

✗ N» ) » Ø DAÄAØQÄAÄE ØS  
 ÁØØçØAAØAAU ØØ ØUADØ  
 Äø Ø DAÄAØØDAØØDAØ ØA » Ø  
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$$V(t) = r \cdot i(t) + e_b(t) \quad (3-1)$$

$$e_b(t) = K_b \cdot \dot{S}(t) \quad (3-2)$$

$$T(t) = K_t \cdot i(t) \quad (3-3)$$

$$T(t) = J \frac{d\dot{S}(t)}{dt} + T_L(t) \quad (3-4)$$

### À ØØR

$$\nu(t) = \text{ØØØØ}(V) \gg W$$

$$\dot{S}(t) = \text{ØØØØ}(rad/s) \gg W$$

$$r = \text{ØØØØ}(\Omega) \gg W$$

$$T(t) = \text{ØØØØ}(N-m) \gg W$$

$$i(t) = \text{ØØØØ}(A) \gg W$$

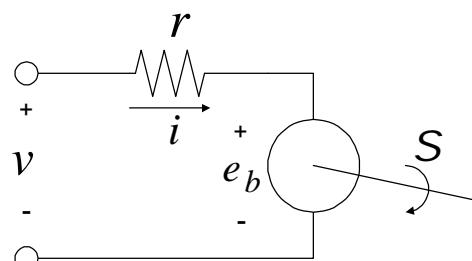
$$K_t = \text{ØØØØ}(N-m/A) \gg W$$

$$e_b(t) = \text{ØØØØ}(V) \gg W$$

$$J = \text{ØØØØ}(N-m \cdot S^2/rad) \gg W$$

$$K_b = \text{ØØØØ}(V \cdot S/rad) \gg W$$

$$T_L(t) = \text{ØØØØ}(N-m) \gg W$$



Ø6-1 ØØØØØØØ

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$$\begin{aligned} \dot{S}(t) &= \frac{v - r \cdot i}{Kb} \\ &= \frac{v - r \cdot \frac{T}{Kt}}{Kb} \\ &= \frac{v}{Kb} - \frac{r}{Kt \cdot Kb} [J\dot{S}(t) + T_L(t)] \end{aligned} \quad (3-4)$$

將上式代入拉氏變換方程，可得

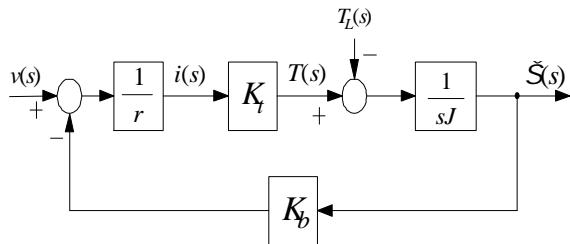


圖 3-2 精確控制輸出

當  $T_L(s) = 0$  時，由圖 3-2 得

$$S(s) = \frac{v(s)}{s^2 + \frac{r}{K_b} s + \frac{1}{sJ}}$$

$\Omega = \sqrt{\frac{1}{K_b J}}$   $\omega_n = \sqrt{\frac{r}{K_b}}$   
MATLAB Identification Toolbox 與 SIMULINK 可以求得  $K_t$ 、 $J$ 、 $r$ 。  
將  $\Omega$ 、 $\omega_n$ 、 $K_t$ 、 $J$ 、 $r$  值代入上式，可得

$$K_t = 0.0671(N \cdot m/A)$$

$$K_b = 0.0671(V \cdot s/rad)$$

$$J = 293 \times 10^{-7}(N \cdot m \cdot s^2/rad)$$

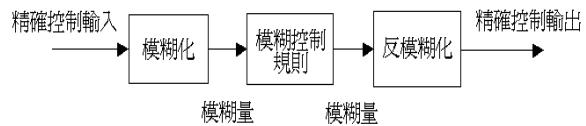
$$r = 177.79(\Omega)$$

## 3.2 模糊控制

模糊控制是基於模糊邏輯的控制方法。其特點是將被控系統的各個參數進行模糊化，根據各個參數的模糊化結果，通過模糊規則庫進行模糊推論，得到一個模糊量，再經過反模糊化，得到精確的控制輸出。

模糊控制的一般過程：

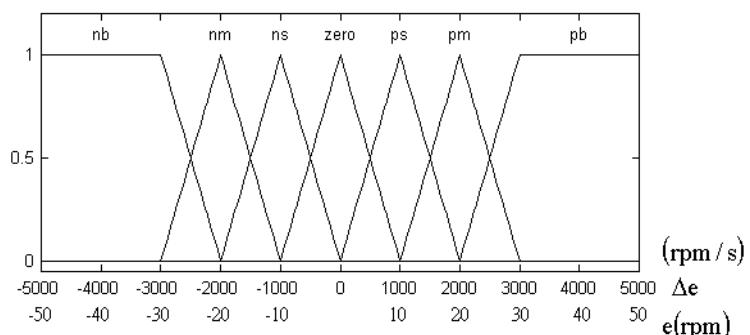
1. 精確控制輸入 → 模糊化 → 模糊控制規則庫 → 反模糊化 → 精確控制輸出



