Answers – Exam 2014. Esbjerg.

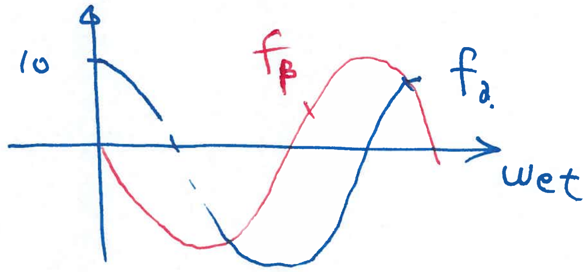
Dynamic modeling of El. machines.

Problem 1.

(1) knowing $\bar{f}_{\alpha\beta} = f_\alpha + j f_\beta$ (the definition).

Now $\bar{f} = 10 e^{-j\omega_e t} = \bar{f}_{\alpha\beta}$

therefore: $\bar{f}_{\alpha\beta} = 10 e^{-j\omega_e t} = 10 [\cos(\omega_e t) - j \sin(\omega_e t)]$



(2) Using the "Vector projection method"

$$f_a = \text{Re}\left(\frac{\bar{f}_{\alpha\beta}}{e^{j0^\circ}}\right) = 10 \cdot \cos \omega_e t.$$

(take the real part) location of phas-a axis

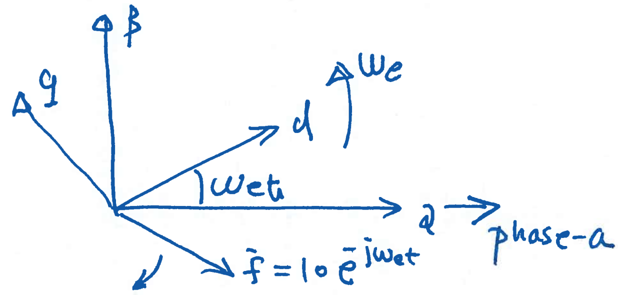
$$f_b = \text{Re}\left(\frac{\bar{f}_{\alpha\beta}}{e^{j120^\circ}}\right) = 10 \cdot \cos(\omega_e t + 120^\circ)$$

location of phase-b axis

$$f_c = \text{Re}\left(\frac{\bar{f}_{\alpha\beta}}{e^{-j120^\circ}}\right) = 10 \cdot \cos(\omega_e t - 120^\circ).$$

What we find is that compared to a normal abc sequence, here, phase-b and phase-c are exchanged.

(3)



this is how the reference frames may be defined.

You can see that at $t=0$, $\omega_e t=0$, and d-axis is alinged with phase-a axis (and the α-axis).

We use the same vector projection method. Note. for $\bar{f} = 10 e^{-j\omega_e t}$, when t increases, it is rotating in a clock-wise (negative) direction.

According to the vector projection method.

$$f_d = Re\left(\frac{\bar{f}_{\alpha\beta}}{e^{j\omega_e t}}\right) = 10 \cdot \cos(2\omega_e t) \quad \left(\text{Note. } \bar{f}_{\alpha\beta} = \bar{f} = 10 e^{-j\omega_e t}\right)$$

location of the d-axis

$$f_q = Re\left(\frac{\bar{f}_{\alpha\beta}}{e^{j(\omega_e t + 90^\circ)}}\right) = -10\sin(2\omega_e t).$$

You can now sketch their waveforms. The frequency is 100 Hz.

(4) We use the equation.

$$\bar{f}_{\alpha\beta} = \bar{f}_{abc} = \frac{2}{3}\left(V_a + V_b \cdot e^{j\frac{2\pi}{3}} + V_c e^{-j\frac{2\pi}{3}}\right)$$

$$= \frac{2}{3} \cdot V_{pk} \underbrace{\left[\sin(w_e t) + \sin\left(w_e t + \frac{2\pi}{3}\right) e^{j\frac{2\pi}{3}} + \sin\left(w_e t - \frac{2\pi}{3}\right) e^{-j\frac{2\pi}{3}}\right]}$$

The real part. of this term

$$= \sin(w_e t) + \sin\left(w_e t + \frac{2\pi}{3}\right) \cdot \cos\frac{2\pi}{3} + \sin\left(w_e t - \frac{2\pi}{3}\right) \cos\frac{2\pi}{3}$$

$$= \sin(w_e t) - \frac{1}{2} \cdot \left[\sin\left(w_e t + \frac{2\pi}{3}\right) + \sin\left(w_e t - \frac{2\pi}{3}\right)\right]$$

$$= \sin(w_e t) - \sin(w_e t) \cdot \cos\frac{2\pi}{3} = \frac{3}{2}\sin(w_e t).$$

The imaginary ~~park~~ part.

$$= \sin\left(w_e t + \frac{2\pi}{3}\right) \sin\frac{2\pi}{3} - \sin\left(w_e t - \frac{2\pi}{3}\right) \cdot \sin\frac{2\pi}{3}$$

$$= \frac{\sqrt{3}}{2} \cdot \left[\sin\left(w_e t + \frac{2\pi}{3}\right) - \sin\left(w_e t - \frac{2\pi}{3}\right)\right]$$

$$= \sqrt{3} \cdot \cos(w_e t) \cdot \sin\frac{2\pi}{3} = \frac{3}{2}\cos(w_e t)$$

Therefore.

$$\bar{f}_{\alpha\beta} = V_{pk} \cdot \frac{2}{3} \cdot \frac{3}{2} \cdot \left[\sin(w_e t) + j\cos(w_e t)\right]$$

$$= V_{pk}\, e^{j\left(w_e t - \frac{\pi}{2}\right)}$$

Then you can do the transformation. to other reference frames using the vector projection method.

Problem 3

(1)
The second row $\times -j$ and then plus the first row.

We have:

$$u_{qs} - j u_{ds} = R_s (i_{qs} - j I_{ds}) + p(\lambda_{qs} - j\lambda_{qs})$$
$$+ \omega_\theta \lambda_{ds} + j\omega_\theta \lambda_{qs}.$$

Therefore

$$\bar{U}_{qds} = R_s \bar{I}_{qds} + p\,\bar{\lambda}_{qds} + j\omega_\theta \bar{\lambda}_{qds}$$

(Note.. $j\omega_\theta \bar{\lambda}_{qds} = j\omega_\theta (\lambda_{qs} - j\lambda_{ds})$
$= \omega_\theta \lambda_{ds} + j\omega_\theta \lambda_{qs}.$)

(2) in Steady State, differentiation term of the flux linkage will dissappear. Therefore.

$$\bar{U}_{qds} = R_s \bar{I}_{qds} + j\omega_\theta \bar{\lambda}_{qds}$$