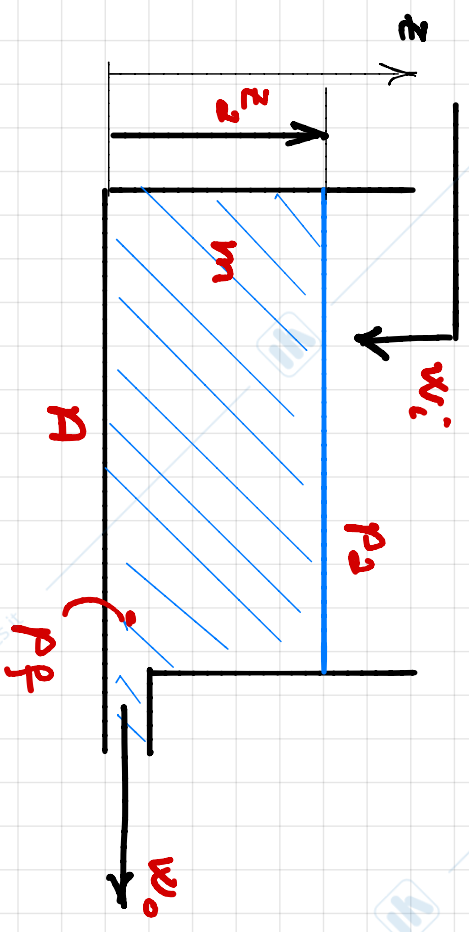


---

# MODELLI DI COMPONENTI IDRAULICI

# - SERBATOIO

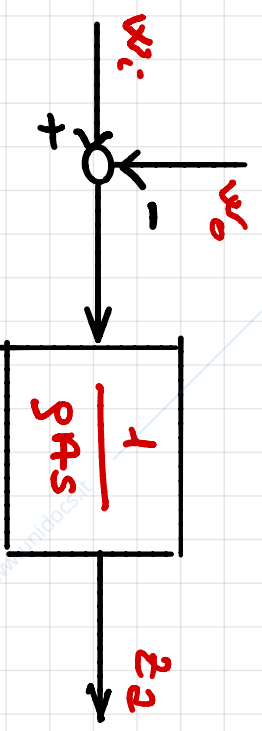


$$m = \rho A z$$

MASSA

- CONSERVAZIONE MASSA  $\implies$

$$\dot{m} = \rho A \dot{z} = w_i - w_o$$



$\rho = \text{cost.}$  DENSITA'  
 $v_z \approx 0$  VELOCITA' UNGUO Z  
 SOLO FENOMENI DI ACCUMULO

MODELLO 0-DIM

$$\dot{z}_2 = \frac{1}{\rho A} (w_i - w_o)$$

SISTEMA DINAMICO  
 LINEARE

- CALCOLO DI  $p_p$

BERNOULLI  $\Rightarrow$   $\frac{p(z)}{\rho} + \frac{1}{2}v^2(z) + gz = \text{cost.}$  LEGGE DI STEVINO

$\frac{p_2}{\rho} + gz_2 = \frac{p_1}{\rho} \Rightarrow p_p = p_2 + \rho gz_2$

IN SUPERFICIE SUL FONDO

- ALTEZZA DI CARICO (HEAD)

