Fişa suspiciunii de plagiat / Sheet of plagiarism's suspicion	Indexat la: 0122/05

Opera suspicionată (OS)	Opera autentică (OA)
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OS	COLOŞI, Tiberiu, UNGUREŞAN, Mihaela Ligia, DULF, Eva Henrietta, CORDOŞ, Roxana Carmen. *Introduction to analogical modelling and numerical simulation with (Mpdx) and Taylor series for distributed parameters processes.* Letter for the reader: DRAGOMIR, Toma Leonida. Târgu-Lăpuş, Romania: Galaxia Gutenberg. 2009.
OA	COLOŞI, T., ABRUDEAN, M., DULF, E.H., and UNGUREŞAN, M.L. *Numerical modelling and simulation method for lumped and distributed parameters processes with Taylor series and local iterative linearizarion.* Reviewers: FEŞTILĂ, Clement, LAZEA, Gheorghe, VÂNĂTORU, Mihai. Cluj-Napoca, Romania: Mediamira. 2008.

Incidența minimă a suspiciunii / Minimum incidence of suspicion	
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p.16:20 – p.19:11	p.07:15 – p.10:14
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colecția tehne 13

Tiberiu COLOȘI

Mihaela-Ligia UNGUREȘAN Eva-Henrietta DULF

Roxana Carmen CORDOȘ

Introduction to Analogical Modeling and Numerical Simulation

With (M_{pdx}) and Taylor Series for Distributed Parameters Processes

Galaxia Gutenberg

Colecție coordonată de Mihaela-Ligia Ungureşan

Coperta: Cristian Marchiş

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Editura Galaxia Gutenberg
435600 Târgu-Lăpuş, str. Florilor nr. 11
Tel/fax: 0262-385786; mobil: 0723-377599
e-mail: contact@galaxiagutenberg.ro
comenzi@librariilegutenberg.ro
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For those interested in applications in the field of automatic process control, the expression „process with distributed parameters" from the book's title requires a supplementary specification. For them „process" represents, in principle, the controlled part in an automatic system. In the general scientific terminology, which is used in the title, the process may also represent the entire automatic system. As a consequence, the methods presented in this book can be applied also for studying through simulation the control systems of plants with distributed parameters.

After having discussed with Professor Coloşi – the first author – about this new book, which is a remarkable work with a complex character, I realized that I had the chance, across time and during the many years we know each other, to witness the birth of the ideas comprised in this book. These ideas reflect restless research efforts in fields such as energetic, chemistry, electrotechnique, which were finalized under his coordination and got materialized in numerous articles, doctoral theses, dissertations and graduation theses, as well as in participations at conferences and published books.

I am convinced that you as a reader, after going through this book, will be also convinced of its value and utility.

Prof. dr. eng. Toma-Leonida Dragomir,
Member of Academy of Technical Sciences of Romania
„Politehnica" University of Timişoara, Romania
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or polynomial variants, used in technique. With these solutions we were able to establish the initial conditions and the final conditions. Also we were able to establish the performances of numerical integration, using the indicator called "cumulative relative error in percent" (crep), which in most examples was between the limits ($10^{-6} \div 10^{-2}$) %, a fact that certifies the accuracy of the method and the programs.

Chapter 12: „Conclusions" presents the importance of study the analogical modeling and numerical simulation through ($\mathbf{M}_{pdx}$) and Taylor Series.

Appendix AI, AII and AIII helps the reader to understand all material presented in Chapters 1 - 12.

The entire paper has been elaborated by Tiberiu Coloşi. This paper could not be published without the very qualified and collegiate support of all authors.

Some examples and programs have been elaborated and included, in many years, in the projects and diploma papers of the students of the Faculty of Automation and Computer Science within the Technical University of Cluj-Napoca.

Prof. Tiberiu Coloşi expresses his thanks and gratitude to Alexander von Humboldt Foundation in Bonn-Germany, for the given material support as well as to Prof. Eng. Rolf Unbehauen, PhD. from the Institut für Allgemeine und Theoretische Elektrotechnik der Universitat Erlangen-Nürnberg-Germany for the professional support and the collegiate atmosphere he enjoyed in this university collective, during twenty months.

THE AUTHORS

II[nd] PART

PROCESSES WITH DISTRIBUTED PARAMETERS

Chapter 4

LINEAR PROCESSES WITH DISTRIBUTED PARAMETERS

4.1. Introduction

It is known that the usual analytical modeling of linear processes with distributed parameters can be expressed using equations or systems of equations with linear partial derivatives, homogeneous (without a free component) or non homogeneous (with free component). The category of equations with linear partial derivatives (pde), to which this chapter refers to, is presented in the following examples:

$$a_{00}y + a_{10}\frac{\partial y}{\partial t} + a_{01}\frac{\partial y}{\partial p} = \varphi(t,p) \tag{4.1}$$

$$a_{000}y + a_{100}\frac{\partial y}{\partial t} + a_{010}\frac{\partial y}{\partial p} + a_{001}\frac{\partial y}{\partial q} = \varphi(t,p,q) \tag{4.2}$$

