+1
DO 1 K=0,KMAX
T = DT*FLOAT(K)
C 300 DEFINE DRIVING TERM "DRIVE"
DRIVE = COS(2.*T) - 1.0
CALL TRNF (DRIVE,XOUT,T,J)
IF (ABS(IFIX(T)-T).LT.DT2) WRITE(8,10) J,T,DRIVE,XOUT
1 CONTINUE
2 CONTINUE
STOP
10 FORMAT(1X,I5,3F20.5)
11 FORMAT('1')
12 FORMAT('/', ' LTFID',16X,'TIME',14X,'DRIVE',19X,'X')
13 FORMAT(' THE INTEGRATION TIME STEP DT = ',F9.6,' .',//)
END

```

```

SUBROUTINE TRNF IO
C   LTFYP 1 -> GAIN/(TAU1*S+1)
C   LTFYP 2 -> GAIN*S/(TAU1*S+1)
C   LTFYP 3 -> GAIN/(S*(TAU1*S+1))
C   LTFYP 4 -> GAIN*(TAU2*S+1)/(TAU1*S+1)
C   LTFYP 5 -> GAIN/(TAU1*S**2 + TAU2*S +TAU3)
C   LTFID ID NO. OF CHANNEL (VARIABLE).
C   TU1 FIRST TIME CONSTANT
C   TU2 SECOND TIME CONSTANT (LTFYP=4 OR 5)
C   TU3 THIRD TIME CONSTANT (LTFYP=5)

```

```

C      X0          INITIAL CONDITION ON VARIABLE
C      DX0         INITIAL CONDITION ON DERIVATIVE (LTFTYP=5)
C      AA          ALPHAMERIC LABEL FOR PRINTOUT
COMMON/TRNSF/TAU1(50),TAU2(50),TAU3(50),TFTIME(50),TFAUX(50),
+ TFAUX2(50),KTFTYP(50),GAIN(50)
CHARACTER AA*30,LABEL(5)*30
DATA LABEL/'GAIN/(TAU1*S+1)
+          'GAIN*S/(TAU1*S+1)
+          'GAIN/(S*(TAU1*S+1))
+          'GAIN*(TAU2*S+1)/(TAU1*S+1)
+          'GAIN/(TAU1*S**2+TAU2*S+TAU3)
WRITE(8,1050)
DO 1 I=1,50
TAU1(I)      = 0.
TAU2(I)      = 0.
TAU3(I)      = 0.
TFTIME(I)    = 0.
TFAUX(I)     = 0.
TFAUX2(I)    = 0.
KTFTYP(I)    = 0
GAIN(I)      = 0.
1 CONTINUE
IFLAG = 0
DO 2 I=1,50
READ (5,1051,END=4) LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA
IF (LTFTYP.LT.1 .OR. LTFTYP.GT.5) THEN
WRITE(8,1052)LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA
IFLAG = 1
WRITE(8,1004)
GO TO 2
ELSE
WRITE(8,1052)LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA,LABEL(LTFTYP)
END IF
IF (LTFID.LT.1 .OR. LTFID.GT.50) THEN
IFLAG = 1
WRITE(8,1001)
GO TO 2
END IF
IF (TAU1(LTFID).NE.0..OR.TAU2(LTFID).NE.0..OR.TAU3(LTFID).NE.0.
+ .OR.KTFTYP(LTFID).NE.0) THEN
IFLAG =1
WRITE(8,1002)
GO TO 2
END IF
IF (TU1.GT.0..AND.TU2.EQ.0..AND.TU3.GT.0..AND.LTFTYP.EQ.5)
+ GO TO 3
IF ((TU1.LE.0..OR.TU2.LE.0..OR.TU3.LE.0.) .AND.LTFTYP.EQ.5) THEN
WRITE(8,1003)
IF (TU1.EQ.0. .AND. TU3.GT.0. .AND.TU2.GT.0.) THEN
WRITE(8,1005)
LTFTYP = 1

```