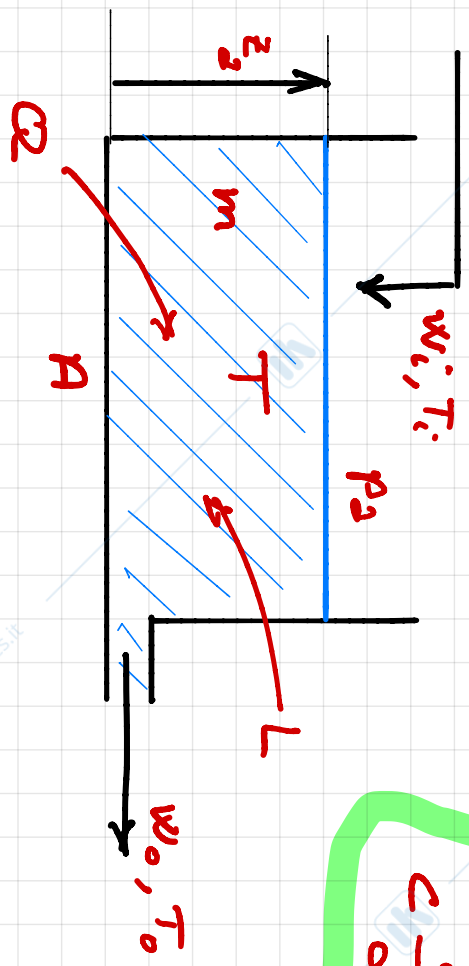
$z^* = z + \frac{p(z)}{\rho g} = \text{cost.} = z_2 + \frac{p_2}{\rho g}$  [m] IN OGNI PUNTO DELLA SEGAZIONE  $z^*$  È COSTANTE

ALTEZZA DI CARICO

- NOTA:  $z^* = z_2 \Rightarrow$

$z^* = \frac{1}{\rho g} (\rho v_1^2 - \rho v_0^2)$  CONS. MASSA

- CONSERVAZIONE ENERGIA



$$c \frac{d}{dt} (mT) = \Phi + \Psi + w_i c T_i - w_o c T_o$$

$$m = \rho A z_2$$

$$\frac{1}{\rho A} (w_i - w_o) \text{ CONS. MASSA}$$

$$c \frac{d}{dt} (mT) = c \rho A \frac{d}{dt} (z_2 T) = c \rho A (\dot{z}_2 T + z_2 \dot{T})$$

$$\Rightarrow c \rho A z_2 \dot{T} = - \frac{c \rho A}{\rho A} T (w_i - w_o) + \Phi + \Psi + w_i c T_i - w_o c T_o =$$

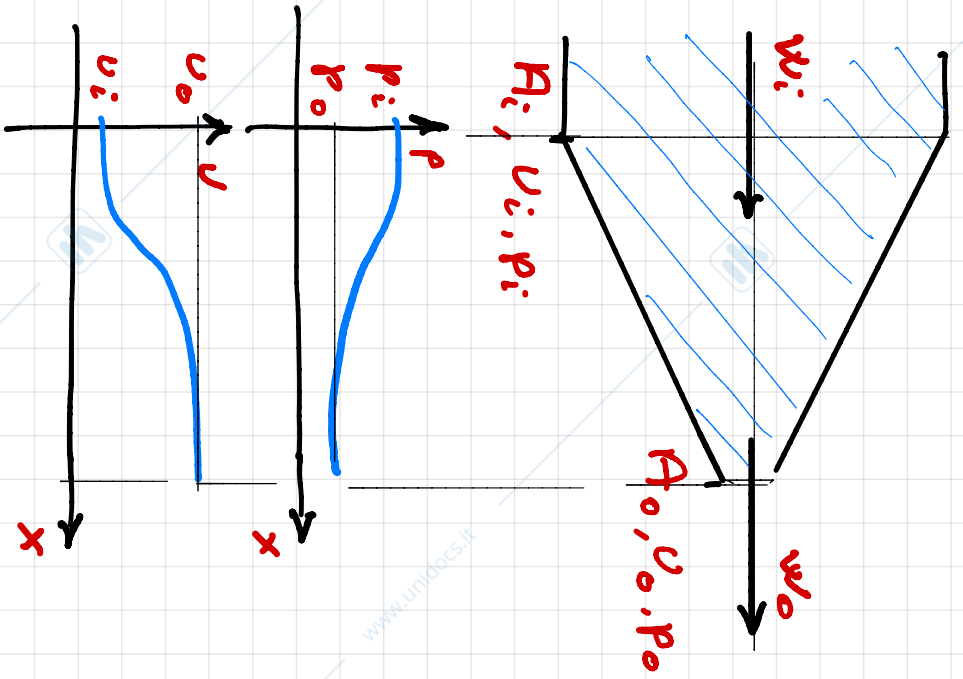
$$= c w_i (T_i - T) - c w_o (T_o - T) + \Phi + \Psi$$

