

Lab Procedure

Block Diagram Modeling Virtual

Introduction

Ensure the following:

1. You have reviewed the [Application Guide – Block Diagram Modeling](#)
2. Make sure you have Quanser Interactive Labs open in the Qube 3 - DC Motor → Servo Workspace.
3. Launch MATLAB and browse to the working directory that includes the Simulink models for this lab.

The **Hardware Interfacing** and **Filtering** labs explained the basic blocks to read and write from the Qube-Servo 3. For simplicity, all labs forward will use a Qube-Servo 3 block that sets up the system beforehand and outputs the available information from the Qube.

Using the gains found to convert tachometer counts/s into rad/s into rads from the instrumentation labs, use the [qs3_block_modeling.slx](#) file to design a model that applies a 2-6 V, 0.4 Hz square wave to the motor and reads the angular velocity using the encoder as shown in Figure 1. We will complete the *QUBE-Servo Model* subsystem during this lab.

The goal of this lab is to model the angular velocity of the Qube-Servo 3 when a 2-6 V, 0.4 Hz square wave is inputted.

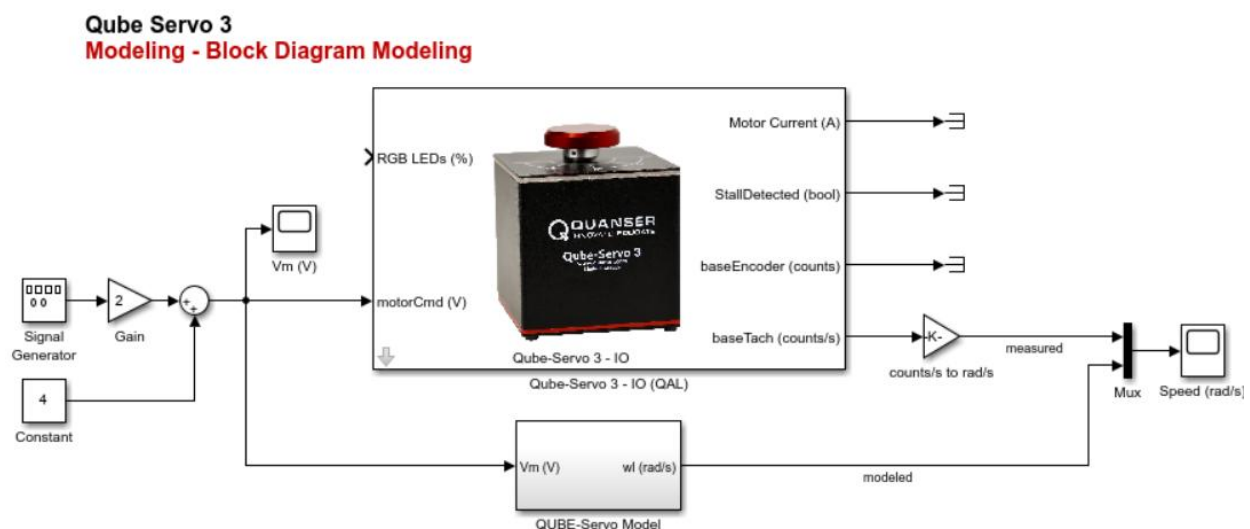


Figure 1: Model that applies a square wave voltage and displays measured and modeled speeds.

Block Diagram Modeling

1. Open the subsystem called **Qube-Servo Model** in your model.
2. Using the Qube-Servo 3 User Manual, record constants that are important to modeling the system dynamics.
3. Implement the partial solution shown in Figure 2. While modeling you'll need a few **Gain** blocks, a **Subtract** block and an **Integrator** block (to go from acceleration to speed). The subsequent steps will highlight important components in your model.
 - a. It may help to write a short MATLAB script that sets the various system parameters in the workspace so that they can be used by the Simulink model. For example, Figure 2 uses R_m for motor resistance and k_t for the current-torque constant as shown below:

```
% Resistance
Rm = 7.5;
% Current-torque (N-m/A)
kt = 0.042;
```

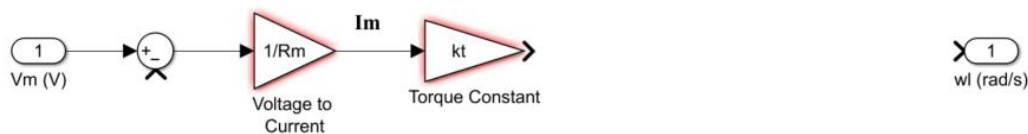


Figure 2: Incomplete Qube-Servo 3 Model.