```

        GA = GA/TU3
        TU1=TU2/TU3
        TU2=0.
        TU3=0.
        WRITE(8,1000)
        WRITE(8,1052)LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA
+ ,LABEL(LTFTYP)
        GOTO 3
    END IF
    IF (TU3.EQ.0. .AND. TU1.GT.0. .AND.TU2.GT.0.) THEN
        WRITE(8,1006)
        LTFTYP = 3
        GA = GA/TU2
        TU1=TU1/TU2
        TU2=0.
        TU3=0.
        WRITE(8,1000)
        WRITE(8,1052)LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA
+ ,LABEL(LTFTYP)
        GOTO 3
    END IF
    IFLAG = 1
    GOTO 2
END IF
IF (TU1.LE.0. .AND. LTFTYP.LE.4) THEN
    IFLAG =1
    WRITE(8,1003)
    GO TO 2
END IF
3 CONTINUE
IF (TU2.GT.0. .AND. LTFTYP.LE.3) THEN
    TU2=0.
    WRITE(8,1003)
END IF
IF (LTFTYP.EQ.4 .AND. TU2.EQ.0. .AND. TU1.GT.0.) THEN
    LTFTYP = 1
    WRITE(8,1003)
    WRITE(8,1005)
    WRITE(8,1000)
    WRITE(8,1052)LTFID,LTFTYP,TU1,TU2,TU3,GA,X0,DX0,AA
+ ,LABEL(LTFTYP)
END IF
IF (TU1.EQ.TU2 .AND. LTFTYP.EQ.4) THEN
    WRITE(8,1007)
END IF
IF (TU3.GT.0. .AND. LTFTYP.LT.5) THEN
    TU3=0.0
    WRITE(8,1003)
END IF
IF (GA.LE.0.) WRITE(8,1008)
TAU1(LTFID) = TU1

```



```

    TAU2(LTFID) = TU2
    TAU3(LTFID) = TU3
    TFAUX(LTFID) = X0
    TFAUX2(LTFID) = DX0
    KTFTYP(LTFID) = LTFTYP
    GAIN(LTFID) = GA
2 WRITE(8,1053)
4 WRITE(8,1053)
    IF (IFLAG.NE.0) STOP
    RETURN
1000 FORMAT(' ***THIS TRANSFER FUNCTION WILL BE TREATED AS:' )
1001 FORMAT(' ***ERROR IN TRNF IO*** KTFID OUT OF RANGE.' )
1002 FORMAT(' ***ERROR IN TRNF IO*** THIS TRANSFER FUNCTION '
+ ',ALREADY DEFINED.')
1003 FORMAT(' ***ERROR IN TRNF IO*** TAU OUT OF RANGE.' )
1004 FORMAT(' ***ERROR IN TRNF IO*** KTFTYP OUT OF RANGE.' )
1005 FORMAT('      SUBSTITUTING 1ST ORDER LAG.  KTFTYP -> 1.')
1006 FORMAT('      SUBSTITUTING 1ST ORDER LAG WITH INTEGRATOR. ',
+ 'KTFTYP -> 3.')
1007 FORMAT(' ***ERROR IN TRNF IO*** TAU1 = TAU2. TRANSFER FUNCTION',
+ ' DEGENERATES TO UNITY.' )
1008 FORMAT(' ***ERROR IN TRNF IO*** GAIN OUT OF RANGE.' )
1050 FORMAT(///,'1TRANSFER FUNCTIONS DEFINITIONS:',///,' KTFID',
+ ' KTFTYP',6X,'TAU1',6X,'TAU2',6X,'TAU3',6X,'GAIN',9X,'X',
+ 8X,'DX',//)
1051 FORMAT(2I2,5X,6F6.0,5X,A30)
1052 FORMAT(2I7,6F10.5,/, ' DESCRIPTION: ',A30,2X,A30)
1053 FORMAT(/)
    END
    SUBROUTINE TRNF(XIN,XOUT,T,KTFID)
C    THIS ROUTINE EVALUATES THE FOLLOWING TRANSFER FUNCTIONS
C    1ST ORDER LAG;
C    1ST ORDER LAG WITH DIFFERENTIATION;
C    1ST ORDER LAG WITH INTEGRATION;
C    COMBINED LEAD/LAG;
C    2ND ORDER LAG - HARMONIC OSCILLATOR.
C    XIN      DRIVING TERM.
C    XOUT     OUTPUT OF TRANSFER FUNCTION.
C    T        TIME.
C    KTFTYP   1 -> 1/(TAU1*S+1)
C             2 -> S/(TAU1*S+1)
C             3 -> 1/(S*(TAU1*S+1))
C             4 -> (TAU2*S+1)/(TAU1*S+1)
C             5 -> 1/(TAU1*S**2 + TAU2*S +TAU3)
C    KTFID    ID NO. OF CHANNEL (VARIABLE).
    COMMON/TRNSF/TAU1(50),TAU2(50),TAU3(50),TFTIME(50),TFAUX(50),
+ TFAUX2(50),KTFTYP(50),GAIN(50)
    REAL KK,II
    IF (KTFID.LT.1 .OR.KTFID.GT.50) GOTO 102
    KTF = KTFTYP(KTFID)
    IF (KTF.LT.1 .OR. KTF.GT.5) GOTO 103

```