### 3.2.1 模糊控制規則庫

模糊控制規則庫是根據被控系統的特點和控制要求，確定各個模糊子集的範圍，並確定各個子集之間的關係，即確定各個規則。規則庫的構成方法有：經驗法、歸納法、知識工程法等。

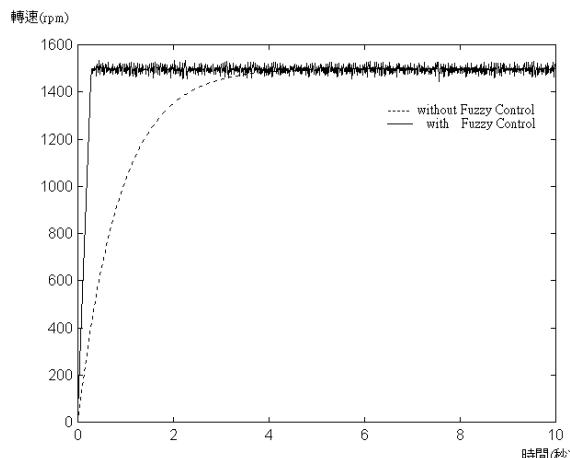
模糊控制規則庫的構成方法有：經驗法、歸納法、知識工程法等。



1. 開環響應：當輸入信號為零時，開環響應為零。

$f$	$\Delta e$							
$V$	$_S$	$_{_S}$	$_{_d}$	$kVc^{\circ}$	$ad$	$a^{\wedge}$	$aS$	
$_S$	$aS$	$aS$	$aS$	$aS$	$a^{\wedge}$	$ad$	$kVc^{\circ}$	
$_{_S}$	$aS$	$aS$	$aS$	$a^{\wedge}$	$ad$	$kVc^{\circ}$	$_{_d}$	
$_{_d}$	$aS$	$aS$	$a^{\wedge}$	$ad$	$kVc^{\circ}$	$_{_d}$	$_{_S}$	
$kVc^{\circ}$	$aS$	$a^{\wedge}$	$ad$	$kVc^{\circ}$	$_{_d}$	$_{_S}$	$_{_S}$	
$ad$	$a^{\wedge}$	$ad$	$kVc^{\circ}$	$_{_d}$	$_{_S}$	$_{_S}$	$_{_S}$	
$a^{\wedge}$	$ad$	$kVc^{\circ}$	$_{_d}$	$_{_S}$	$_{_S}$	$_{_S}$	$_{_S}$	
$aS$	$kVc^{\circ}$	$_{_d}$	$_{_S}$	$_{_S}$	$_{_S}$	$_{_S}$	$_{_S}$	

○<sub>4</sub>-2 F A E O<sub>g</sub> E A A O O D A E  
A G A I C A O X F A O O L G U Y R N O  
C G 3/4 U N A G X E 500(rpm) E A E A A O  
U N A E A O E D X R O G A O X F A X e

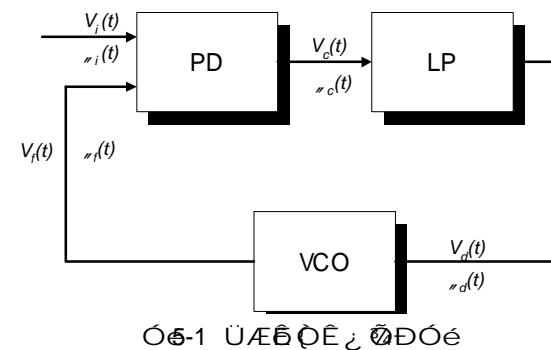


○<sub>4</sub>-3 O<sub>g</sub> F A 3/4 A A U A E ^  
O O K D A M O M E D X R A A A O N A G S A  
N I G Q H A D D X T

