Motomatic System Characterization

Fill in the system parameters (with units).

Component:

Parameter	Value	Units
Kknob		
R1		
R2		
Rf		
Ka		
Km		
Vdb+		
Vdb-		
Vdb-avg		
Km-lin		
Tm		
Kpulley		
Kq		

Results:

	Experimental	Linearized	Non-linear	Units
%OS				
Tp				
Kss				

CLTF: **OLTF:**