**Compte rendu**

**TP4**

**ASNL : Méthode du premier harmonique**

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# Introduction

Lors de ce TP, nous allons étudier un système non linéaire composé d’une partie linéaire représenté par un moteur, et d’une partie non linéaire représentée par un relais qui ajoute une hystérésis. Le but est d’utiliser la méthode du premier harmonique afin de pouvoir annuler les auto-oscillations du système qui peuvent avoir un impact négatif dans l’industrie. Nous allons donc tout d’abord analyser ces auto-oscillations, puis nous linéariserons le système par balayage et par retour tachymétrique.

# Étude des auto-oscillations.

Le système que nous allons étudier est représenté sur l’Annexe 1 dans sa version finale. Pour cette première partie, nous mettons de côté le retour tachymétrique représenté. Le montage se compose donc d’une partie linéaire et d’une partie non linéaire. C’est à cause de cette partie non linéaire que nous observons des auto-oscillations.

## Étude théorique.

Afin de pouvoir trouver l’amplitude X0 des auto-oscillations ainsi que la pulsation de pompage w0, nous devons chercher la limite de stabilité de notre système qui est obtenue lorsque :

avec la partie linéaire dépendant de la fréquence et la partie non linéaire dépendant de l’amplitude.

La partie de droite correspond au lieu critique, et la partie de gauche au lieu linéaire. Grâce au schéma bloc, on trouve que .

De plus, d’après le cours de ASNL, on sait que pour une hystérésis,  avec la tension de sortie et *X* l’amplitude.

Grâce à toutes ces données, nous pouvons tracer les lieux critiques et linéaire dans le plan de Nyquist et en déduire l’amplitude et la fréquence des auto-oscillations pour différentes valeurs de k1. Le script Matlab utilisé est donné en Annexe 2. On obtient avec ce script les graphiques donnés en annexe 3 et 4. La fréquence de pompage est obtenue en plaçant le curseur sur la courbe du lieu linéaire au niveau du point d’intersection avec le lieu critique (voir Annexe 4). Quant à l’amplitude, on l’obtient en déterminant entre quels points du lieu critique se situe l’intersection. Chaque point correspond à une amplitude, et on en déduit donc l’amplitude de nos auto-oscillations.

Le tableau des résultats obtenus est présenté en Annexe 5. On remarque que plus k1 est grand, plus la pulsation de pompage est grande, et plus l’amplitude est grande.

## Étude pratique.

Avant de pouvoir placer notre relai dans le montage, il faut vérifier ses caractéristiques pour qu’elles correspondent à l’hystérésis désirée. Pour cela, on branche notre relai à un oscilloscope en mode XY. Après réglage, on obtient l’hystérésis montrée en Annexe 6. On peut remarquer que nous avons bien les caractéristiques désirées à savoir l’hystérésis H à la valeur correcte de 1 V sur le module relais simulé et la sortie Sr vaut ±7.25V.

Une fois le relais calibré, on l’insère dans la boucle du système et on va caractériser les auto-oscillations du moteur avec ce relais.

Sur l’Annexe 7, on peut visualiser notre montage. On peut y voir que notre gain k1 est réalisé à l’aide d’un potentiomètre qui fonctionnement comme un pont diviseur de tension. L'auto-oscillation est une technique qui consiste à ajouter une boucle de rétroaction à un système et à augmenter le gain jusqu'à ce que le système commence à osciller spontanément. Ensuite, on peut mesurer les caractéristiques de cette oscillation, telles que la fréquence et l'amplitude, pour déterminer le lieu critique du système.

On peut voir aussi notre boucle est réalisé à l’aide d’un montage AOP. On peut remarquer aussi que nous n’avons pas de signal à l’entrée + de notre soustracteur, nous cherchons juste à tracer le lieu critique de notre relais.

Grâce à ce montage, nous avons pu récupérer les valeurs pratiques d'amplitude et de gain pour différents k1 donnés, notées dans l’Annexe 8. Nous remarquons que l’amplitude et les pulsations des auto-oscillations de notre système augmentent avec le gain, ce qui est en adéquation avec la théorie. Les valeurs obtenues sont proches des valeurs théoriques. Ces mesures nous permettent alors de tracer le lieu critique de notre relais. Pour cela, on trace les différents lieux linéaires correspondant à chaque valeur de gain testées. Pour chaque courbe, on place un marqueur sur le point dont la fréquence correspond à la pulsation de pompage. Puis, en reliant les différents points trouvés, nous pouvons ainsi identifier le point critique du relais.

