

حل: علی پورچ

VI- گزشتہ

$$\text{الف) } R\phi = NI \Rightarrow \frac{L}{\mu \cdot \mu_A A} \times \phi_A = NI \Rightarrow \phi_A = \frac{NI \cdot I_1}{\frac{L}{\mu \cdot \mu_A A}} = \frac{\mu \cdot \mu_A A NI_1}{L}$$

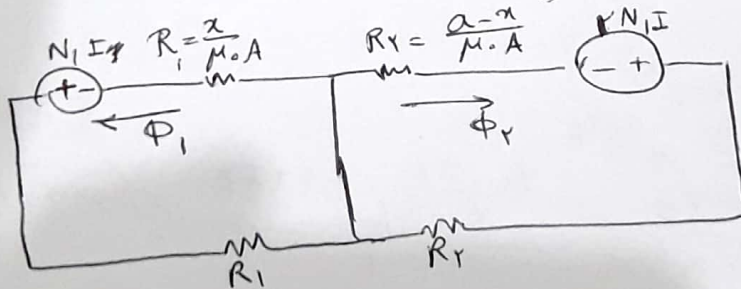
$$\text{ب) } R\phi = NI \Rightarrow \left(\frac{L}{\mu \cdot \mu_B A} + \frac{g}{\mu \cdot A} \right) \phi_B = NI \cdot I_1$$

$$\Rightarrow \phi_B = \frac{NI \cdot I_1}{\frac{L}{\mu \cdot \mu_B A} + \frac{g}{\mu \cdot A}} = \frac{\mu \cdot \mu_B A NI_1}{L + g \mu_B}$$

$$\Rightarrow \phi_B = \frac{2 \mu \cdot \mu_A A NI_1}{L + 2g \mu_A}$$

$$\left\{ \begin{array}{l} B_1 = \frac{\phi_A}{A} \\ B_2 = \frac{\phi_B}{A} \end{array} \right. \Rightarrow \left\{ \begin{array}{l} (g \rightarrow \bullet) \Rightarrow B_2 = 2B_1 \\ g > \bullet \Rightarrow B_2 < 2B_1 \end{array} \right.$$

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$$F_1 = -\frac{1}{\mu} \phi_1^2 \frac{dR_1}{dx} = -\frac{1}{\mu} \phi_1^2 \times \frac{2}{\mu \cdot A}$$

موازنہ قوتوں $\Rightarrow (F_1 = F_2) \Rightarrow \phi_1 = \phi_2$

$$F_2 = -\frac{1}{\mu} \phi_2^2 \frac{dR_2}{dx} = -\frac{1}{\mu} \phi_2^2 \frac{2(-1)}{\mu \cdot A}$$

$$\left\{ \begin{array}{l} \phi_1 = \frac{NI}{2R_1} = \frac{NI}{\frac{2x}{\mu \cdot A}} \\ \phi_2 = \frac{2NI}{2R_2} = \frac{2NI}{\frac{2(a-x)}{\mu \cdot A}} \end{array} \right. \Rightarrow \frac{2x}{\mu \cdot A} = \frac{a-x}{\mu \cdot A} \Rightarrow \boxed{x = \frac{a}{2}}$$

۷۴ - گزینه ۴

شرط ماکزیمم آوج برقرار کنیم

$$I_a = \frac{E_a - \overset{R_f I_f}{V_t}}{r_a} = \frac{400 \frac{I_f}{3 + I_f} - 49 I_f}{1}$$

$$\frac{d I_a}{d I_f} = 0 \rightarrow \frac{400(3 + I_f) - 400 I_f - 49 \cdot 1}{(3 + I_f)^2} = 0$$

$$\frac{1200}{(3 + I_f)^2} - 49 = 0 \rightarrow 1200 = 49(3 + I_f)^2 \Rightarrow \boxed{I_f = 3 \text{ A}}$$

$$I_{a \max} = \frac{400 \times 3}{3 + 3} - 49 \times 3 = 300 - 147 = \boxed{153 \text{ A}}$$

$$E_a = V_t - (R_a + R_s) I_a = 400 - 2 \times 100 = 200 \text{ V} \quad \text{۷۵- گذرینا}$$