$$a_{00}y + a_{10} + \frac{\partial y}{\partial t} + a_{01}\frac{\partial y}{\partial p} + a_{20}\frac{\partial^2 y}{\partial t^2} + a_{11}\frac{\partial^2 y}{\partial t\partial p} + a_{02}\frac{\partial^2 y}{\partial p^2} = \varphi(t,p) \tag{4.3}$$

$$a_{000}y + a_{200}\frac{\partial^2 y}{\partial t^2} + a_{020}\frac{\partial^2 y}{\partial p^2} + a_{002}\frac{\partial^2 y}{\partial q^2} = \varphi(t,p,q) \tag{4.4}$$

$$\begin{aligned} &a_{000}y + a_{100}\frac{\partial y}{\partial t} + a_{010}\frac{\partial y}{\partial p} + a_{001}\frac{\partial y}{\partial q} + a_{200}\frac{\partial^2 y}{\partial t^2} + a_{110}\frac{\partial^2 y}{\partial t\partial p} + \\ &+ a_{020}\frac{\partial^2 y}{\partial p^2} + a_{011}\frac{\partial^2 y}{\partial p\partial q} + a_{002}\frac{\partial^2 y}{\partial q^2} + a_{101}\frac{\partial^2 y}{\partial t\partial q} = \varphi(t,p,q) \end{aligned} \tag{4.4'}$$

$$a_{0000}y + a_{1000}\frac{\partial y}{\partial t} + a_{0100}\frac{\partial y}{\partial p} + a_{0010}\frac{\partial y}{\partial q} + a_{0001}\frac{\partial y}{\partial r} + a_{2000}\frac{\partial^2 y}{\partial t^2} +$$

$$+ a_{1100}\frac{\partial^2 y}{\partial t\partial p} + a_{0200}\frac{\partial^2 y}{\partial p^2} + a_{0110}\frac{\partial^2 y}{\partial p\partial q} + a_{0020}\frac{\partial^2 y}{\partial q^2} + a_{0011}\frac{\partial^2 y}{\partial q\partial r} + \qquad (4.4")$$

$$+ a_{0002}\frac{\partial^2 y}{\partial r^2} + a_{1001}\frac{\partial^2 y}{\partial t\partial r} + a_{0101}\frac{\partial^2 y}{\partial p\partial r} + a_{1010}\frac{\partial^2 y}{\partial t\partial q} = \varphi(t,p,q,r)$$

$$a_{00}y + a_{30}\frac{\partial^3 y}{\partial t^3} + a_{03}\frac{\partial^3 y}{\partial p^3} = \varphi(t,p) \qquad (4.5)$$

$$a_{000}y + a_{300}\frac{\partial^3 y}{\partial t^3} + a_{030}\frac{\partial^3 y}{\partial p^3} + a_{003}\frac{\partial^3 y}{\partial q^3} = \varphi(t,p,q) \qquad (4.6)$$

$$a_{00}y + a_{40} + \frac{\partial^4 y}{\partial t^4} + a_{04}\frac{\partial^4 y}{\partial p^4} = \varphi(t,p) \qquad (4.7)$$

$$a_{000}y + a_{400}\frac{\partial^4 y}{\partial t^4} + a_{040}\frac{\partial^4 y}{\partial p^4} + a_{004}\frac{\partial^4 y}{\partial q^4} = \varphi(t,p,q) \qquad (4.8)$$

All coefficients (a…) are considered to be constant or variable, and φ(t, p), y(t, p), φ(t, p, q), y(t, p, q), φ(t, p, q, r) and y(t, p, q, r), fulfil the continuity conditions in the Cauchy sense. The independent variables (t), (p), and (q) could represent the time (t), respectively the spatial abscise (p), and (q) defined, for instance, in Cartesian coordinates.

The initial conditions (IC) are considered to be known, and other explanations could be added, from case to case, for boundary conditions (BC) and final conditions (FC).

4.2. State variables, initial conditions and final conditions

Introducing the notations:

$$x_{TP} = \frac{\partial^{T+P} y}{\partial t^T \partial p^P} \qquad (4.9)$$

$$x_{TPQ} = \frac{\partial^{T+P+Q} y}{\partial t^T \partial p^P \partial q^Q} \quad \text{or} \quad x_{TPQR} = \frac{\partial^{T+P+Q+R} y}{\partial t^T \partial p^P \partial q^Q \partial r^R} \tag{4.10}$$

