

Fig. P5.20

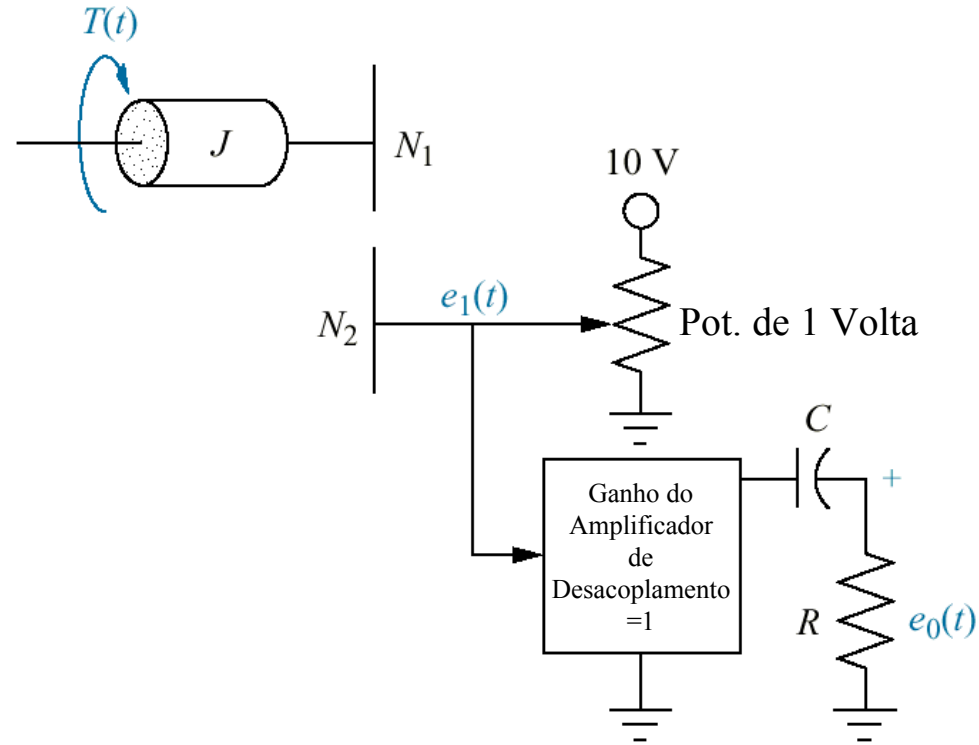


Fig. P5.21

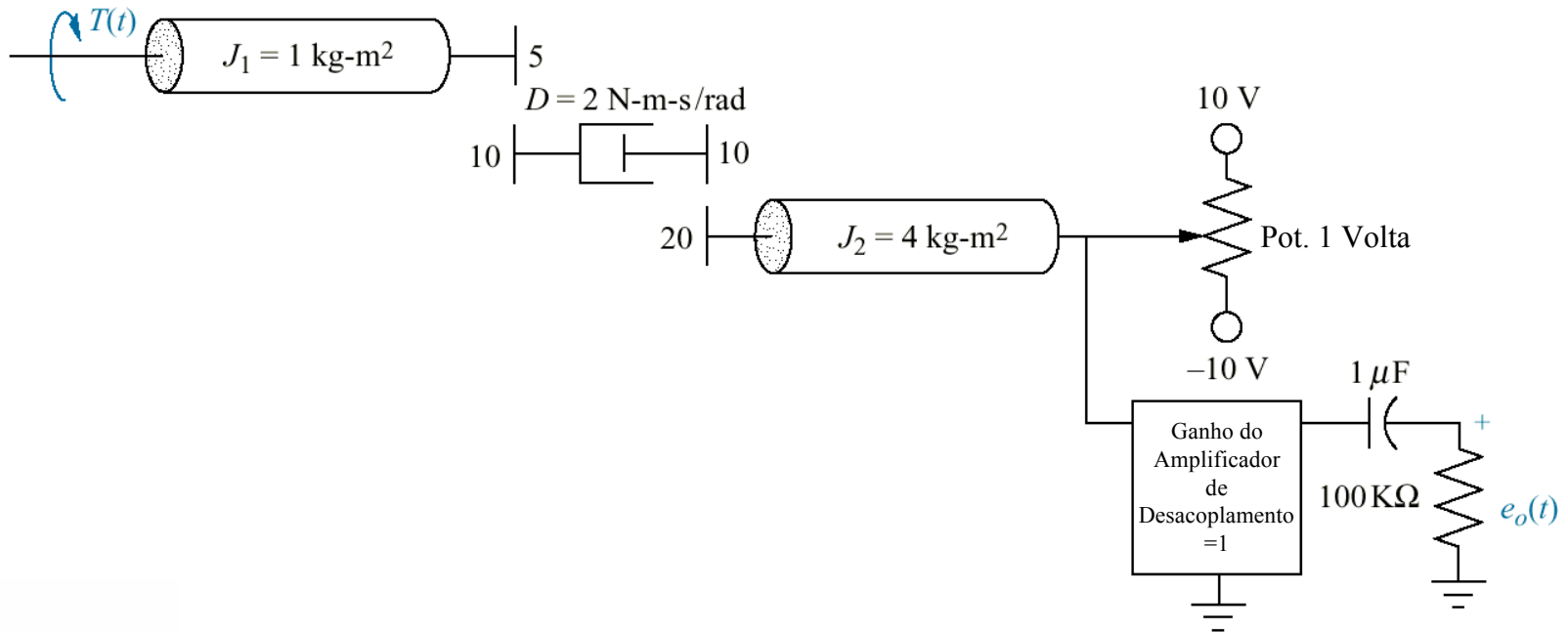


Fig. P5.22