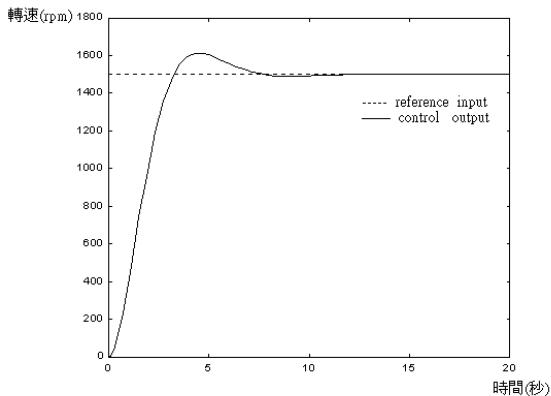
### 3/4 G M A E H D

U A E D O<sub>g</sub> A P A E E A A O A H A E  
3/4 A H T H G 3/4 A Q A S A P C I G Z  
G R A C K-1 A D A 3/4 A A H C D O A A G E A 3/4 E  
I G X R E A E D D P D ) F D U A D P D )  
3/4 M T D M O P C O ) R E A E D D Q C E  
3/4 O E A E E D O E E B D A A E S A Y  
U G 3/4 D U A O M B D D D O D U A D O  
U E B S M E A M R N A A 3/4 U T D M O A O  
U 3/4 E R N U A E D O U E A S E A R C K-1 3/4 A  
A O D D M O A J A G D E A W R D D M  
D D O G K A E G D E A M D K K D D G A O U  
I E D D T

D A A A A U A D D D D D N E A E D O  
O E E B D A O H G E A A G A A S U 3/4 A  
3/4 D R 4 E G B D A A Q A P N I G Q U A D )  
A G A L A Q G D E A U H G D D D P D )  
A A G A E A E D D D A M D D D N A A T U,  
A D D N A A G C A D Q U A D D D R 3/4 U U  
A G X E 500(rpm) E A E A A D A M U U  
A E A J E -2 X T



○<sub>4</sub>-1 U A E D O E G D D O E



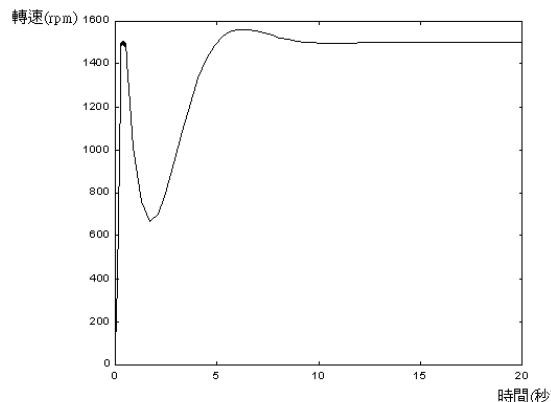
○<sub>4</sub>-2 U A E D O E G D D O E

G G C G A G R A E D D O E G U E N  
3/4 D E A M A G Q D E S A E A P A E D )  
3/4 A G R V 2 A E A G O D O G D E A M Q E  
A H T

### 3/4 G M A E H D

G G V A G O X F A 3/4 G M A E H D  
A G C A D A O D A A I A A P E B R  
C A G G H G A G O U A A D A M A D A E  
A D D E B A A G C D E A M Q A H T  
3/4 D A A D G O D E O X F A 3/4 G M A E H  
E D O G D E B D D D E N E A W A O D B E  
U E A G D G D D D E A D D R N E A W A

Y-QIE ARAQHOTAEH QEA » RNU<sup>3/4</sup>[  
Ae AEH 500(rpm) E AAWU AEAJé  
G>B» T

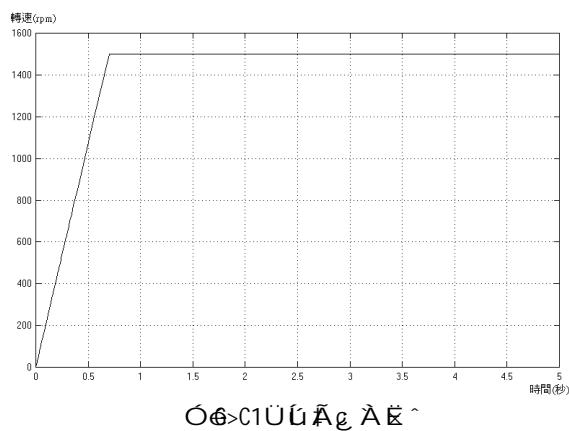


OGB1 E MOTHUHAAOATHAWU  
AEEAEH QAOHBU AAO<sup>3/4</sup>h  
OIK EAA » AEH 500(rpm) E AAWU AEA  
Ae AEH 500(rpm) E AAWU AEA  
3/4 UHU AEAQAA PAAQHCEC 3/4  
AOUAe » AAEAOHCAOUAE