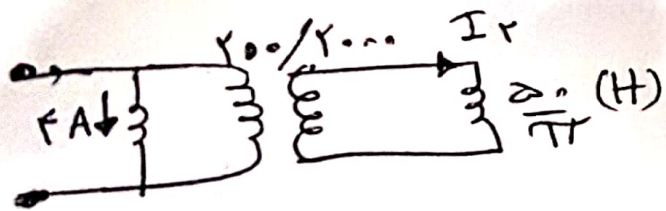
$$E_a = k \phi \omega = k' I_a \omega = k' \times 100 \times 100 = 200 \rightarrow \boxed{k' = 0.4}$$

↓
موتور سری

$$I_{ast} = \frac{V_t}{R_a + R_s} = \frac{400}{2} = 200 \text{ A}$$

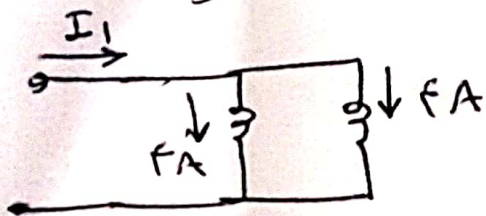
$$T_{st} = k' I_{ast}^2 = 0.4 \times 200^2 = 16000 \text{ N.m}$$

↓
موتور سری



$$I_r = \frac{2000}{\frac{50}{\pi} \times 2\pi f} = \frac{2000}{5000} = \frac{4}{5} \text{ A} \quad \text{۷۶- گذرینا}$$

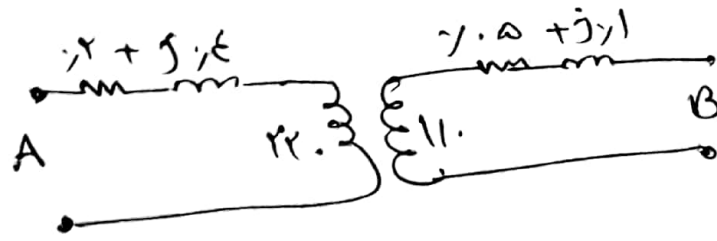
$$I_r' = \frac{4}{5} \times 10 = 8 \text{ A} \quad \leftarrow \text{انتقال به سمت اولیه}$$



$$I_1 = 4 + 4 = 8 \text{ (A)}$$

هر دو سلف هستند
در شیم عددی جمع می کنیم

۷۷ - کزینه ۱



$$Z_{eqA} = (j4 + j1) + \left(\frac{22}{11}\right)^2 (1.5 + j1)$$

$$\boxed{Z_{eqA} = j4 + j1}$$

$$S_n = V_n I_n \Rightarrow 22 \text{ VA} = 22 \times I_n \Rightarrow \boxed{I_n = 1 \text{ A}}$$

$$\frac{V_L}{V_H} = \frac{22}{22} = 1 \Rightarrow S_{Auto} = \frac{S_t}{1-k} = \frac{22 \text{ kVA}}{1-\frac{1}{3}} = 33 \text{ kVA} \Rightarrow \boxed{I_{n_{Auto}} = 3 \text{ A}}$$

$$V \cdot R_t = \frac{R_{eqp} I_p \cos \phi + X_{eqp} I_p \sin \phi}{V_{rn}} = \frac{j4 \times 1 \times j1 + j1 \times 1 \times j1}{22}$$

$$V \cdot R_t = 0.24$$

$$V \cdot R_{Auto} = V R_t (1-k) = 0.24 \times \left(1 - \frac{1}{3}\right) = 0.12 = \boxed{1.2\%}$$

(با صرف نظر از تلفات ۲۸ W)

-VA

$$S_B = 1 - \left(\frac{P_B}{P_A} \frac{1 - S_A}{S_A} \right) \xrightarrow{S_B = S_A} S_A = 1 - \left(\frac{K}{1} \frac{1 - S_A}{S_A} \right)$$