4. The motor shaft of the Qube-Servo 3 is attached to a load **hub** and an **inertia disc** load. **Based on the parameters given in the user manual, calculate the total moment of inertia that is acting on the motor shaft.** Save your calculations.
5. Add the total moment of inertia to your block diagram model of the Qube-Servo 3.
6. Add the Back-EMF constant to your block diagram model of the Qube-Servo 3.
7. Save a screenshot of your block diagram model and the parameters you used.
8. Run the QUARC controller using the Run button on the **Simulation** tab. The speed (rad/s) scope response should be similar to Figure 3. Take a screenshot of the scope.

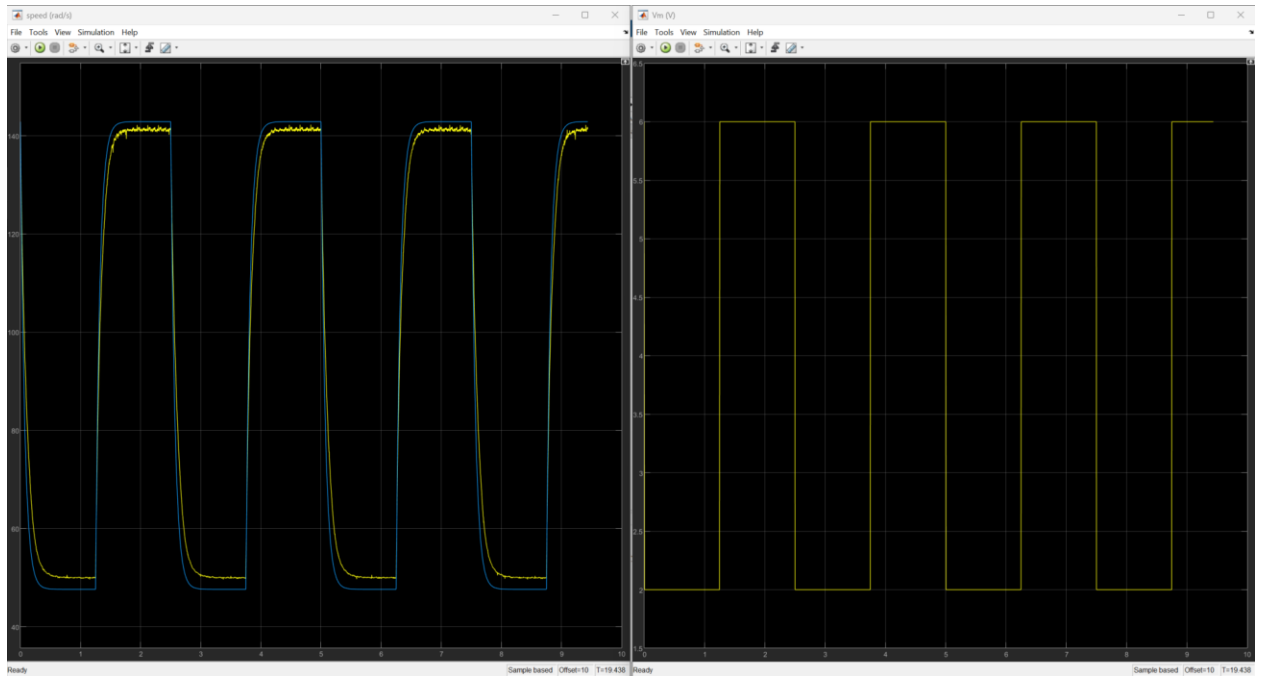


Figure 3: Speed scope of the Qube-Servo 3 Physical Vs. Model

9. Stop the Simulink model. Ensure you save a copy of the files for review later.
10. Close your model.
11. Close Quanser Interactive Labs.