

Cahier Réponses - PSI

Question 1 - Bilan des Actions Mécaniques Extérieures :

Théorème ou Principe utilisé, éléments d'application :

Équation d'équilibre :

Question 2

$b m_3 =$

Question 3



$\gamma =$

Question 4

$m_i =$

$m_u =$

$h =$

Intérêt de l'hyperstatisme :

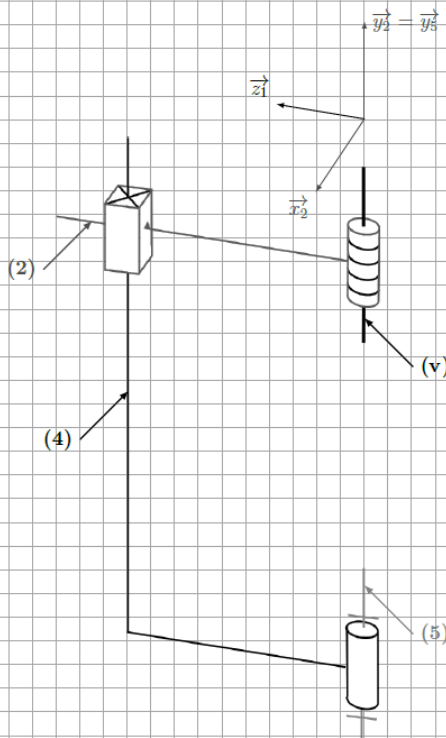
Question 5

Liaison (N)/(5) :

Justification :

Liaison (N)/(v) :

Justification :



Question 6

Défaut	Rattrapage possible par le joint d'Oldham	
<p>Diagram showing a joint d'Oldham with a spring in the \vec{x}_2 direction. The rotation is labeled $\delta\theta_x$. The coordinate systems (\vec{x}_1, \vec{y}_1) and (\vec{x}_2, \vec{y}_2) are shown.</p>	OUI	NON
<p>Diagram showing a joint d'Oldham with a spring in the \vec{z}_1 direction. The displacement is labeled δl_z. The coordinate systems (\vec{x}_1, \vec{y}_1) and (\vec{x}_2, \vec{y}_2) are shown.</p>	OUI	NON
<p>Diagram showing a joint d'Oldham with a spring in the \vec{z}_1 direction. The rotation is labeled $\delta\theta_z$. The coordinate systems (\vec{x}_1, \vec{y}_1) and (\vec{x}_2, \vec{y}_2) are shown.</p>	OUI	NON
<p>Diagram showing a joint d'Oldham with a spring in the \vec{x}_2 direction. The displacement is labeled δl_x. The coordinate systems (\vec{x}_1, \vec{y}_1) and (\vec{x}_2, \vec{y}_2) are shown.</p>	OUI	NON
<p>Diagram showing a joint d'Oldham with a spring in the \vec{y}_2 direction. The displacement is labeled δl_y. The coordinate systems (\vec{x}_1, \vec{y}_1) and (\vec{x}_2, \vec{y}_2) are shown.</p>	OUI	NON

Question 7 Justification $\omega_{4/2} = 0$:

$$k = \frac{\omega_{5/2}}{\omega_{7/2}} =$$

Application numérique :

Question 8

$$k_g = \frac{\omega_{5/2}}{\omega_{m/2}} =$$

Question 9

$d_v =$

Application numérique : $d_v =$

Conclusion vis-à-vis de l'exigence 1.1 :

Question 10

Question 11

Erreur de positionnement :

Conclusion vis-à-vis de l'exigence 1.1 :

Question 12 - Plan de symétrie :

$$\bar{I}_{(O_1, 2+3)} =$$

Question 13

$$\vec{\sigma}_{O_1, (2+3)/R_0} =$$

Question 14 Calcul de $\vec{\sigma}_{O_1, (2+3)/R_0} \cdot \vec{z}_1$:

Grid area for the answer to Question 14.

$$\gamma_{x2}(t) =$$

Question 15

Systeme isolé :

Theoreme utilise :

Justification equation non-lineaire :

Question 16

Grid area for the answer to Question 16.

Question 17

$$\frac{\alpha(p)}{\gamma_{x2}(p)} =$$

Condition de stabilité :

Rôle stabilisateur du ressort :

Question 18

$A =$

$\omega_0 =$

$\xi =$

Question 19

$C_0 =$

Question 20

Plage de valeurs de k :