Q EADAOIK EAAOQCCF  
I WOHBU AEOHBU AAWU AEA  
E O<sup>3/4</sup>AQH 3/4AOU AEA » AAEAO  
Ceez UH4OIK EAAOQCCF DPU<sup>3/4</sup> E  
OECUH AEAQ OEE E UHU AOE H:  
Ae » AAEAOHCAOUAE  
OIK EAAOQCCF DPU<sup>3/4</sup> E  
CaaA A G>B» DOK OQAA AWAQHAA  
CaaA E UHU AOU AEA UH<sup>3/4</sup> E  
AEEAA AWAQHAA E 3/4AEH E 3/4  
G>F» T

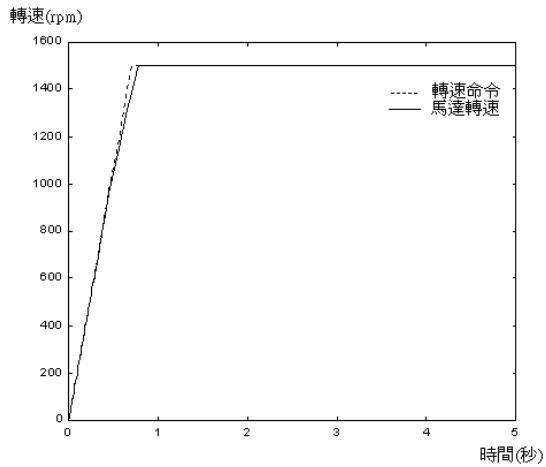
A G>B1OIK EAAU E OECA

ÜU Aeg (RPM)	OE „
0~1500	0.25
1500~3000	0.5
3000~4500	0.75
4500~6000	1

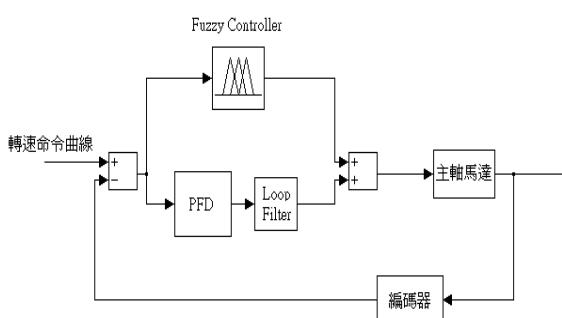


OGB1UH AEA

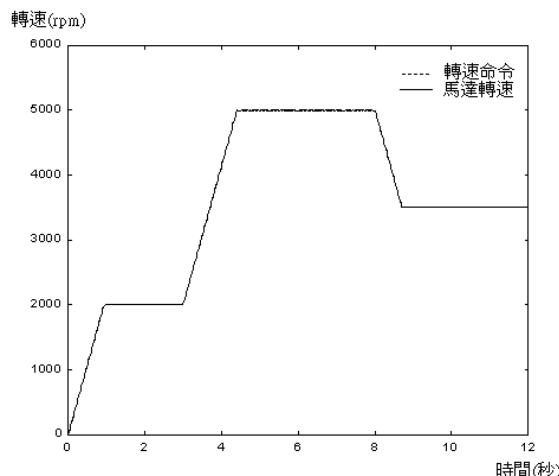
B E AWDUHUAe AEA » OIK EAAOQAA  
UEH Q<sup>3/4</sup>OHUOQHUA AKAIAE AEA  
E AAW AEAQHCAOUD» T



OGB1E AAWU AEA AEH 500rpm: Oé



OGB1Fuzzy + PLL1 AEA<sup>3/4</sup>DÓé



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[11n1] SIMULINK User's Guide, The MathWork Inc ,March 1992.

○ $\rightarrow$ F1 E 當前的值是 2000->5000->3500rpm)

### $\frac{3}{4}$ T & k

Å Ç Ö È Y 2 / 4 O O K F Å Ç Y 4 M A E B Q  
Å D A E A O O E A O B A O O U A E u  
3 / 4 A » R L U B Y 4 A I A O E N A E C  
Ö U A D A X A O R C A Q H U A E A E ^  
A E H A E A U I A A Q D U S R L A C a e  
I Y 2 A D A E A O O E U 3 / 4 O A U M A R A U e  
U E D » R L U N E A V A O W Q E A D E Y 4 f  
A 0.08 Y 4 » T

### $\frac{3}{4}$ > F A M P ~

- I Bn1  $\frac{3}{4}$  3 / 4 A » R E A U U O O I A A Z D E A  
O W A E A » R L U B Y 3 / 4 O D B Y 4 Y R  
E I F A » T
- I Cn1 N A A F R L O O B D B A O A O U  
D E A M U E A 3 / 4 A M O % R L U Y 3 / 4 {  
O A D Y 4 Y R L I G A » T
- I Dn1 I E A E » R L L A E A U A E D O U L A O  
L » R D L E A A M R E 83 A 6  $\frac{3}{4}$  » T
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