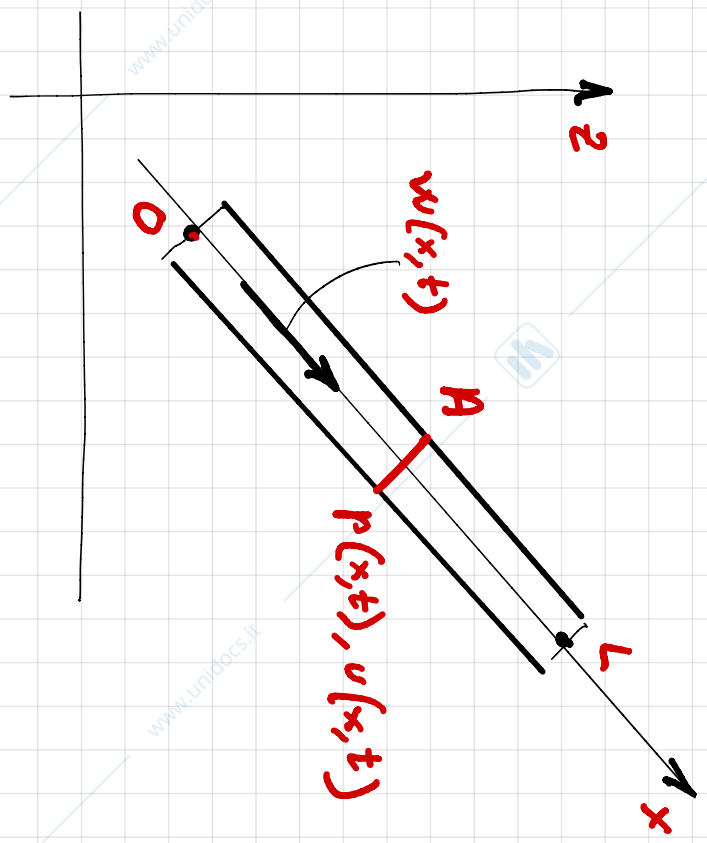


CONTROLLO MINIMO DI LIVELLO E PORTATA

- MODELLO DI UNA CORDETTA VIBRANTE



- $\rho = \text{cost.}$ DENSITA'
- $A = \text{cost.}$ SEZIONE
- $w(x,t) > 0$ PORTATA
- $v(x,t) > 0$ VELOCITA'
- $p(x,t)$ PRESSIONE

- CONSERVAZIONE MASSA (1-DIM)

$$\frac{\partial}{\partial x} w(x,t) = 0$$

$\Rightarrow w(t)$ NON DIPENDE DA X

$v(t) = \frac{w(t)}{\rho A}$ NON DIPENDE DA X

- CONSERVAZIONE Q. DI MOTO (1-DIM)

$$\frac{\partial}{\partial t} w(t) = - \frac{\partial}{\partial x} \left(\rho A \dot{w}^2(t) \right) - A \frac{\partial p(x,t)}{\partial x} - \frac{1}{2} \rho A \dot{w}^2(t) \pi D - \rho A g \frac{dz(x)}{dx} = 0$$

TERMINI DI FINE

$$-\frac{1}{2} c_p \rho v^2(t) \pi D = -\frac{1}{2} c_f \rho \frac{w^2(t)}{g^2 \Omega^2} \pi D = -\bar{F} w^2(t)$$

$$\bar{F} = \frac{1}{2} c_f \frac{\pi D}{g^2 \Omega^2}$$

COEFF. FINE
[kg⁻¹]

CORS. Q. DI MOTO

$$\frac{dw(t)}{dt} = -g \Omega g \left(\frac{1}{g g} \frac{\partial p(x,t)}{\partial x} + \frac{dz(x)}{dx} \right) - \bar{F} w^2(t) =$$

$$= -g \Omega g \frac{\partial}{\partial x} \left(\frac{p(x,t)}{g g} + z(x) \right) - \bar{F} w^2(t)$$

