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Figure 3-52(b). Define the outputs of the integrators as state variables, as shown in Figure 3-52(b). Then from Figure 3-52(b) we obtain. Chapter 3 / Mathematical Modeling of Dynamic Systems. Figure 3- (a) Control system; (b) modified block diagram. Taking the inverse Laplace transforms of the preceding three equations, we obtain.

$$\dot{x}_1 = -ax_1 + x_2 + au$$

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