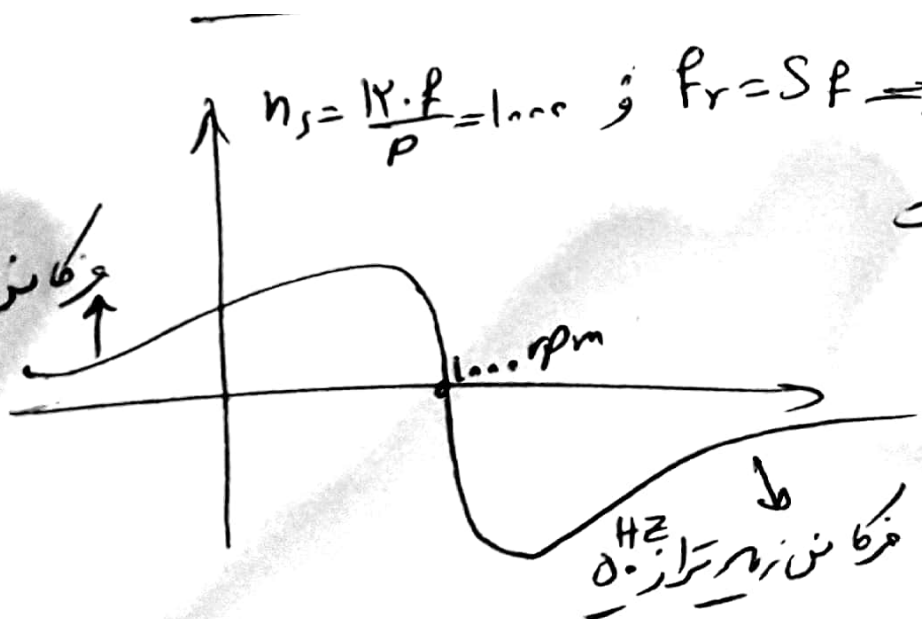
$$\Rightarrow 1 - S_A = \frac{K}{1} \frac{(1 - S_A)}{S_A} \Rightarrow 1 = \frac{K}{1 \cdot S_A} \Rightarrow \boxed{S_A = \frac{K}{1}} = S_B$$

$$n_{S_A} = \frac{K \cdot P}{P} = 4.0 \Rightarrow n_{r_A} = (1 - S_A) n_{S_A} = (1 - \frac{K}{1}) \times 4.0 = \frac{1}{4} \times 4.0 = 1.0 \text{ rpm}$$

$$n_s = \frac{12 \cdot f}{p} = 1000 \text{ و } f_r = S f \Rightarrow S = \frac{n_s - n_r}{n_s} = \frac{1000 - n_r}{1000} \quad \text{--- } \checkmark \text{ a}$$

برای رزوناتوری بزرگه قطعا n_r بیل از 1000 rpm است

$$f_r = S f = \frac{1000 - n_r}{1000} \times 50$$



$$f_r = 12 = \frac{1000 + n_r}{1000} \times 50 \Rightarrow \boxed{n_r = 140}$$

$$f_r = 22 \text{ Hz} = \frac{1000 + n_r}{1000} \times 50 \Rightarrow \boxed{n_r = 380}$$

برای جلوگیری از منفی شدن سرعت مناسب حالت ترمز n_r را حساب می کنیم

$$I_r(t) = 1 \cdot \sqrt{2} \sin(\omega t + \phi_r) \Rightarrow I_{rms} = 1 \text{ A}$$

۱-۲ کرنس

$$f_r = S f \Rightarrow 1 = S \times \omega \rightarrow S = \frac{1}{\omega}$$

$$P_{jr} = S P_{ag} = \frac{1}{\omega} \times 9 \text{ kW} = \frac{9 \text{ kW}}{\omega}$$

$$P_{jr} = 3 R_r I_{rms}^2 \Rightarrow \frac{9}{\omega} = 3 \times R_r \times 1^2 \Rightarrow R_r = \frac{3}{\omega} = 4 \Omega$$

۱۱- کرنس

$$P_r = \left(\frac{V_1 V_r}{X=1} \sin(\delta_r - \delta_1) \right) - (P_0 + \gamma V_r^2)$$

$$Q_r = \left(\frac{V_1 V_r}{X=1} \cos(\delta_r - \delta_1) \right) - (Q_0 + \gamma V_r^2)$$

$$\frac{\partial P_r}{\partial \delta_r} = V_r \cos \delta_r$$

$$\frac{\partial P_r}{\partial V_r} = \sin \delta_r - \gamma V_r$$

$$\frac{\partial Q_r}{\partial \delta_r} = V_r \sin \delta_r$$

$$\frac{\partial Q_r}{\partial V_r} = \gamma V_r - V_1 \cos \delta_r - \gamma$$

$$J = \begin{bmatrix} V_r \cos \delta_r & \sin \delta_r - \gamma V_r \\ V_r \sin \delta_r & \gamma V_r - V_1 \cos \delta_r - \gamma \end{bmatrix} \Bigg|_{\substack{V_r=1 \\ \delta_r=0}} = \begin{bmatrix} 1 & -\gamma^2 \\ 0 & \gamma \end{bmatrix}$$