(for T = 0, 1, 2, …; P = 0, 1, 2, …; Q = 0, 1, 2, …; R = 0,1, 2, …) the ten pde, that is (4.1), (4.2), …, (4.8) can be rewritten as:

$$a_{00}x_{00} + a_{10}x_{10} + a_{01}x_{01} = \varphi_{00} \tag{4.11}$$

$$a_{000}x_{000} + a_{100}x_{100} + a_{010}x_{010} + a_{001}x_{001} = \varphi_{000} \tag{4.12}$$

$$a_{00}x_{00} + a_{10}x_{10} + a_{01}x_{01} + a_{20}x_{20} + a_{11}x_{11} + a_{02}x_{02} = \varphi_{00} \tag{4.13}$$

$$a_{000}x_{000} + a_{200}x_{200} + a_{020}x_{020} + a_{002}x_{002} = \varphi_{000} \tag{4.14}$$

$$\begin{aligned} &a_{000}x_{000} + a_{100}x_{100} + a_{010}x_{010} + a_{001}x_{001} + a_{200}x_{200} + a_{110}x_{110} + \\ &+ a_{020}x_{020} + a_{011}x_{011} + a_{002}x_{002} + a_{101}x_{101} = \varphi_{000} \end{aligned} \tag{4.14'}$$

$$\begin{aligned} &a_{0000}x_{0000} + a_{1000}x_{1000} + a_{0100}x_{0100} + a_{0010}x_{0010} + a_{0001}x_{0001} + \\ &+ a_{2000}x_{2000} + a_{1100}x_{1100} + a_{0200}x_{0200} + a_{0110}x_{0110} + a_{0020}x_{0020} + \\ &+ a_{0011}x_{0011} + a_{0002}x_{0002} + a_{1001}x_{1001} + a_{0101}x_{0101} + a_{1010}x_{1010} = \varphi_{0000} \end{aligned} \tag{4.14''}$$

$$a_{00}x_{00} + a_{30}x_{30} + a_{03}x_{03} = \varphi_{00} \tag{4.15}$$

$$a_{000}x_{000} + a_{300}x_{300} + a_{030}x_{030} + a_{003}x_{003} = \varphi_{000} \tag{4.16}$$

$$a_{00}x_{00} + a_{40}x_{40} + a_{04}x_{04} = \varphi_{00} \tag{4.17}$$

$$a_{000}x_{000} + a_{400}x_{400} + a_{040}x_{040} + a_{004}x_{004} = \varphi_{000} \tag{4.18}$$

In the hypothesis of integration with respect to time (t), the elements of the state vector (**x**), which correspond to the pde (1), (2), …(8) are presented in Table 4.1.

The notation (n, υ) in line 2, Table 4.1, underlines by n = I, II, III and IV the order of pde, and by υ = 2, 3 and 4 the number of variables, respectively 2 for (t, p), 3 for (t, p, q) and 4 for (t, p, q, r).

The state vector is presented in Table 4.2 for the initial conditions ($\mathbf{x}_{IC}$) and for some possible boundary conditions ($\mathbf{x}_{BC}$), respectively the final conditions ($\mathbf{x}_{FC}$), where (0) and (f) underline the initial and final values.

Table 4.1

pde	4.1	4.2	4.3	4.4	4.4'	4.4"	4.5	4.6	4.7	4.8
Notation	I·2	I·3	II·2	II·3	II·3	II·4	III·2	III·3	IV·2	IV·3
x STATE VECTOR	x_{00}	x_{000}	x_{00} x_{10}	x_{000} x_{100}	x_{000} x_{100}	x_{0000} x_{1000}	x_{00} x_{10} x_{20}	x_{000} x_{100} x_{200}	x_{00} x_{10} x_{20} x_{30}	x_{000} x_{100} x_{200} x_{300}

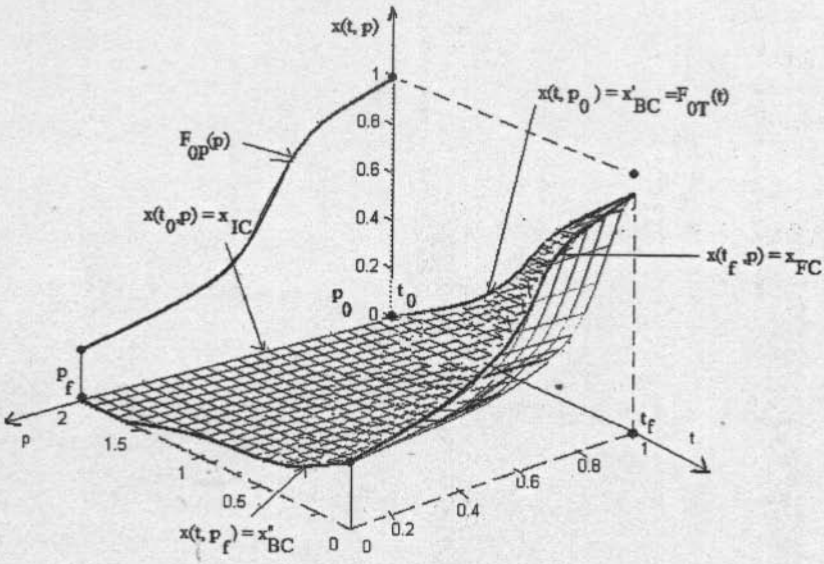

Fig. 4.1: The evolutions of $F_{0T}(t)$ and $F_{0P}(p)$

In order to exemplify the first line from Table 4.2 it is considered: $x(t, p) = F_{0T}(t) \cdot F_{0P}(p)$, where the exponentials $F_{0T}(t)$ and $F_{0P}(p)$ present increasing, respectively decreasing evolutions, as in figure 4.1. It can be noticed that: