

Table of Contents

Foreword	xiii
Introduction	xvii
Chapter 1. Sensors and Electrical Measurements	1
1.1. Optical encoder	2
1.1.1. Technical aspect	2
1.1.2. Absolute encoder	3
1.1.3. Incremental encoder	6
1.2. The velocity measurement	7
1.2.1. Method of the frequency counter	7
1.2.2. Method of the period measurement	8
1.3. The resolver	9
1.4. The isolated measurement	14
1.4.1. The isolated ammeter	14
1.4.2. The isolated voltmeter	15
1.5. The numerical aspect	15
1.6. The analog to digital converter	16
1.6.1. Principle of the flash converter	17
1.6.2. Principle of the successive approximation converter	18
1.6.3. The zero-order hold	18
1.6.4. The multiplexer	19
1.6.5. Principle of converter using slope(s)	20
1.7. The digital-to-analog converter	21
1.8. The digital output	22
1.9. The arithmetic logic unit	22
1.10. Real time or abuse language	23
1.11. Programming	24

Chapter 2. Analog, Numerical Control	25
2.1. Structure of a regulator	25
2.2. Stability of a system	26
2.2.1. Introduction	26
2.2.2. A formal criterion	27
2.2.3. A graphical criterion	28
2.2.4. The stability criterion	29
2.3. Precision of systems	30
2.3.1. The initial and final value	30
2.3.2. The precision of systems	31
2.4. Correction of systems	31
2.4.1. The lag and lead corrector	32
2.4.2. Other correctors	33
2.5. Nonlinear control	34
2.5.1. First harmonic method	34
2.5.2. The oscillation stability	34
2.6. Practical method of identification and control	35
2.6.1. Broïda's method	35
2.6.2. Ziegler's and Nichols's method	36
2.7. The digital correctors	36
2.7.1. Digital controller	36
2.7.2. The Z -transform	37
2.7.3. The Z -transform of a function	38
2.7.4. Advanced Z -transform	39
2.7.5. The Z -transform of a loop	40
2.7.6. Some theorems	41
2.7.6.1. The initial and final value	41
2.7.6.2. The recurrence relation	41
2.7.6.3. The fraction expansion	42
2.7.7. The Jury stability criterion	42
2.7.8. Stability: graphical criterion	43
2.7.8.1. The bilinear transform	44
2.7.8.2. The formal criterion	44
2.7.8.3. The graphical criterion	45
2.8. Classical controllers	45
2.8.1. The PID structure	46
2.8.2. The PI anti-windup structure	46
2.8.3. Conversion of an analog controller to a digital controller	48
2.8.3.1. Approximation of the integrator	48
2.8.3.2. Use of the bilinear transform	49
2.9. Disadvantages of digital controller	52
2.9.1. Choice of the sampling period	52
2.9.2. Noise	53

2.9.2.1. Reminder of some concepts	53
2.9.2.2. Quantization by truncation	53
2.9.2.3. Quantization by rounding	54
2.9.2.4. Quantization of a product using two's complement	55
2.9.2.5. Quantization of a product by truncation	56
2.9.2.6. The signal-to-quantization noise ratio	57
2.9.3. Cycles limits and limitations	58
Chapter 3. Models of Asynchronous Machines	59
3.1. The induction motor	59
3.1.1. The electromagnetic torque	62
3.1.2. The equivalent scheme	63
3.2. The squirrel cage induction motor	66
3.2.1. The stator inductances	67
3.2.2. The stator mutual inductances	69
3.2.3. The rotor inductances	70
3.2.4. The rotor mutual inductances	72
3.2.5. The stator-rotor mutual inductances	73
3.2.6. The rotor voltage equations	75
3.2.7. The voltage and mechanical equations	75
3.2.8. Reduction of the model	77
3.3. The static and dynamic behavior	82
3.3.1. The steady state of the induction machine	82
3.3.1.1. Assessment of the power	82
3.3.1.2. Characteristics of the electromagnetic torque	84
3.3.2. Some practical characteristics	88
3.3.3. The dynamics of the induction motor	92
3.3.3.1. No choice of reference frame	94
3.3.3.2. Choice of rotor reference frame	94
3.3.3.3. Choice of stator reference frame	95
3.3.3.4. Choice of synchronous reference frame	95
3.3.3.5. Arrangement of variables	96
3.3.4. Some electromagnetic torque expressions	98
3.4. Winding and induced harmonics	99
3.4.1. Principle of the rotating field	100
3.4.2. The effect of currents	103
3.4.2.1. Effect of unbalanced currents	104
3.4.2.2. Effect of non-sinusoidal currents	106
3.4.2.3. Effect of non-sinusoidal winding	107
3.4.2.4. Effect of harmonic components and winding	108
3.4.3. Choices of winding	108
3.4.3.1. Single-layer winding	109
3.4.3.2. Concentric and distributed winding	112

3.4.3.3. Double-layer winding	113
3.5. Squirrel cage	115
3.5.1. The fundamental component of MMF	115
3.5.2. Effect of harmonics due to slots	116
3.5.3. Effect of harmonic components on the torque	117
3.6. Variation in air-gap permeance	118
3.6.1. Effect of the rotor and stator slots	119
3.6.2. Effect of magnetic saturation	120
3.6.3. Effect of eccentricity	120
3.7. Noise and vibrations	121
3.7.1. The first harmonics approach	122
3.7.2. Choice of the number of rotor bars in squirrel-cage induction	124
3.8. Influence of rotor frequency	125
3.8.1. One ideal rotor bar at null frequency	126
3.8.1.1. Aspects of the rotor bar	126
3.8.1.2. The aspect of the isthmus	127
3.8.1.3. Synthesis	128
3.8.2. One ideal rotor bar at non-null frequency	128
3.8.2.1. The aspect of inductance	129
3.8.2.2. The aspect of resistance	129
3.8.2.3. Synthesis	129
3.9. Thermal behavior	130
3.9.1. Insulation classes	131
3.9.2. Static thermal model	132
3.9.3. A dynamic hybrid thermal model	134
Chapter 4. Speed Variation	137
4.1. Cases of multiphase machines	137
4.1.1. Motors with a high number of phases	138
4.1.1.1. Type-I motors	138
4.1.1.2. Type-II motors	140
4.1.2. Interactions between harmonics	141
4.1.3. Three-phase induction machine	144
4.1.3.1. Three-phase model	144
4.1.3.2. Application in another frame	146
4.1.4. Five-phase induction machine	151
4.1.5. Double-star induction motor	155
4.1.5.1. Six-phase induction motor: version 1	156
4.1.5.2. Six-phase induction motor: version 2	161
4.2. Control of asynchronous motors	164
4.2.1. The basic environment	166
4.2.2. Scalar control: V/f	167
4.2.3. Vector control: V/f	169

4.2.3.1. A classical approach	171
4.2.3.2. Variant without a speed sensor	172
4.2.4. Direct torque control (DTC)	175
4.2.4.1. The concept	178
4.2.4.2. Strategy of vector choice	181
4.2.4.3. Torque ripple	182
4.2.4.4. Three-level inverter	184
4.2.4.5. Influence of voltage limitation	189
4.2.4.6. The DTC-SVM approach	189
4.2.4.7. Prediction of the torque ripple	192
4.2.4.8. Application to a five-phase induction motor	193
4.2.5. Direct self-control approach (DSC)	194
4.2.6. Vector control: FOC	197
4.2.6.1. Application to three-phase induction motors	200
4.2.6.2. Application to five-phase induction motors	203
4.2.6.3. Application to six-phase induction motors	207
4.2.7. Control without a position sensor	208
4.2.8. Exploitation of natural asymmetries	209
4.2.8.1. The static and dynamic eccentricity	209
4.2.8.2. The rotor slots effect	210
4.2.8.3. The magnetic saturation effect	211
4.2.8.4. The estimation of the velocity	211
4.2.8.5. Spectrum estimation	213
4.2.9. Estimation by high-frequency injection	213
4.3. Identification of parameter aspects	216
4.3.1. Classical methods	216
4.3.1.1. The step method	217
4.3.1.2. Empirical method	219
4.3.2. Generic methods	221
4.3.2.1. Principle of the method based on the model	221
4.3.2.2. The gradient method	222
4.3.2.3. The Newton-Raphson method	222
4.3.2.4. The Marquardt-Levenberg method	222
4.3.2.5. The genetic algorithm	223
4.3.2.6. Identification of electrical and mechanical parameters	225
4.3.3. Conclusion	226
4.4. Voltage inverter converters	227
4.4.1. Inverters using the pulse width modulation technique	227
4.4.1.1. Two-level inverter	228
4.4.1.2. Over-modulation	232
4.4.1.3. Three levels inverter	233
4.4.1.4. Three-level inverter using clamped capacitor	235
4.4.1.5. Four-level inverter	236

4.4.1.6. Multi-levels inverter	239
4.4.2. The inverters using the space vector modulation	243
4.4.2.1. Application to the three-phase induction motor	245
4.4.2.2. Application to the five-phase induction motor	249
4.4.2.3. Application to the six-phase induction motor	253
4.4.2.4. Multilevel aspect	257
4.4.3. The matrix converter	261
4.4.3.1. Direct matrix converter	263
4.4.3.2. Indirect matrix converter	266
4.5. Rectifiers based on the PWM	268
4.5.1. Two-level rectifier	268
4.5.2. Three-level rectifier	270
Chapter 5. Tools of Fuzzy Logic	273
5.1. Preamble	273
5.2. Introduction	274
5.3. Fuzzy logic	275
5.3.1. Definitions and norms	275
5.3.2. Some variants	276
5.3.3. T -norm and T -conorm	276
5.3.4. Membership functions	277
5.3.5. Inference engine	278
5.3.6. Defuzzification	280
5.4. Fuzzy logic controller	280
5.5. Fuzzy and adaptive PI	284
5.5.1. Examples of programs to calculate a fuzzy surface	286
5.5.1.1. The layout of a fuzzy surface	286
5.5.1.2. Routine of a PI-fuzzy controller	287
5.5.2. Examples of application	288
5.5.3. Examples of simulation results	289
5.5.3.1. Controller based on a fuzzy PI	289
5.5.3.2. A controller based on a fuzzy PID	291
5.5.4. Examples of tables of rules	291
5.6. Conclusion	295
Chapter 6. Diagnostics and Signals Pointing to a Change	297
6.1. Signals and measurements	298
6.2. Defects	299
6.2.1. Problems with broken bars	300
6.2.2. Problems in the stator	302
6.2.3. Problems due to eccentricities	304
6.2.4. Problems due to speed ripples	307
6.2.5. Problems with ball bearings	307

6.3. Analysis of signals	309
6.3.1. Fast Fourier transform analysis of the stator current	309
6.3.2. Fast Fourier transform	309
6.3.3. Discrete fast Fourier transform	311
6.3.4. Windows functions	312
6.3.4.1. The Hamming function	313
6.3.4.2. The Hanning function	313
6.3.4.3. The Blackmann function	313
6.3.4.4. The Bartlett function	313
6.3.4.5. The Kaiser function	313
6.3.5. Sliding discrete fast Fourier transform	314
6.3.5.1. Zoom effect	316
6.4. Some considerations regarding broken bar defects	317
6.4.1. Model of the induction motor	317
6.4.2. Inherent frequencies in the broken bar defect	318
6.4.3. Evaluation of the magnitude of the left line	320
6.4.4. Equivalent model in the steady state	320
6.5. Evaluation of the severity of broken bars	322
6.5.1. Some spectra results	322
6.5.2. Evaluation of the severity of broken bars	326
6.5.2.1. Analytical approach	326
6.5.2.2. Artificial intelligence approach	328
6.5.2.3. Self-extraction of signatures: an application of PSO	330
6.5.3. Wireless communication	335
Exercise No. 1: Fuzzy Logic	337
1.1. Adaptive k and k_i coefficients in function of the error	337
1.2. Adaptive k and k_i coefficients in function of the error and its derivative	338
1.3. Answers	339
Exercise No. 2: The Stator Defect	345
2.1. Equations of the induction motor under stator defect	347
2.2. Torque ripple due to a stator defect	348
2.3. Fault current estimation	349
2.4. Schematic model of three-phase induction motor under a stator defect	350
2.5. Answers	351
Exercise No. 3: The Control of Five-Phase Induction Motors	357
3.1. The five-phase system	358
3.2. Distribution of active currents	359

3.3. A model for control	362
3.4. Answers	364
Exercise No. 4: The Control of Serial Connected Induction Motors	373
4.1. Study about the serial connection of two five-phase induction motors	374
4.2. Study on the serial connection of several seven-phase induction motors	375
4.3. Study on the serial connection of multi-phase induction motors	377
4.4. Answers	378
Exercise No. 5: Fault Detection of a Three-Phase Voltage Inverter Converter	385
5.1. A conducting fault	386
5.2. Fault detector	387
5.3. Monitoring of the DC component	389
5.4. Answers	390
Appendix. Some Mathematical Expressions	393
A.1. Laplace transforms	393
A.2. Z transforms	394
A.3. W transforms	395
A.4. Common expressions	395
A.5. Trigonometric identities	395
A.5.1. Addition	396
A.5.2. Sum identities	396
A.5.3. Product identities	397
A.5.4. The product	397
A.5.5. Sum of sinus and cosinus	397
A.6. Mathematical series	398
A.7. Greek numbers	398
Bibliography	399
Index	407