Dans notre tableau donné dans l’Annexe 8, on remarque des % d’erreur entre nos valeurs théoriques et expérimentales. Cela s’explique notamment par les caractéristiques du moteur en pratique qui ne sont pas les mêmes que celle en simulation. De plus nous effectuons des « mesures », il est donc normal d’avoir des différences dues aux précisions des appareils. Néanmoins les résultats obtenus sont dans les mêmes ordres de grandeurs.

# Linéarisation par balayage.

## Étude pratique.

Maintenant, nous cherchons à atténuer ces auto-oscillations qui peuvent être gênantes dans l’industrie. Pour cela nous allons réaliser une linéarisation par balayage. La linéarisation par balayage est une méthode utilisée en automatique pour approximer le comportement non-linéaire d'un système par un modèle linéaire. Cette technique consiste à appliquer une entrée sinusoïdale à fréquence variable sur le système et à mesurer sa réponse en sortie. On fixe notre relais à H=1 et notre gain k1=0,5.

Dans un premier temps, nous avons réglé le GBF pour avoir une sortie sinusoïdale fréquence 50 Hz et d’amplitude 0.2 V. Le système étant en auto-oscillation, nous avons ajouté un signal d’erreur sur une autre entrée du relais, pour notre montage sur l’entrée + de notre montage AOP vu sur l’Annexe 7. Nous avons augmenté progressivement l’amplitude sur notre GBF, et nous avons observé que les auto-oscillations disparaissent au bout d’une amplitude de 1,2Vpp.

## Vérification sous Matlab.

Afin de vérifier ces observations sous Matlab, nous allons utiliser le schéma Simulink présenté en Annexe 9. On observe que dès que la tension d’entrée du GBF dépasse 0.5, les auto-oscillations ne sont plus présentent. On peut faire cette observation grâce aux Annexes 9 et 10. Cela est dû aux caractéristiques de notre hystérésis. Dès que l’amplitude du GBF dépasse la demi-largeur de l’hystérésis (0.5), les auto-oscillations sont atténuées.

AUGMENTER PETIT A PETIT LE GBF EN SIMU.

EXPLIQUER LA THEORIE A L’AIDE DES AUTRES COMPTES RENDUS.

En résumé, l'utilité de la linéarisation par balayage en automatique est de faciliter la conception de régulateurs pour des systèmes non-linéaires en approximant le comportement non-linéaire du système par un modèle linéaire.

# Correction par boucle secondaire tachymétrique.

## Étude pratique.

Ce paragraphe décrit l'utilisation d'un type de correcteur qui implique l'ajout d'une boucle de rétroaction supplémentaire dans le système d'asservissement. Dans ce cas précis, cette boucle de rétroaction, réalisée à l’aide d’un deuxième montage AOP, permet de mesurer la vitesse du moteur et de l'utiliser pour effectuer la régulation de ce dernier. Pour cela, on utilise un capteur de vitesse du moteur, dont le signal est amplifié par un gain k2 (à l’aide d’un nouveau potentiomètre) avant d'être utilisé dans le processus de régulation.

Tout d’abord, on garde H = 1V et on règle k1 = 0.5. Initialement, lorsque le taux de contre-réaction tachymétrique était réglé sur 0, le système continuait à présenter des auto-oscillations, avec une amplitude de 0.845 Vpp. Cependant, dès que nous avons augmenté le taux de contre-réaction tachymétrique, l'amplitude, la forme et la fréquence des oscillations ont été altérées. En effet, une augmentation du taux de contre-réaction est associée à une diminution de l'amplitude et à une augmentation de la fréquence.

Ensuite, nous avons déterminé expérimentalement la valeur du taux de contre-réaction tachymétrique permettant de diviser par deux l'amplitude de l'auto-oscillation. Nous avons obtenu comme résultat un taux de contre-réaction tachymétrique k2 égal à 0,6.