```

      XOUT          = 0.
      XTMP          = 0.
      XTMP2         = 0.
      IF (TFTIME(KTFID).GT.T) GOTO 101
      TDELTA = T - TFTIME(KTFID)
      IF (TDELTA.EQ.0.) THEN
        TFEXP = 1.
        TFEXOT = 1./TAU1(KTFID)
        GOTO 1
      END IF
      TFEXP = EXP(-TDELTA/TAU1(KTFID))
C     FOLLOWING CODE ASSURES CORRECT LIMITING VALUES AS TAU -> 0.
      IF (ABS(TAU1(KTFID)/TDELTA) .LT. 1.E-4) THEN
        TFEXOT = 1.0/TDELTA
      ELSE
        TFEXOT = TFEXP/TAU1(KTFID)
      END IF
1  DRIVE = XIN
      OMEGA = DRIVE
      KTF = KTFTYP(KTFID)
      IF (KTF.EQ.4) OMEGA=(1.-TAU2(KTFID)/TAU1(KTFID)) *
+  DRIVE
      IF (KTF.EQ.1 .OR. KTF.EQ.4) XTMP =
+  TFAUX(KTFID)*TFEXP+(1.-TFEXP)*OMEGA
      IF (KTF.EQ.1) XOUT = XTMP
      IF (KTF.EQ.2) THEN
        XTMP = TFEXOT*(DRIVE-TFAUX2(KTFID))+TFAUX(KTFID)*TFEXP
        XOUT = XTMP
        XTMP2= DRIVE
      END IF
      IF (KTF.EQ.3) THEN
        TEMP = TFAUX2(KTFID)-DRIVE
        XTMP=TFAUX(KTFID)+TAU1(KTFID)*TEMP*(1.-TFEXP)+DRIVE*TDELTA
        XOUT = XTMP
        XTMP2 = TEMP*TFEXP+DRIVE
      END IF
      IF (KTF.EQ.4) XOUT = DRIVE*(TAU2(KTFID)/TAU1(KTFID))
+ + XTMP
      IF (KTF.EQ.5) THEN
        KK = TAU3(KTFID)
        II = TAU1(KTFID)
        BETA = TAU2(KTFID)
        FORCE = DRIVE
        DELZ = TFAUX(KTFID)
        DELDZ = TFAUX2(KTFID)
        TLAST = TFTIME(KTFID)
        CALL SOLAG(II,BETA,KK,DELZ,DELDZ,FORCE,T,TLAST,DELT,DELTD)
        XTMP = DELT
        XTMP2 = DELTD
        XOUT = XTMP
      END IF

```