Question 21

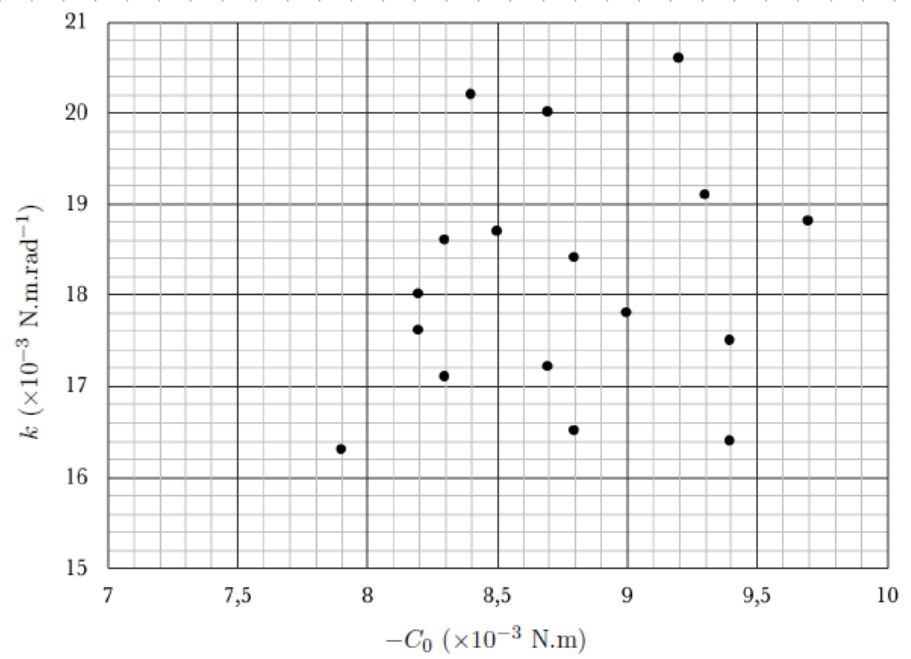


FIGURE A

Question 22

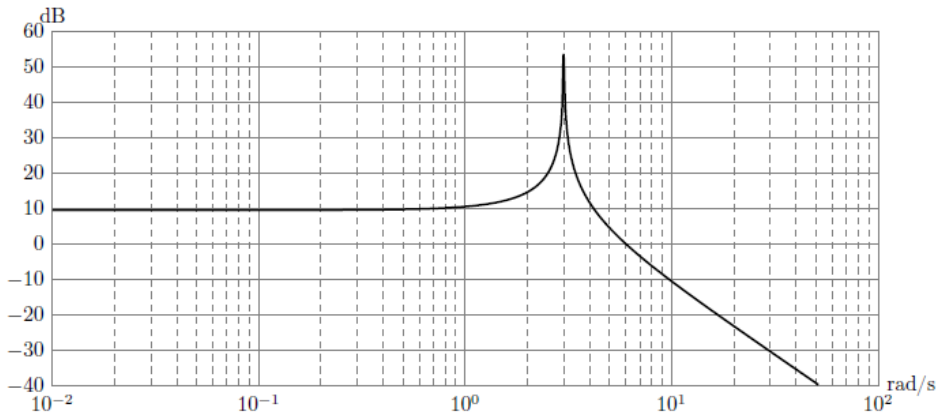


FIGURE B - Diagramme de Bode en gain de $\frac{\alpha(p)}{\gamma_{r2}(p)}$

Conclusion :

Question 23

$$H_{\gamma}(p) =$$

$$K_{HF} =$$

$$a_1 =$$

$$b_1 =$$

$$b_2 =$$

$$b_3 =$$

Question 24 – Justification de la stabilité :

Justification du choix de K_1 :

$K_1 =$

Question 25

$\tau_2 =$

$\tau_3 =$

Question 26 Exigence 3.2 :

Exigence 3.3 :

Question 27 Intérêt de la chaîne d'action BF :

Question 28

$$H_{BO}(p) =$$

$$\tau_4 =$$

Question 29

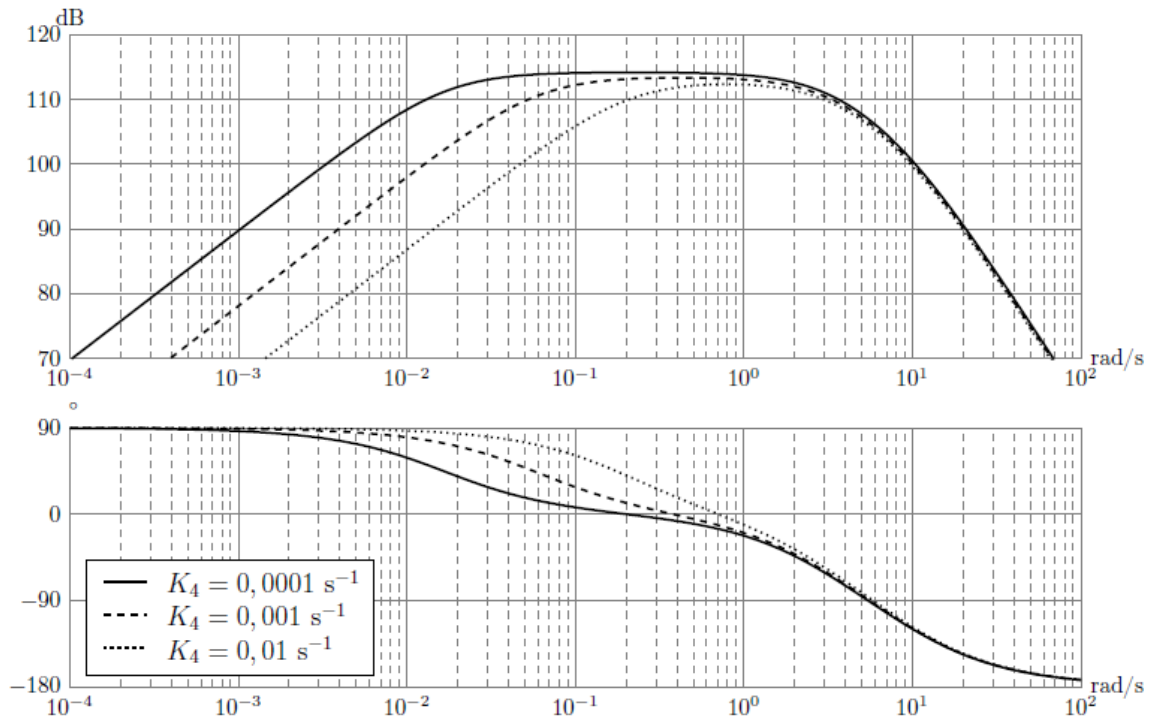


FIGURE C - Diagramme de Bode de l'asservissement en tension $\frac{U(p)}{\gamma_{x2}(p)}$

$K_4 =$

Question 30