## Vérification sous Matlab.

Afin des vérifier ces observations sous Matlab, nous devons trouver les nouvelles limites de stabilité de notre nouveau système. Ces nouvelles limites de stabilité sont obtenues avec l’équation :

On trace alors les lieux critiques et linéaires dans le plan de Nyquist pour différentes valeurs de k2. Le graphique obtenu est présenté en annexe ? et ?. Le but est d’identifier sur ce graphique pour quelle valeur de k2 le point d’intersection diminue par 2 l’amplitude des auto-oscillations, càd

Sur le graphique, on trouve que pour k2 = 0.7, l’amplitude est environ égale à 0.63.

En utilisant le retour tachymétrique, il est possible de mesurer avec précision la vitesse du moteur et de l'ajuster en temps réel pour compenser les perturbations qui pourraient affecter la vitesse du moteur. Cela permet d'obtenir un contrôle plus précis du moteur et d'améliorer sa performance.

# Conclusion.

# Annexes

Une image contenant diagramme

Description générée automatiquement

Annexe 1 : Schéma simulink du système étudié

Une image contenant texte

Description générée automatiquement

Annexe 2 : Script Matlab pour afficher les lieux dans le plan de Nyquist

Une image contenant diagramme

Description générée automatiquement

Valeurs de k1 selon les couleurs : bleu/0.3 orange/0.4 jaune/0.5 violet/0.6 vert/0.7

Courbe rouge : Lieu critique

Annexe3 : Tracé des lieux critique et linéaire dans le plan de Nyquist pour différents k1

Une image contenant graphique

Description générée automatiquement

Valeurs de k1 selon les couleurs : bleu/0.3 orange/0.4 jaune/0.5 violet/0.6 vert/0.7

Courbe rouge : Lieu critique

Annexe 4 : Zoom sur les points d’intersection de l’annexe 3

|  |  |  |
| --- | --- | --- |
| k1 | Pulsation de pompage w0  (en rad/s) | Amplitude |
| 0.3 | 9 | 1.08 |
| 0.4 | 10 | 1.18 |
| 0.5 | 10.9 | 1.27 |
| 0.6 | 11.7 | 1.34 |
| 0.7 | 12.3 | 1.41 |

Annexe 5 : Tableau récapitulatif des pulsations et amplitudes des auto-oscillation en fonction de k1

![Une image contenant texte, écran, intérieur, micro-ondes

Description générée automatiquement](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEASABIAAD/4UMURXhpZgAATU0AKgAAAAgACgALAAIAAAAmAAAIkgESAAMAAAABAAEAAAEaAAUAAAABAAAIuAEbAAUAAAABAAAIwAEoAAMAAAABAAIAAAExAAIAAAAmAAAIyAEyAAIAAAAUAAAI7gITAAMAAAABAAEAAIdpAAQAAAABAAAJAuocAAcAAAgMAAAAhgAAEhYc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFdpbmRvd3MgUGhvdG8gRWRpdG9yIDEwLjAuMTAwMTEuMTYzODQAAAAASAAAAAEAAABIAAAAAVdpbmRvd3MgUGhvdG8gRWRpdG9yIDEwLjAuMTAwMTEuMTYzODQAMjAyMzowMzoyMiAxNjoyOToxMwAAEJAAAAcAAAAEMDIyMZADAAIAAAAUAAAR1JAEAAIAAAAUAAAR6JAQAAIAAAAHAAAR/JARAAIAAAAHAAASBJASAAIAAAAHAAASDJEBAAcAAAAEAQIDAJKQAAIAAAAEMzA4AJKRAAIAAAAEMzA4AJKSAAIAAAAEMzA4AKAAAAcAAAAEMDEwMKABAAMAAAABAAEAAKACAAQAAAABAAAE3KADAAQAAAABAAAIoKQGAAMAAAABAAAAAOocAAcAAAgMAAAJyAAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Annexe 6 : Hystérésis obtenue après calibration

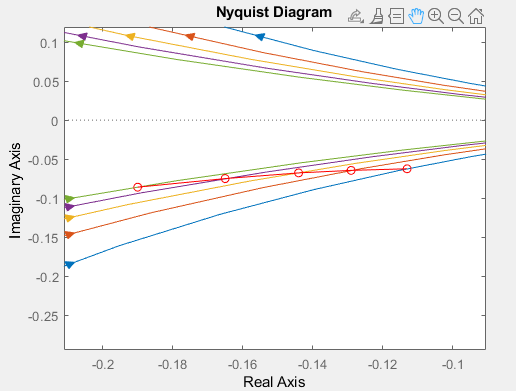
Une image contenant texte, Appareils électroniques

