# Induction Motor

=> Induction motor (defn, advantage, disadvantage)

-> Induction motor (working principle)

> RMF 1 How RMF is peroduced?

> Fract equivalent cirrouit (at an slip), transformen equivalent cincuit.

and of move in had

> Powen stayes in 3 phase induction motor

Synchronous V5 -Induction

>> Synchronous motor working principle

34.3, 34.4, 34.5, 34.14(a), 34.19, 34.27

#### Sleppen Moton:

> Driving modes

⇒ VFD

> Magnet: O Variable frequency drive @ Permanent mougnet 1 Hybrid

Math: 39.1, 39.2

## Heasunement and ennon

> Acounacy Vs precision

> 6.1, 6.2 - (All math from slide) 6.2 → 4.1, 4.2 (\* \* \*)

> slide 5,6 (Tanek sin): Impedance matching Mechanical loading

& sin en notes (Full)

#### OP-Amp

- > Depr of op-amp
- ⇒ log amplifier (Proof)

- > CMRR, voltage gain (voltage curive)
- chanactoristics of op-amp

Plath: 12.3, 12.4, 13.5-13.8, 13.10, 13.11, 14.8, 14.9

=> 7 segment, DVM

## OP-to electronicis

- > Thermocouple Math
- > Transducen (Tarek sin 10 no slide)

  - > electrical transducen
    > characteristics
    > types
- > PV COLL (10 Start 1)

  - > Working principle

    > Advantages, disadvantages, Defn
- > Temp [RTD
- > Piezo electric (Application)
- > Photodiode | LED (\*\*\*

From Taneg Sin (slide 3)

> Stepper motor thanking principle

=> Steppen motor types and contribution

> Roton > 1. PMR (Permanent magnet noton)

2. VRR (Variable Reductance Roton)

3. FIR (Hybrid Rotory)

[ Figure + Description te line]

>-How synchronous motor make self starting

> RTD (Principle)

-> Strain Gauge (principle + Gauge factor eqn Prove) \*\*\*

-> Piezo electric (principle) \*\*\*

> RTD VS Thenmocouple

> Thenmocouple (single math)

=> Measwrement & ennon (all math)

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