$z^*(x,t)$ **MEZZA DI CARICO**

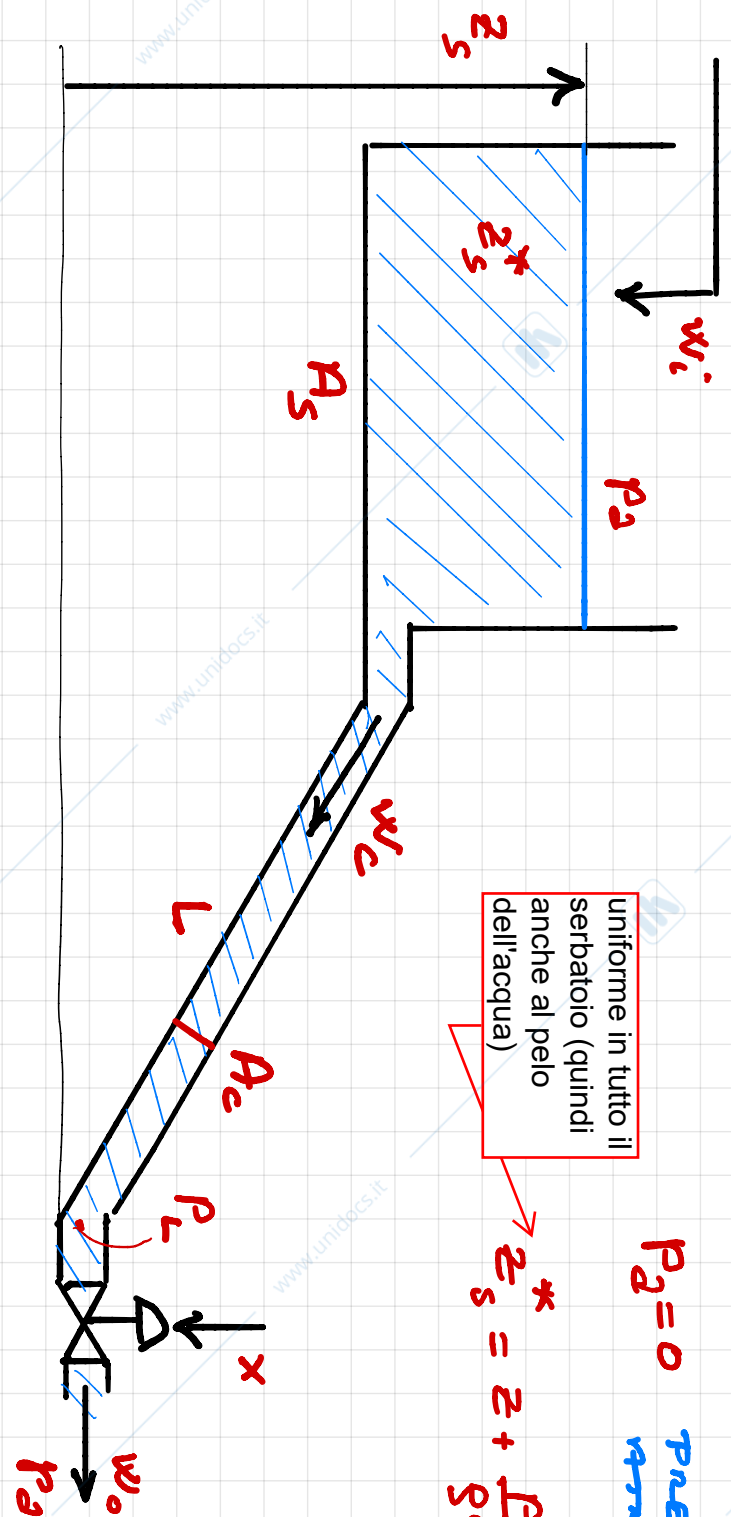
INTEGRANDO DA $x=0$ A $x=L$:

$$\int_0^L \frac{dw(t)}{dt} dx = -g \Omega g \int_0^L \frac{\partial}{\partial x} z^*(x,t) dx - \bar{F} \int_0^L w^2(t) dx$$

$$L \dot{w}(t) = -g \Omega g (z^*(L,t) - z^*(0,t)) - \bar{F} L w^2(t)$$

$$\Rightarrow \dot{w}(t) = -\frac{g \Omega g}{L} (z^*(L,t) - z^*(0,t)) - \bar{F} w^2(t)$$

Commo di un Processo Serbatoio - Condotta - Valvola



uniforme in tutto il serbatoio (quindi anche al pelo dell'acqua)