NO SE LIQUIDO BEN MISCELATO

$$\dot{T} = \frac{1}{c \rho A z_2} (c w_i (T_i - T) + \Phi + \Psi)$$

SISTEMA DINAMICO NON LINEARE

# - Velocità



## - COMPONENTE USATA PER

- RIDURRE PRESSIONE
- AUMENTARE VELOCITÀ

## - IPOTESI

- ACCUMULO MASCONABILE  $w_i = w_0$
- PICCOLE DIMENSIONI  $z_i = z_0$
- ATTUO MASCONABILE

- MODELLO (NOU DYNAMIC)

BEHAVIOR

$$p_i + \frac{1}{2} u_i^2 + g z_i = \frac{p_0}{\rho} + \frac{1}{2} u_0^2 + g z_0$$

$$u_0^2 - u_i^2 = \frac{2}{\rho} (p_i - p_0)$$

$$w_i = \rho A_i u_i = \rho A_0 u_0 = w_0 \implies \frac{u_i}{u_0} = \frac{A_0}{A_i} = \alpha < 1$$

$$u_0^2 - u_i^2 = (1 - \alpha^2) u_0^2$$

$$u_0 = \sqrt{\frac{1}{1 - \alpha^2} \cdot \frac{2}{\rho} (p_i - p_0)}$$

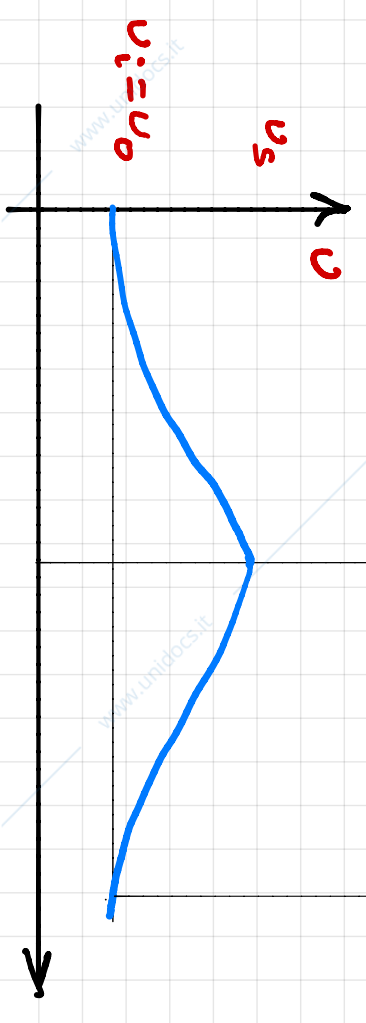
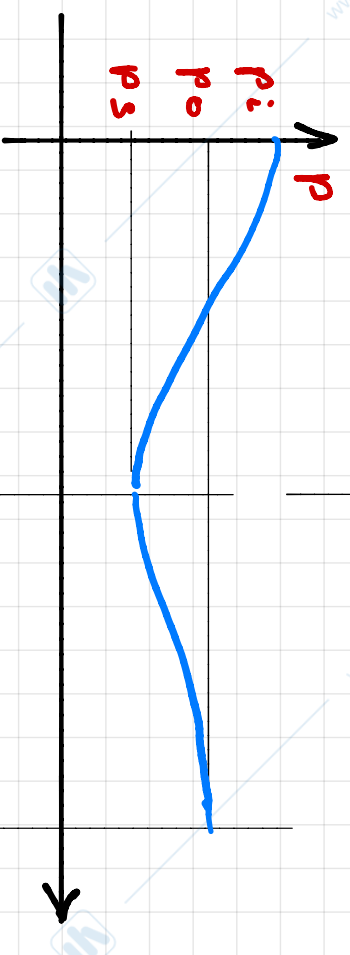
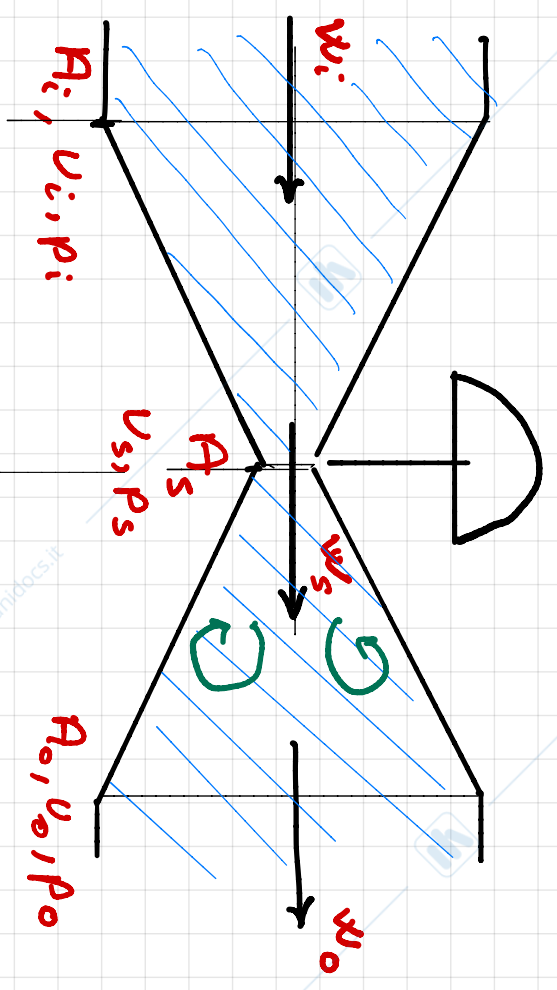
$$w = w_0 = \rho A_0 u_0 = \rho A_0 k_v \sqrt{\frac{2}{\rho} (p_i - p_0)} = \sqrt{\rho} A_0 k_v \sqrt{2 (p_i - p_0)}$$

