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Control Trainer Setup
Section 5.1 explains how to setup the DCMCT module on the ELVIS unit and properly initialize the system. The LabView controllers associated with the DCMCT QNET module are overviewed in Section 5.2. 5.1. ELVIS and DCMCT Module Setup Procedure

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**DC Motor Control
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DCMCT Speed Control
Laboratory Manual
Figure 1 DCMCT
Components 3.2.
DCMCT Plant
Description The DCMCT
system consists of a

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DC motor equipped with a servo motor driving a disc load. The motor input is a voltage with a range of $\pm 24V$. The motor has an encoder that measures its position, a digital tachometer that measures its speed, and a current ...

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Control Systems Lab Solutions - Quanser

the DCMCT can be used by a team of students; in fact, the prelab assignments and DCMCT

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experiments provide enough material to keep a team of two or three students busy. DCMCT Hardware The DCMCT hardware consists of the board shown in Figure 1. The most evident feature of the QET trainer is the wheel attached to a dc motor with encoder.

**The Quanser DC
Motor Control
Trainer - University**

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Figure 11: NI ELVIS and QNET-DCMCT setup for use with LabVIEW.

Some of the components used in the installation procedure are located and marked by an ID number in Figure 11 and described in the Table 3, below.

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The gray boxes present in the instructor manual are not intended for the students as they provide solutions to the pre-lab assignments and contain typical experimental results from the laboratory procedure. 2.

References [1] NI-ELVIS

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User Manual [2]
DCMCT User Manual
[3] QNET Experiment
#01: DC Motor Speed
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Instrument 6 2.3 Lab 1:
Bump Test [60 min] ...

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5. Use your results to justify neglecting the electrical transient, i.e. assuming $L_m = 0$. Use this assumption to derive a single differential equation for $\dot{\omega}_m$ in terms of ω_m , V_m , and T_d and create

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a second model in Simulink parallel to your first which ignores the electrical transient.
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