```

100 TETIME(KTFID) = T
    TFAUX(KTFID) = XTMP
    TFAUX2(KTFID) = XTMP2
    XOUT = XOUT*GAIN(KTFID)
C ABOVE SAVES XD FOR 2ND ORDER LAG/OSCILLATOR AND DX/DT FOR
C FIRST ORDER LAG WITH DIFFERENTIATOR. FOR USE AS INITIAL
C CONDITIONS ON NEXT INTEGRATION STEP.
    RETURN
101 WRITE(8,200) T,TETIME(KTFID),KTFID
    STOP
102 WRITE(8,201) KTFID
    STOP
103 WRITE(8,202) KTF
    STOP
200 FORMAT(' ***ERROR*** IN TRNF. TIME=',F10.5,' IS GREATER THAN ',
+ 'LAST TIME=',F10.5,' FOR CHANNEL',I3,/)
201 FORMAT(' ***ERROR*** IN TRNF. CHANNEL NO. KTFID=',I4,
+ ' IS OUT OF RANGE.'/)
202 FORMAT(' ***ERROR*** IN TRNF. TYPE CODE NUMBER KTFID=',I4,
+ ' IS OUT OF RANGE.'/)
    END
    SUBROUTINE SOLAG(II,BETA,KK,DELZ,DELDZ,FORCE,T,TLAST,DELT,
+ DELTD)
C      DIFFERENTIAL EQUATION
C      
$$II \cdot YDDOT + BETA \cdot YDOT + KK \cdot Y = FORCE$$

C      NOTE: THE CALLING ROUTINE MUST SAVE TLAST,DELZ AND DELDZ
C      FOR THE NEXT CALL TO SOLAG
    REAL NUM,LAMB1,LAMB2,LAMB,II,KK
    IF (BETA.LT.0. .OR. KK.LE.0.) THEN
        WRITE(8,1000) BETA,KK
        STOP
    END IF
    IF (II.LT.0.) THEN
        WRITE(8,1001) II
        STOP
    END IF
    BOV2I = BETA/(2.*II)
    RDCND = BOV2I**2 -KK/II
    FOVK = FORCE/KK
    IF(RDCND .GT. 0.)GO TO 100
    IF(RDCND .EQ. 0.)GO TO 120
C      OSCILLATORY SOLUTION
    LAMB =-BOV2I
    OMEGA = SQRT(-RDCND)
    NUM = OMEGA*(DELZ-FOVK)
    DENOM = DELDZ-LAMB*(DELZ-FOVK)
    LAMB = -BOV2I
    IF(NUM .EQ. 0. .AND. DENOM .EQ. 0.) GO TO 20
    PHI = ATAN2(NUM,DENOM) - OMEGA*TLAST
    GO TO 30
20 CONTINUE

```