$p_2 = 0$ **PRESIONE ATMOSFERICA**

$z_s^* = z + \frac{p_v}{\rho g} = z_s$

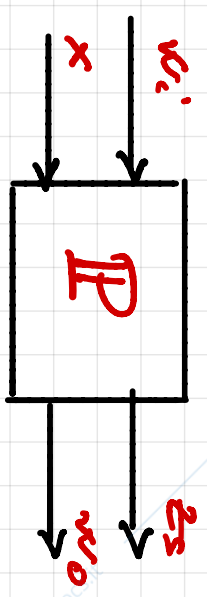
AL PELLO DEL SERBATOIO

considero la pressione $p_a = 0$ al pelo dell'acqua

PROBLEMA

Commo di un Processo Serbatoio - Condotta - Valvola

ADRIANTE w_i, x



- MODELLO

- SENSATIONE (MASSA)

$$\dot{z}_s^*(t) = \dot{z}_s(t) = \frac{1}{gA_s} (w_i(t) - w_c(t))$$

$$z_{s(0,t)}^* = z_s^*(t) = z_s(t)$$

- CONDOTTA (MASSA)

$$w_c(t) = w_o(t)$$

- CONDOTTA (R.DI MOTO)

$$\dot{w}_o(t) = -\frac{gA_e g}{L} (z^*(L,t) - z^*(0,t)) - \bar{f} w_o^2(t)$$

$$z^*(L,t) = \frac{p(L,t)}{g}$$

- VAVOLA (CURVATURE)

$$w_o(t) = k A_v x(t) \sqrt{g(p(L,t) - 0)} =$$

$$p(L,t) = \frac{w_o^2(t)}{k^2 A_v^2 g x^2(t)}$$

$$\Rightarrow \dot{w}_o(t) = \frac{gA_e g}{L} z_s(t) - \left(\frac{k A_e}{L k^2 A_v^2 g x^2(t)} + \bar{f} \right) w_o^2(t)$$

- MODELLO

SIST. DINAMICO MIMO 2x2
NON LINEARE
PROPRIETÀ n=2

$$\dot{z}_s(t) = \frac{1}{gA_s} (w_i(t) - w_o(t))$$

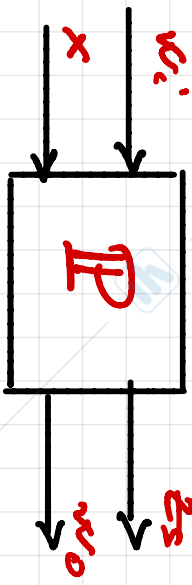
$$w_o(t) = \frac{gA_e g}{L} z_s(t) - \left(\frac{R_e}{Lk^2 A_v^2 g x^2(t)} + \bar{f} \right) w_o^2(t)$$

$$y(t) = \begin{bmatrix} z_s(t) \\ w_o(t) \end{bmatrix}$$

USCITA

$$v(t) = \begin{bmatrix} w_i(t) \\ x(t) \end{bmatrix}$$

INGRESSO



- Equilibrio

$$\begin{cases} \bar{w}_0 = \bar{w}_i \\ \bar{z}_s = \frac{L}{\rho A_c g} \left(\frac{A_c}{L k^2 A_v^2 g \bar{x}^2} + \bar{p} \right) \bar{w}_0^2 \end{cases}$$

FISSATI \bar{w}_i, \bar{x}
L'EQUILIBRIO È UNICO

- LINEARIZZAZIONE

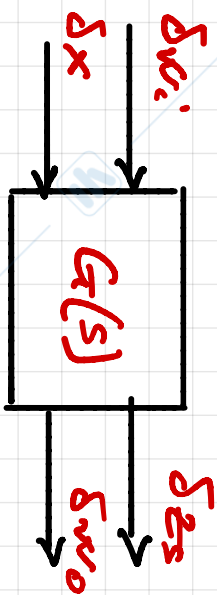
$$\begin{cases} \delta z_s(t) = -\frac{1}{\rho A_s} \delta w_0(t) + \frac{1}{\rho A_s} \delta w_i(t) \\ \delta \dot{w}_0(t) = \frac{\rho A_c g}{L} \delta z_s(t) - 2 \bar{w}_0 \left(\frac{A_c}{L k^2 A_v^2 g \bar{x}^2} + \bar{p} \right) \delta w_0(t) + \frac{2 A_c \bar{w}_0^2}{L k^2 A_v^2 g \bar{x}^3} \delta x(t) \end{cases}$$

β_1 β_2 β_3

$$\begin{cases} \delta z_s(t) = -\alpha \delta w_0(t) + \alpha \delta w_i(t) \\ \delta \dot{w}_0(t) = \beta_1 \delta z_s(t) - \beta_2 \delta w_0(t) + \beta_3 \delta x(t) \end{cases}$$