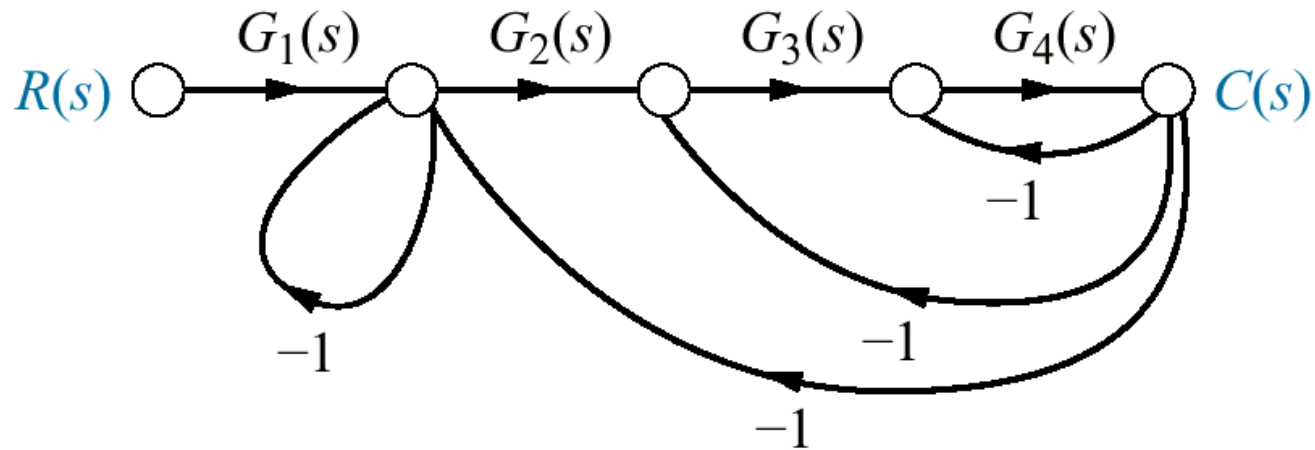


Fig. P5.23

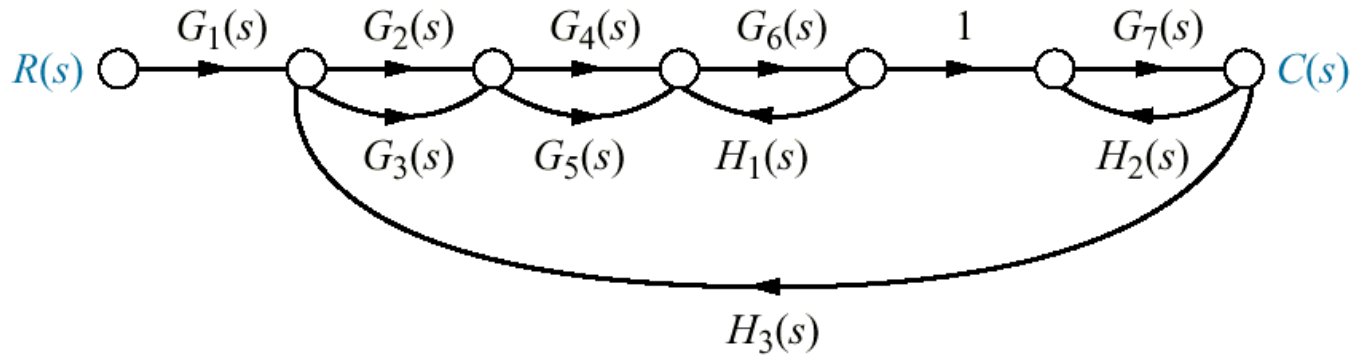


Fig. P5.24
(*Continuação*)