- **NOTA**: SE NEGOTIABILE,  $A_0$  PUO' ESSERE

VARIATA PER MODIFICARE  $w$

MODELLO STATICO  
NON USARE

**Varvola**



COMPONENTE USATO PER  
REGOLARE LA PORTATA  
(DISSIPANDO ED. CINETICA)

1. POTESI  
- ACCUMULO MASCONABILE  
 $W_i = W_s = W_o$   
- MASCONABILI EFFETTI  
DI CAVITAZIONE  
(BOLE DI VAPORE)

- Modello (non Dinamico)

. SEZIONE CONVERGENTE (VEDI UGROSS)

$$w_s = \rho A_s v_s = \sqrt{2\rho} A_s k_s \sqrt{p_i - p_o}$$

. SEZIONE DIVERGENTE

$$C_r = \sqrt{\frac{p_i - p_o}{p_i - p_s}}$$

COEFFICIENTE DI RECUPERO

$$0 < C_r < 1$$

$$\sqrt{p_i - p_s} = \frac{1}{C_r} \sqrt{p_i - p_o} \implies w_o = w_s = \sqrt{2\rho} A_s k_s \frac{1}{C_r} \sqrt{p_i - p_o}$$

- POUENDO

APPARURA MASSIMA

POSIZIONE STESSA

$$A_s k_s = A_v \eta(x)$$

$$k = \frac{\sqrt{2}}{C_r}$$

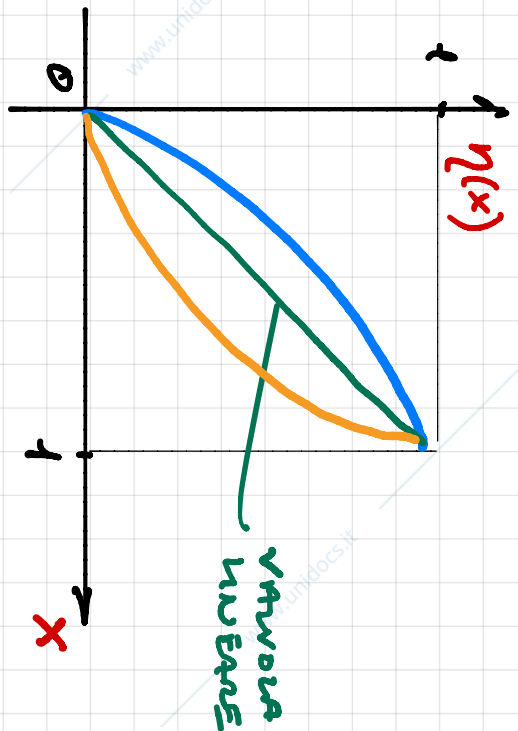
(ADIMENSIONALE)

$x \in [0,1]$

CARATTERISTICA VARIABILE  $\eta \in [0,1]$

$$w_o = k A_v \eta(x) \sqrt{\rho (p_i - p_o)}$$

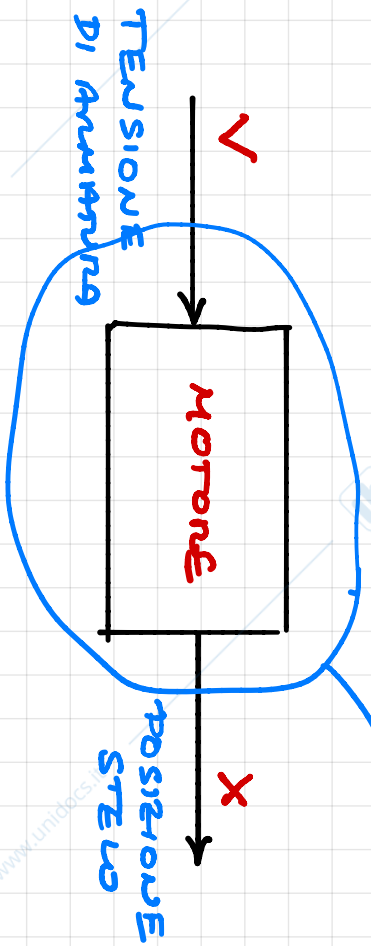
MODELLO STATICO NON LINEARE



VARIABILE LINEARE

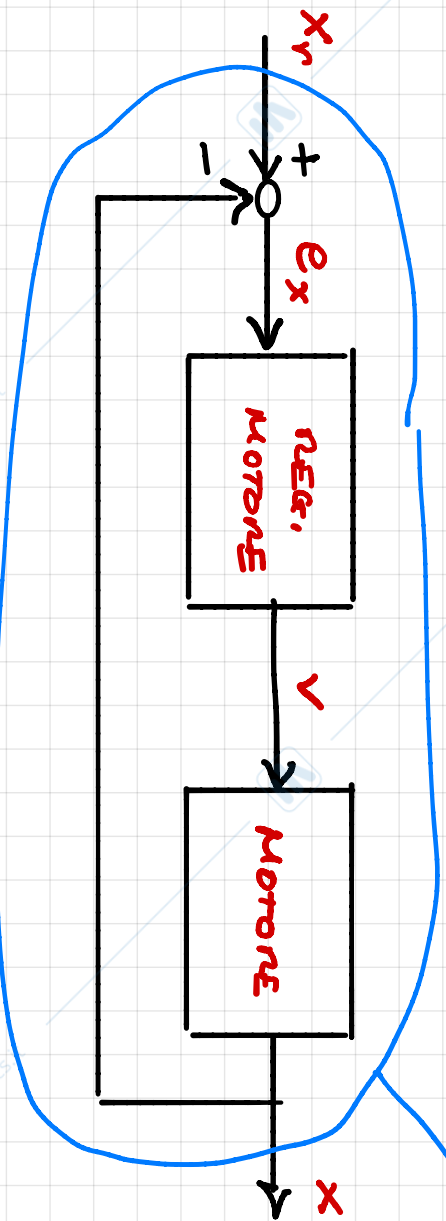
# Azionario Valvola

- In Aereo Aperto



$A(s)$

- In Aereo Chiuso (SERVOMOTORE)