$$\beta L = \omega l \sqrt{LC} = 2\pi f l \sqrt{LC} = 2\pi \times 10^3 \times 1 \times \frac{1}{\sqrt{10^{-9} \times 10^{-7}}} = \frac{2\pi \times 10^3 \times 1}{\sqrt{10^{-16}}} = \frac{2\pi \times 10^3 \times 1}{10^{-8}} = 2\pi \times 10^{11}$$

$$\beta L = 2\pi \times 10^{11} = \frac{\pi}{f}$$

$$\sin \beta L = \frac{\sqrt{r}}{r}, \quad G_s \beta L = \frac{\sqrt{r}}{r} \Rightarrow \begin{cases} A = G_s \beta L = \frac{\sqrt{r}}{r} \\ B = j Z_c \sin \beta L = j Z_c \frac{\sqrt{r}}{r} \end{cases}$$

$$X_{sh} = \frac{B}{\frac{V_s}{V_R} - A} = \frac{Z_c \frac{\sqrt{r}}{r}}{\frac{r\sqrt{r}}{r} - \frac{\sqrt{r}}{r}} = \frac{Z_c \frac{\sqrt{r}}{r}}{\frac{r\sqrt{r} - \sqrt{r}}{r}} = \frac{Z_c \frac{\sqrt{r}}{r}}{\frac{\sqrt{r}}{r}} = r Z_c$$

$$Q = \frac{V_{in}}{X_{sh}} = \frac{V_{in}}{r Z_c} \Rightarrow SIL = \frac{V_{in}^2}{Z_c} \Rightarrow Q = \frac{1}{r} SIL$$

۱۳۰ - گذریم

$$Q_{\phi} = \dots = \text{Im} \left(\frac{V^r}{Z^*} \right) = \text{Im} \left(\frac{V^r}{1. \sqrt{R} - j1.} \right)$$

$$Q_{\phi} = \text{Im} \left(\frac{V^r (1. \sqrt{R} + j1.)}{(1. \sqrt{R})^2 + 1.^2} \right) \Rightarrow \frac{V^r \times 1.}{(1. \sqrt{R})^2 + 1.^2} = \dots$$

$$V^r = \dots \Rightarrow \boxed{V = \sqrt{\dots}}$$

$$S_{\phi} = \frac{V^r}{|Z|} = \frac{\dots}{\sqrt{(1. \sqrt{R})^2 + 1.^2}} = \frac{\dots}{\sqrt{R..}} = \frac{\dots}{R.} = \dots \text{ (V.A)}$$

$$S_{\phi} = \dots \text{ (VA)}$$

$$\begin{cases} Q = X I^r = \dots \Rightarrow I^r = \frac{\dots}{1.} = \dots \Rightarrow P = R I^r = \dots \sqrt{R}, \text{ (Do)}, \\ S = \sqrt{P^2 + Q^2} = \dots \Rightarrow S_{\phi} = \dots \end{cases}$$

۱۴ - گزینہ ۲

$$X_C = \frac{V_{rms}}{I_{rms}} = \frac{V_{rms}}{V_{rms} / Z} = Z \dots \Omega$$

$$\frac{1}{\omega C} = \frac{1}{2\pi f C} = Z \dots \Rightarrow \boxed{C = \frac{1}{Z \dots \pi}}$$

$$W_{max} = \frac{1}{2} C V_{max}^2 = \frac{1}{2} \times \frac{1}{Z \dots \pi} \times (V_{rms} \sqrt{2})^2 = V_{rms}^2 = V_{rms}^2 \text{ J}$$

۱۵ - گزینہ ۲

$$GMD \uparrow \Rightarrow L \uparrow \propto \ln \frac{GMD \uparrow}{GMR}, \quad C \downarrow \propto \frac{1}{\ln \frac{GMD \uparrow}{GMR}}$$

$$Z_C \uparrow = \sqrt{\frac{L \uparrow}{C \downarrow}} \Rightarrow SIL \downarrow = \frac{V_n^2}{Z_C \uparrow}$$