```

      PHI = 0.
30  CONTINUE
      ETEMP = EXP(-LAMB*TLAST)
      IF (DELZ - FOVK .EQ. 0.) GO TO 40
      A = (DELZ - FOVK)*ETEMP/SIN(OMEGA*TLAST+PHI)
      GO TO 50
40  CONTINUE
      A = DELDZ*ETEMP/(LAMB*SIN(OMEGA*TLAST + PHI)
1      + OMEGA*COS(OMEGA*TLAST + PHI) )
50  CONTINUE
      FTEMP = EXP(LAMB*T)
      DELT = A*FTEMP*SIN(OMEGA*T + PHI) + FOVK
      DELTD = LAMB*A*FTEMP*SIN(OMEGA*T+PHI) +
1      OMEGA*A*FTEMP*COS(OMEGA*T+PHI)
      GO TO 150
100 CONTINUE
C      EXPONENTIAL SOLUTION
      LAMB1 = -BOV2I+SQRT(RDCND)
      LAMB2 = -BOV2I-SQRT(RDCND)
      A = (DELZ - DELDZ/LAMB2 - FOVK)*EXP(-LAMB1*TLAST)/
1      (1. - LAMB1/LAMB2)
      B = (DELZ - DELDZ/LAMB1 - FOVK)*EXP(-LAMB2*TLAST)/
1      (1. - LAMB2/LAMB1)
      DELT = A*EXP(LAMB1*T) + B*EXP(LAMB2*T) + FOVK
      DELTD = LAMB1*A*EXP(LAMB1*T)+LAMB2*B*EXP(LAMB2*T)
      GO TO 150
120 CONTINUE
C      CRITICALLY DAMPED SOLUTION
      LAMB = -BOV2I
      A = ((DELZ-FOVK)*(1+TLAST*LAMB)-TLAST*DELDZ)*EXP(-LAMB*TLAST)
      B = (DELDZ+LAMB*(FOVK-DELZ))*EXP(-LAMB*TLAST)
      DELT = (A+B*T)*EXP(LAMB*T)+FOVK
      DELTD = (LAMB*A+B+LAMB*B*T)*EXP(LAMB*T)
150 CONTINUE
      TLAST = T
      DELZ = DELT
      DELDZ = DELTD
      RETURN
1000 FORMAT(/,' ***-ERR IN SOLAG-*** BETA=',E12.4,',KK=',E12.4,/,
+ ' ONLY POSITIVE DEFINITE VALUES ALLOWED.',/)
1001 FORMAT(/,' ***-ERR IN SOLAG-*** II=',E12.4,/,
+ ' NEGATIVE VALUES NOT ALLOWED.',/)
      END

```

SAMPLE DATA INPUT CARDS.

K K	T	T	T	G	X	D	A
T T	A	A	A	A	.	X	A
F F	U	U	U	I	.	.	.
I T	1	2	3	N	.	.	.
D Y	.	.	.	.	.	.	.
. P	.	.	.	.	.	.	.
. .	.	.	.	.	.	.	.
0101	.02	0.	0.	4.0	0.0	0.	PITCH ATTITUDE HOLD
0202	.2	0.	0.	2.0	0.0	0.	PITCH SYNTHETIC DAMPING
0303	.02	0.	0.	2.0	0.0	0.	YAW ATTITUDE HOLD
0404	.02	.01	0.0	1.0	0.0	0.	YAW LOS RATE FILTER
0504	.02	0.	0.0	1.0	0.0	0.	YAW LOS RATE FILTER
0605	1.	3.	.25	1.0	10.0	0.	PURE DAMPING
0705	1.	1.	.25	1.0	10.0	0.	CRITICALLY DAMPED
0805	1.	.5	.25	1.0	10.0	0.	DAMPED OSCILLATION
0905	1.	.0	.25	1.0	10.0	0.	PURE OSCILLATION
1005	0.	.5	.25	1.0	10.0	0.	
1105	1.	.5	.0	1.0	10.0	0.	
1205	.001	.0002	20.	1.0	10.0	0.	
1305	.0002	0.0	5000.	1.0	10.0	0.	

SAMPLE OUTPUT

TRANSFER FUNCTIONS DEFINITIONS:

KTFID	KTFTYP	TAU1	TAU2	TAU3	GAIN	X	DX
1	1	.02000	.00000	.00000	4.00000	.00000	.00000
DESCRIPTION: PITCH ATTITUDE HOLD $GAIN/(TAU1*S+1)$							
2	2	.20000	.00000	.00000	2.00000	.00000	.00000
DESCRIPTION: PITCH SYNTHETIC DAMPING $GAIN*S/(TAU1*S+1)$							
3	3	.02000	.00000	.00000	2.00000	.00000	.00000
DESCRIPTION: YAW ATTITUDE HOLD $GAIN/(S*(TAU1*S+1))$							
4	4	.02000	.01000	.00000	1.00000	.00000	.00000
DESCRIPTION: YAW LOS RATE FILTER $GAIN*(TAU2*S+1)/(TAU1*S+1)$							
5	4	.02000	.00000	.00000	1.00000	.00000	.00000
DESCRIPTION: YAW LOS RATE FILTER $GAIN*(TAU2*S+1)/(TAU1*S+1)$ ***ERROR IN TRNF IO*** TAU OUT OF RANGE. SUBSTITUTING 1ST ORDER LAG. KTFTYP -> 1. ***THIS TRANSFER FUNCTION WILL BE TREATED AS:							
5	1	.02000	.00000	.00000	1.00000	.00000	.00000
DESCRIPTION: YAW LOS RATE FILTER $GAIN/(TAU1*S+1)$							
6	5	1.00000	3.00000	.25000	1.00000	10.00000	.00000
DESCRIPTION: PURE DAMPING $GAIN/(TAU1*S**2+TAU2*S+TAU3)$							