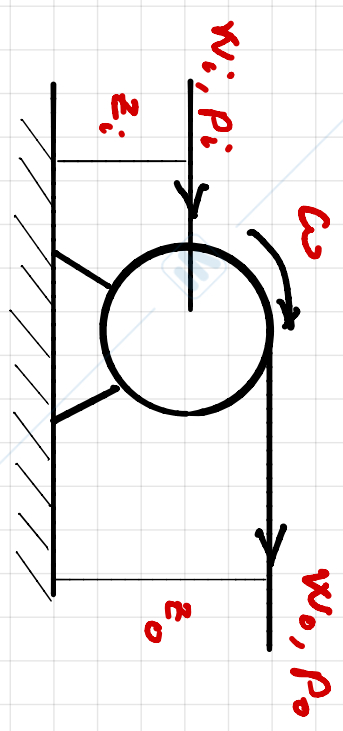


$$M(s) \approx \frac{1}{1 + s\tau_m}$$

$$\tau_m = \frac{1}{\omega_{cm}}$$

BANDA SIST. COMPLESSO MOTORE

- POMPA



ω VELOCITÀ DI ROTAZIONE [rpm]

- PRESSIONE (HEAD)

$$H = \frac{p_o - p_i}{\rho g} + \frac{z_o - z_i}{g} + \frac{1}{2} \frac{w_o^2 - w_i^2}{g}$$

PRESSIONE POTENZIALE CINETICA

- MODELLO (NON DINAMICO)

$$H = \alpha \omega^2 - \beta w^2$$

MODELLO STATICO  
NON DINAMICO

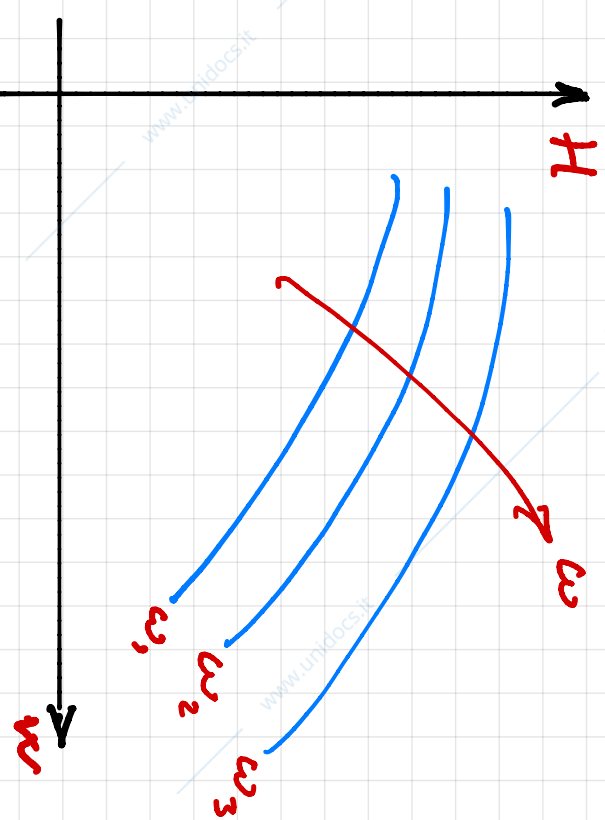
$\alpha > 0$   
 $\beta > 0$

- COMPONENTE USATO PER  
- TRASFORMARE ENERGIA CINETICA  
IN AUMENTO DI PRESSIONE

- IPOTESI  
- ACCUMULO TRASCURABILE  
 $w_i = w_o = w$   
- PICCOLE DIMENSIONI  $z_i \approx z_o$

