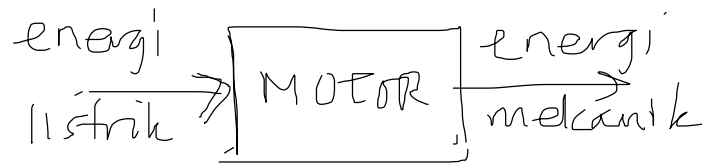


Bab I Pemodelan Motor DC (Armature Controller)

* Model STATIS

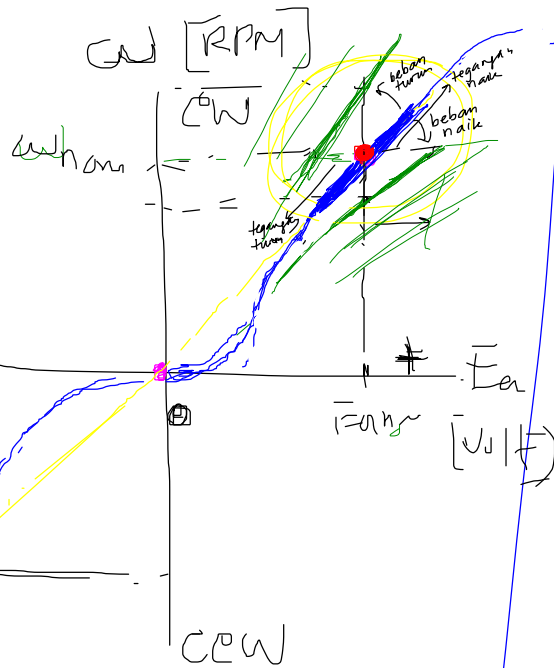
$$1 \text{ RPM} = \frac{2\pi}{60} \text{ rad/sec}$$



$$E_a \text{ [V]} \quad \text{rating} \quad \omega \text{ [RPM, rad/sec]}$$

$$\omega = K \cdot E_a$$

$$K = \frac{\omega_{\text{nominal}}}{E_{a \text{ nominal}}}$$



PPML Pemodelan dan Pengendalian Motor Listrik

8 pekan : Motor DC Terkendali Jangkar (Armature-Controlled DC Motor)

Tugas 1 (dikumpul 19/03/13)

Motor DC Terkendali Jangkar
U.S. Motors
- Merk, Tipe, U.S. Motors
- Spesifikasi: HP, P, ω_{nom} (RPM),
- Data (R_a, L_a, J, B) rad/sec
 K_m, K_b I_a, E_a

Referensi:
<http://www.unhas.ac.id/rhiza/arsip/kuliah>
→ PPML

PENILAIAN!

* Tugas 2
* Test tertulis

digabung
dengan
nilai dari
pale Faizal (TK)
pale Saifur (TE)

Materi = Bab I Pemodelan Motor DC

- * Model Statis
- * Model Dinamis/Analitik
 - Model Fisik
 - Model Nisbah Alih
 - Model Ruang Keadaan
- * Model Simulink/Numerik

LAPTOP/MATLAB

Bab II Pengendalian Motor DC

- * Pengendalian Open-Loop
START/STOP
- * Pengendalian Closed-Loop
(dengan feedback)

ω_{nom} = Kecepatan NOMINAL

$E_{a \text{ nom}}$ = Tegangan Jangkar NOMINAL