7	5	1.00000	1.00000	.25000	1.00000	10.00000	.00000
DESCRIPTION: CRITICALLY DAMPED $GAIN/(TAU1*S**2+TAU2*S+TAU3)$							
8	5	1.00000	.50000	.25000	1.00000	10.00000	.00000
DESCRIPTION: DAMPED OSCILLATION $GAIN/(TAU1*S**2+TAU2*S+TAU3)$							
9	5	1.00000	.00000	.25000	1.00000	10.00000	.00000
DESCRIPTION: PURE OSCILLATION $GAIN/(TAU1*S**2+TAU2*S+TAU3)$							

10	5	.00000	.50000	.25000	1.00000	10.00000	.00000
DESCRIPTION:					GAIN/(TAU1*S**2+TAU2*S+TAU3)		

ERROR IN TRNF IO TAU OUT OF RANGE.

SUBSTITUTING 1ST ORDER LAG. KTFTYP -> 1.

***THIS TRANSFER FUNCTION WILL BE TREATED AS:

10	1	2.00000	.00000	.00000	4.00000	10.00000	.00000
DESCRIPTION:					GAIN/(TAU1*S+1)		

11	5	1.00000	.50000	.00000	1.00000	10.00000	.00000
DESCRIPTION:					GAIN/(TAU1*S**2+TAU2*S+TAU3)		

ERROR IN TRNF IO TAU OUT OF RANGE.

SUBSTITUTING 1ST ORDER LAG WITH INTEGRATOR. KTFTYP -> 3.

***THIS TRANSFER FUNCTION WILL BE TREATED AS:

11	3	2.00000	.00000	.00000	2.00000	10.00000	.00000
DESCRIPTION:					GAIN/(S*(TAU1*S+1))		

12	5	.00100	.00020	20.00000	1.00000	10.00000	.00000
DESCRIPTION:					GAIN/(TAU1*S**2+TAU2*S+TAU3)		

13	5	.00020	.000005	5000.00000	1.00000	10.00000	.00000
DESCRIPTION:					GAIN/(TAU1*S**2+TAU2*S+TAU3)		

THE INTEGRATION TIME STEP DT = .005000 .

LTFID	TIME	DRIVE	X
1	.00000	.00000	.00000
1	1.00000	-1.41615	-5.53438
1	2.00000	-1.65364	-6.71729
1	3.00000	-.03983	-.20403
1	4.00000	-1.14550	-4.44207
1	5.00000	-1.83907	-7.42804

LTFID	TIME	DRIVE	X
2	.00000	.00000	.00000
2	1.00000	-1.41615	-3.67251
2	2.00000	-1.65364	1.68669
2	3.00000	-.03983	2.25946
2	4.00000	-1.14550	-3.56729
2	5.00000	-1.83907	.70957

LTFID	TIME	DRIVE	X
3	.00000	.00000	.00000
3	1.00000	-1.41615	-1.04245
3	2.00000	-1.65364	-4.69789
3	3.00000	-.03983	-6.27757
3	4.00000	-1.14550	-6.97196
3	5.00000	-1.83907	-10.47893

LTFID	TIME	DRIVE	X
4	.00000	.00000	.00000
4	1.00000	-1.41615	-1.39987
4	2.00000	-1.65364	-1.66648
4	3.00000	-.03983	-.04542
4	4.00000	-1.14550	-1.12801
4	5.00000	-1.83907	-1.84804

LTFID	TIME	DRIVE	X
5	.00000	.00000	.00000
5	1.00000	-1.41615	-1.38360
5	2.00000	-1.65364	-1.67932
5	3.00000	-.03983	-.05101
5	4.00000	-1.14550	-1.11052
5	5.00000	-1.83907	-1.85701

LTFID	TIME	DRIVE	X
6	.00000	.00000	10.00000
6	1.00000	-1.41615	9.35272
6	2.00000	-1.65364	8.09988
6	3.00000	-.03983	7.04001
6	4.00000	-1.14550	6.35853
6	5.00000	-1.83907	5.38481

LTFID	TIME	DRIVE	X
7	.00000	.00000	10.00000
7	1.00000	-1.41615	8.97774
7	2.00000	-1.65364	6.33926
7	3.00000	-.03983	3.54739
7	4.00000	-1.14550	1.78784
7	5.00000	-1.83907	.10284

LTFID	TIME	DRIVE	X
8	.00000	.00000	10.00000
8	1.00000	-1.41615	8.82387
8	2.00000	-1.65364	5.36682
8	3.00000	-.03983	1.15018
8	4.00000	-1.14550	-1.86486
8	5.00000	-1.83907	-4.23518

LTFID	TIME	DRIVE	X
9	.00000	.00000	10.00000
9	1.00000	-1.41615	8.62980
9	2.00000	-1.65364	3.87712
9	3.00000	-.03983	-3.25255
9	4.00000	-1.14550	-9.90176
9	5.00000	-1.83907	-15.20981

LTFID	TIME	DRIVE	X
10	.00000	.00000	40.00000
10	1.00000	-1.41615	23.29664
10	2.00000	-1.65364	11.23015
10	3.00000	-.03983	5.73197
10	4.00000	-1.14550	2.81734
10	5.00000	-1.83907	-1.12071

LTFID	TIME	DRIVE	X
11	.00000	.00000	20.00000
11	1.00000	-1.41615	19.86679
11	2.00000	-1.65364	18.71997
11	3.00000	-.03983	16.91363
11	4.00000	-1.14550	15.57969

11	5.00000	-1.83907	13.85090
----	---------	----------	----------

LTFID	TIME	DRIVE	X
12	.00000	.00000	10.00000
12	1.00000	-1.41615	-9.10857
12	2.00000	-1.65364	8.06504
12	3.00000	-.03983	-7.32883
12	4.00000	-1.14550	6.51484
12	5.00000	-1.83907	-5.97223

LTFID	TIME	DRIVE	X
13	.00000	.00000	10.00000
13	1.00000	-1.41615	1.54640
13	2.00000	-1.65364	-9.52188
13	3.00000	-.03983	-4.49206
13	4.00000	-1.14550	8.13177
13	5.00000	-1.83907	7.00721

APPENDIX B
PROGRAM USAGE

The program consists of three subroutines (TRNF IO, TRNF, and SOLAG) and a main program, TFMAIN.* TRNF IO is the initialization routine. The data records that define the transfer functions are read by this routine. (See the explanation for input data format given below.) TRNF performs the analytical transfer function simulations. It accesses subroutine SOLAG for treatment of the second order lag/harmonic oscillator. The driving main program TFMAIN is supplied for demonstration and testing only. Use it as a model for interfacing TRNF IO, TRNF, and SOLAG with your computer program. The initial time is at line 100, and the integration time step is at line 200. The driving term is defined in the lines following 300.

The call to TRNF contains four arguments:

DRIVE	Driving function
XOUT	Output of the transfer function channel
T	Time
J	Channel I.D. number LTFID

One input data record is required for each transfer function variable to be integrated. These records have the following form:

<u>Column</u>	<u>Format</u>	<u>Variable</u>	<u>Definition</u>
1	I2	LTFID	I.D number of channel; values are from 1 to 50
3	I2	LTFTYP	Code for type of transfer function; values are 1 to 5
10	F9.0	TAU1	First constant, for all LTFTYP
19	F9.0	TAU2	Second constant, for LTFTYP = 4 or 5
28	F9.0	TAU3	Third constant, for LTFTYP=5
37	F9.0	X0	Initial condition for variable
46	F9.0	DX0	Initial condition for derivative of variable
55	A26	AA	Alphanumeric label

LTFID is an integer variable from 1 to 50 that is associated with each transfer function channel (output variable) to be simulated. For example, a lag

* A listing of a program implementing these techniques and a sample run are in appendix A.

might be applied to both a fin yaw deflection command and to a fin pitch deflection command. Each of these two channels is defined as a separate data input record and is assigned an identifying integer LTFID. If the user chooses an integer that was previously assigned on another input data record, execution terminates with an explanatory message.

LTFTYP is an integer variable in the range 1 to 5 that defines the type of transfer function:

<u>LTFTYP</u>	<u>Description and FORTRAN code</u>
1	First-order lag $1/(\text{TAU1} \cdot S + 1)$
2	First-order lag with differentiator $S/(\text{TAU1} \cdot S + 1)$
3	First-order lag with integrator $1/[S \cdot (\text{TAU1} \cdot S + 1)]$
4	Combined lead/lag $(\text{TAU2} \cdot S + 1)/(\text{TAU1} \cdot S + 1)$
5	Second-order lag/harmonic oscillator $1/(\text{TAU1} \cdot S^2 + \text{TAU2} \cdot S + \text{TAU3})$

TAU1 is the first constant (see LTFTYP above). All five transfer function types (LTFTYP = 1 to 5) require this quantity to be positive.

TAU2 is the second constant. Lead/lag and second-order lag/oscillator transfer functions (LTFTYP = 4,5) require a positive value.

TAU3 is the third constant. The second-order lag/oscillator (LTFTYP = 5) requires a positive value.

X0 is the initial condition on the output variable, i.e., $y_0 = y$ at $t = t_0$.

DX0 is the initial condition on the derivative of the output variable, $y' = dy/dt$ at $t = t_0$.

AA is an alphanumeric label of 26 characters that identifies the nature of the transfer function when an echo of the input data is printed out by TRNF IO. Examples might be "PITCH SYNTHETIC DAMPING" or "YAW ATTITUDE HOLD."

If an input variable is out of range, the program prints an error message and reformulates the transfer function into an equivalent form. For example, if an attempt is made to run an oscillator (LTFTYP = 5) with TAU1 = 0, subroutine TRNF IO will substitute the equivalent simple lag (LTFTYP = 1), as can be seen in the sample output for KTFID = 10. Two other examples appear in the sample output in the sample execution, i.e., for KTFID = 5 and KTFID = 11.

SYMBOLS

Algebraic Expressions

A	Constant of integration
B	Constant of integration
D	Coefficient of the Laplace operator s in the transfer function of the second-order lag/oscillator
I	Coefficient of the square of the Laplace operator s in the transfer function of the second-order lag/oscillator
K	Constant term in the transfer function of the second-order lag/oscillator
L	Damping coefficient $-D/2I$ for the second-order lag/oscillator
s	Laplace transform operator
t	Time, independent variable
T	Time constant
D	Driving term
y	Output of transfer function, dependent variable
y_0	Initial condition on y at $t = t_0$
y'	Initial condition on dy/dt at $t = t_0$
z	Auxiliary dependent variable for first-order lag with differentiation or for first-order lag with integration
ω	Frequency of oscillation for second-order lag/oscillator
ϕ	Phase angle of oscillation for second-order lag/oscillator

FORTTRAN Variable Names

AA	Alphanumeric label for printout (80 characters)
DX	Initial condition on derivative when KTFTYP=5
KTFID	I.D. number of channel or variable (range is 1 to 50)
KTFTYP	Integer variable used to indicate type of transfer function (range 1 to 50) KTFTYP = 1 is first-order lag Transfer function: $GAIN/(TAU1*S+1)$ KTFTYP = 2 is first-order lag with differentiation Transfer function: $GAIN*S/(TAU1*S+1)$ KTFTYP = 3 is first-order lag with integration Transfer function: $GAIN/[S*(TAU1*S+1)]$ KTFTYP = 4 is combined lead/lag Transfer function: $GAIN*(TAU2*S+1)/(TAU1*S+1)$ KTFTYP = 5 is second-order lag/harmonic oscillator Transfer function: $GAIN/(TAU1*S^2 + TAU2*S + TAU3)$
T	Time
TAU1	First time constant
TAU2	Second time constant (T_1 for KTFTYP=4 or D for KTFTYP)
TAU3	Third time constant (K for KTFTYP=5)
X	Initial condition on variable
XIN	Driving term
XOUT	Output of transfer function

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