



Technology Training that Works

Practical Motion Control for Engineers and Technicians

Contents

Chapter 1 - Fundamentals of motion control	1
1.1 Introduction	1
1.2 Definition of motion control	2
1.3 Fundamental concepts	3
1.4 Engineering practice and techniques	12
Chapter 2 - Motion control techniques	17
2.1 Introduction	17
2.2 Hydraulic control system	17
2.3 Pneumatic control systems	29
2.4 Electrical control systems	35
2.5 Electro-mechanical control systems	44
2.6 Mechanical control systems	45
Chapter 3 - Motion control system loops	53
3.1 Introduction	53
3.2 Closed loop and open loop control systems	53
3.3 Sequentially controlled systems	55
3.4 Motion control systems	55
3.5 Block diagrams	57
3.6 Implementation of a motion control system	63
3.7 Bandwidth	80
Chapter 4 - Selection of the feedback	83
4.1 Introduction	83
4.2 Effect of feedback	84
4.3 Selection of the feedback	89
4.4 Feedback interface	92
4.5 Feedback resolution	95



Technology Training that Works

Chapter 5 - Physics of mechanical loads	97
5.1 Introduction	97
5.2 Behavior of mechanical components	97
5.3 Motion of rotation	98
5.4 Kinetics of motion of rotation	101
5.5 Mechanics of translation	104
5.6 Fixed axis rotation	105
Chapter 6 - Mechanical transformation devices	107
6.1 Introduction	107
6.2 Speed reducer	107
6.3 Load transmission by belts and pulleys	109
6.4 Gears	116
6.5 Reflecting loads through a transformer	125
Chapter 7 - Non-linear load transformation	127
7.1 Introduction	127
7.2 Moment of inertia of an area of plane with respect to an axis in its plane	128
7.3 Polar moment of inertia	129
7.4 Radius of gyration of an area	129
7.5 Parallel axis theorem	130
7.6 Moment of inertia of a composite area or a hollow section	131
7.7 Product of inertia	132
7.8 Displacement of axis parallel to themselves	134
7.9 Rotation of axis—principal axis and principal moments of inertia	134
7.10 Moment of inertia of a mass (rigid) body	136
7.11 Moment of inertia of solids	137
Chapter 8 - Load and system analysis	139
8.1 Motor and load considerations	139
8.2 Load driving methods	145
8.3 Load system analysis	146
Chapter 9 - Servo basics	153
9.1 Introduction	153
9.2 Basic gain equation	153
9.3 Selecting system components	158
9.4 Criteria for motor selection	158
9.5 Criteria for amplifier sizing	160
9.6 Criteria for encoder	160
9.7 Criteria for controller	161
9.8 Command generation	162
9.9 Feedback	163



Technology Training that Works

9.10 Types of servos	163
9.11 Bode diagrams or bode plots	167
<hr/>	
Chapter 10 - Servo responses	175
10.1 Introduction	175
10.2 Standard test signals	176
10.3 Sinusoidal signal	180
10.4 Performance prediction	181
10.5 Gain adjustment	183
10.6 Feed forward control	187
10.7 Stability criteria in a servo	190
10.8 'S' curves and their application	191
<hr/>	
Chapter 11 - Introduction to basics of drives	193
11.1 Introduction	193
11.2 DC/AC drives	194
11.3 Classification of drives	196
11.4 Elements of an electric drive	196
11.5 Drive motor equations	197
11.6 Compensation techniques to improve the performance	202
11.7 Duty cycle	207
<hr/>	
Chapter 12 - Direct current motors	215
12.1 Introduction	215
12.2 Fundamental principles	217
12.3 Energy conversion and losses	228
12.4 DC motors	231
12.5 Dynamic characteristics of DC machines	238
12.6 Speed control of DC motors	240
12.7 Special machines	244
12.8 Brushless DC motors	246
12.9 Motor constants	248
12.10 Formulas	249
12.11 Sample Calculation	250
<hr/>	
Chapter 13 - Stepper motors	253
13.1 Introduction	253
13.2 Principles of operation	253
13.3 Stepper motor accuracy and induced errors	264
13.4 Types of stepper motor translators (drives)	267
13.5 Translator types	270
13.6 Control methods	274
13.7 Control methods—ASIC and processor	275
13.8 Application of stepper motors	276



Technology Training that Works

Chapter 14 - AC induction motors	279
14.1 Introduction	279
14.2 Induction motors	279
14.3 Torque-speed characteristics of inductor motor	282
14.4 Split-phase control motors	283
14.5 AC servomotors	284
14.6 Control of AC motors	288
Chapter 15 - Linear motors	293
15.1 Introduction	293
15.2 Linear motor	293
15.3 Types of linear motors	296
15.4 Applications of linear motors	296
Appendix 1 - Laplace transforms	297
A1.1 Introduction	297
A1.2 Laplace transform of some useful functions	298
Appendix 2 - Motion programming	301
A2.1 Introduction	301
A2.2 Independent motion commands	301
A2.3 Stored programs	302
A2.4 Control variables	303
A2.5 Input/output interface	305
A2.6 Trip points	308
A2.7 Record	312
Appendix 3 - Coordinated motion	315
A3.1 Coordinated motion	315
A3.2 Feed rate override	316
A3.3 Variable feed rate	317
A3.4 Tangent motion	320
A3.5 Proportional motion	320
Appendix 4 - Contouring motion	323
A4.1 Contouring motion	323
A4.2 Coordinate transformation	324
A4.3 Mathematical expression	326
A4.4 Record and play back	328
Appendix 5 - Electronic gearing	331
A5.1 Electronic gearing	331
A5.2 Synchronized gantry	331
A5.3 Rotating knife control	334
A5.4 Rotating knife with mark synchronization	336



Technology Training that Works

Appendix 6 - Tension control systems	339
A6.1 Tension control systems	339
A6.2 The open loop approach	339
A6.3 Closed loop velocity control method	346
A6.4 Combined method of velocity control and electronic gearing	349

Appendix 7 - Dual loop design	353
A7.1 Dual loop design	353
A7.2 Systems with backlash	353
A7.3 The dual loop design	354
A7.4 Stability analysis	357