Description générée automatiquement

Annexe 7 : Montage pour observer des auto-oscillations

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| k1 | w théorique (en rad/s) | w réel  (en rad/sec) | % d’erreur | Amplitude théorique | Amplitude réelle | % d’erreur |
| 0.3 | 9 | 8.48 | 5,78% | 1.08 | 1.35 | 25% |
| 0.4 | 10 | 9.36 | 6.4% | 1.18 | 1.55 | 31,36% |
| 0.5 | 10.9 | 10.05 | 7.80% | 1.27 | 1.69 | 33,07% |
| 0.6 | 11.7 | 10.37 | 11,37% | 1.34 | 1.83 | 36.57% |
| 0.7 | 12.3 | 10.43 | 15.20% | 1.41 | 1.97 | 39,72% |

Annexe 8 : Tableau comparatif des valeurs de w et d’amplitude réelles et théoriques



Valeurs de k1 selon les couleurs : bleu/0.3 orange/0.4 jaune/0.5 violet/0.6 vert/0.7

Courbe rouge : Lieu critique

Annexe 9 : Tracé du lieu critique du relai sous Matlab

Une image contenant diagramme

Description générée automatiquement

Annexe 10 : Schéma Simulink du montage avec le GBF

Une image contenant diagramme

Description générée automatiquement

Valeurs de k2 : k2 va de 0.1 à 1 par pas de 0.1 en partant de la gauche (bleu) vers la droite (jaune)

Courbe rouge : Lieu critique

Annexe 11 : Tracé des lieux critique et linéaire dans le plan de Nyquist pour différents k2

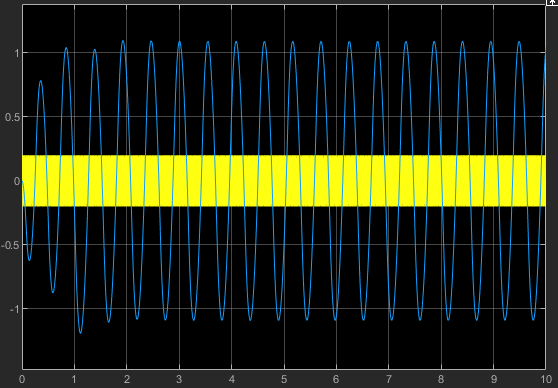
Une image contenant graphique

Description générée automatiquement

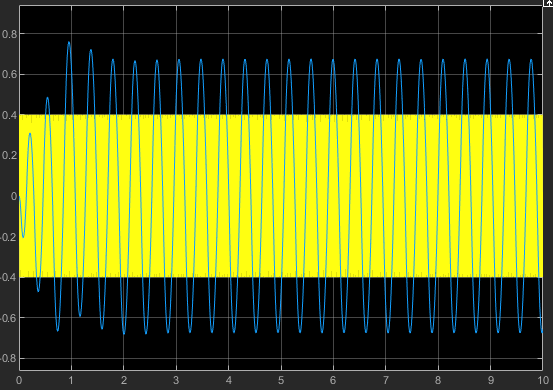
Valeurs de k2 : k2 va de 0.1 à 1 par pas de 0.1 en partant de la gauche (bleu) vers la droite (jaune)

Courbe rouge : Lieu critique

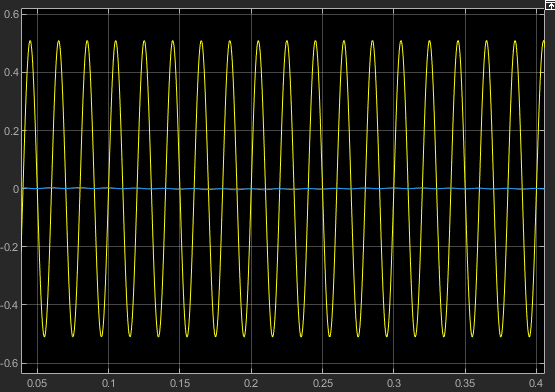
Annexe 12 : Zoom sur les points d’intersection de l’annexe 11.



Amplitude GBF = 0.2V



Amplitude GBF = 0.4V



Amplitude GBF = 0.51V