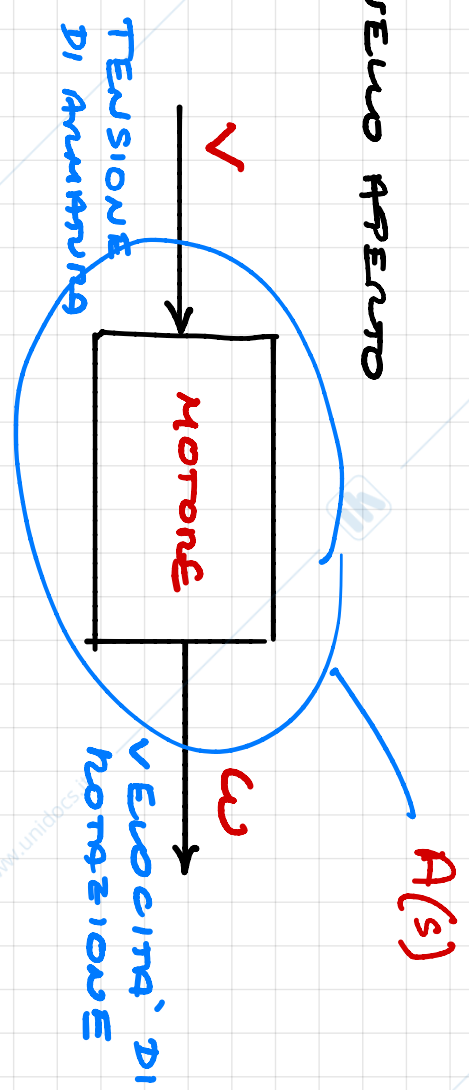
$\approx 0$  SE  $A_o \approx A_i$

[m]

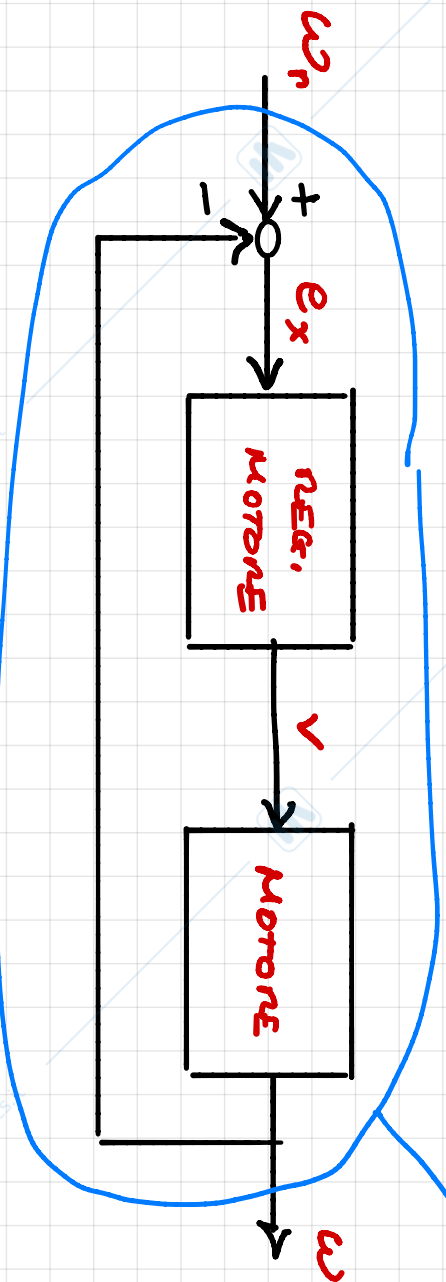


# Азонаменто Ронпа

- IN RUOLO APERTO



- IN RUOLO CHIUSO (SERVOCONTROLLO)



$$M(s) \approx \frac{1}{1 + s\tau_m}$$

$$\tau_m = \frac{1}{\omega_{cm}}$$

BANDA SIST. CONTROLLO MOTORE