- MODELLO LINEARIZZATO

$$\begin{cases} \dot{\delta z}_s(t) = -\alpha \delta w_0(t) + \alpha \delta w_1(t) \\ \delta \dot{w}_0(t) = \beta_1 \delta z_s(t) - \beta_2 \delta w_0(t) + \beta_3 \delta x(t) \end{cases}$$



$$A = \begin{bmatrix} 0 & -\alpha \\ \beta_1 & -\beta_2 \end{bmatrix} \quad B = \begin{bmatrix} \alpha & 0 \\ 0 & \beta_3 \end{bmatrix} \quad C = I$$

- MATRICE DI TRASFERIMENTO

$$G(s) = C(sI - A)^{-1}B = \frac{1}{\underbrace{s^2 + \beta_2 s + \alpha \beta_1}_{\varphi(s)}} \begin{bmatrix} \alpha(s + \beta_2) & -\alpha \beta_3 \\ \alpha \beta_1 & \beta_3 s \end{bmatrix} =$$

$$= \begin{bmatrix} G_{zw}(s) & G_{zx}(s) \\ G_{ww}(s) & G_{wx}(s) \end{bmatrix}$$

- CORNICO DECOMPOSTO - Scena Accoppiamenti con RGA

$$G(\theta) = \begin{bmatrix} \mu_{zw} & \mu_{zx} \\ \mu_{ww} & 0 \end{bmatrix} = \begin{bmatrix} \beta_2/\beta_1 & -\beta_3/\beta_1 \\ 1 & 0 \end{bmatrix}$$

$$\lambda = \frac{0}{-\mu_{ww} \mu_{zx}} = 0 \implies \text{MIGLIORI ACCOPPIAMENTI} \\ \{x, z_s\}, \{w_i, w_o\}$$

- Esempio Numero

- DATI

$$A_s = 8 \text{ [m}^2\text{]}$$

$$A_c = 0.15 \text{ [m}^2\text{]}$$

$$L = 15 \text{ [m]}$$

$$\bar{P} = 1.24 \cdot 10^{-6} \text{ [kg}^{-1}\text{]}$$

$$A_v = 35 \cdot 10^{-4} \text{ [m}^2\text{]} \quad k = 4$$

$$\rho = 1000 \text{ [kg/m}^3\text{]} \quad g = 9.8 \text{ [m/s}^2\text{]}$$

$$C_p \approx 0.0035$$

- EQUILIBRIO

$$\bar{W}_i = \bar{W}_0 = 70 \text{ [kg/s]}$$

$$\bar{z}_s = 10 \text{ [m]}$$

$$\bar{x} = 0.5048$$

- PARAMETRI MODELLO UNDETERMINATO

$$\alpha = 1.25 \cdot 10^{-4}$$

$$\beta_1 = 98.1$$

$$\beta_2 = 28.03$$

$$\beta_3 = 3.887 \cdot 10^3$$

$$CP(s) = s^2 + \beta_2 s + \alpha \beta_1 = s^2 + 28.035 s + 0.0123$$

POLINOMIO CARATTERISTICO

AUTONUMI

$$s_1 = -4 \cdot 10^{-4}$$

$$s_2 = -28.03$$

COSTANTI DI TEMPO

$$\tau_1 = 2286$$

$$\tau_2 = 0.0357$$

← DENUMI

FDT

$$G_{zw}(s) = \frac{\alpha(s + \beta_2)}{\varphi(s)} = \frac{\mu_{zw}(1 + sT)}{(1 + s\tau_1)(1 + s\tau_2)} \sim \frac{\mu_{zw}}{1 + s\tau_1}$$

$T \approx \tau_2$
 $\mu_{zw} = \frac{\beta_2}{\beta_1} \approx 0.28$

$$G_{zx}(s) = \frac{-\alpha\beta_3}{\varphi(s)} = \frac{\mu_{zx}}{(1 + s\tau_1)(1 + s\tau_2)}$$

$\mu_{zx} = -\frac{\beta_3}{\beta_1} \approx -39.62$

$$G_{ww}(s) = \frac{\alpha\beta_1}{\varphi(s)} = \frac{\mu_{ww}}{(1 + s\tau_1)(1 + s\tau_2)}$$

$\mu_{ww} = 1$

$$G_{wx}(s) = \frac{\beta_3 s}{\varphi(s)} = \frac{\mu_{wx} s}{(1 + s\tau_1)(1 + s\tau_2)}$$

$\mu_{wx} = \frac{\beta_3}{\alpha\beta_1} \approx 3.2 \cdot 10^5$

- SPECIFICHE DI PROBLEMA

(a) $e(\infty) = 0$

(b) $\omega_c \approx 0.002$

(c) $\varphi_m > 75^\circ$

]

\Rightarrow

$T_d \approx 2500$