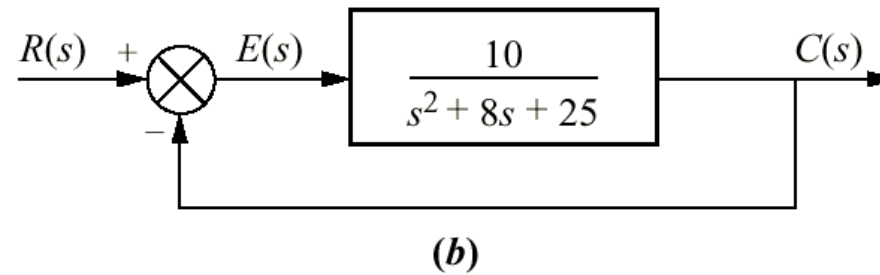
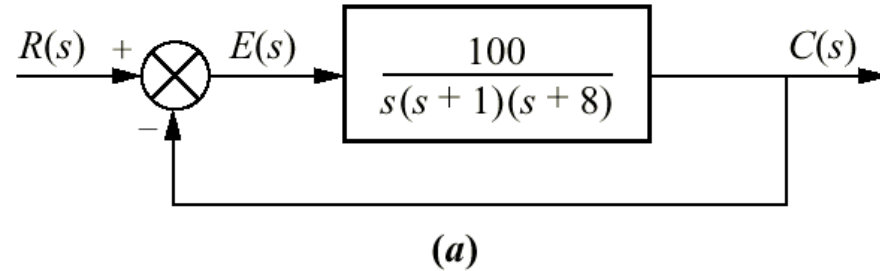
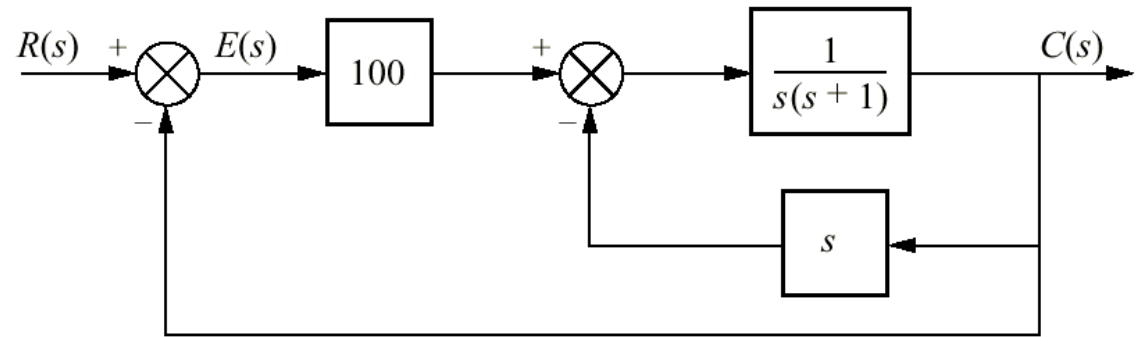
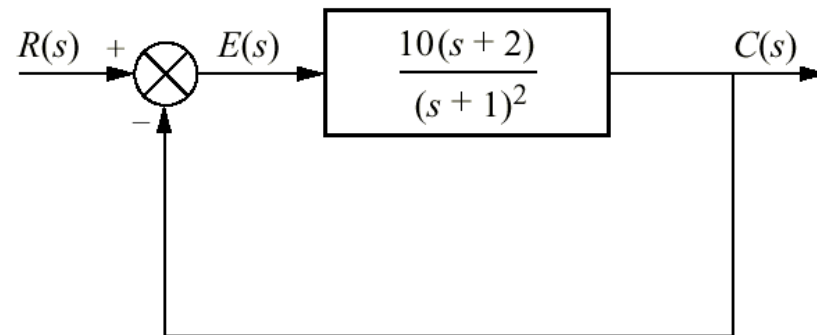


Fig. P5.24
(*Continuação*)



(c)



(d)

Fig. P5.25

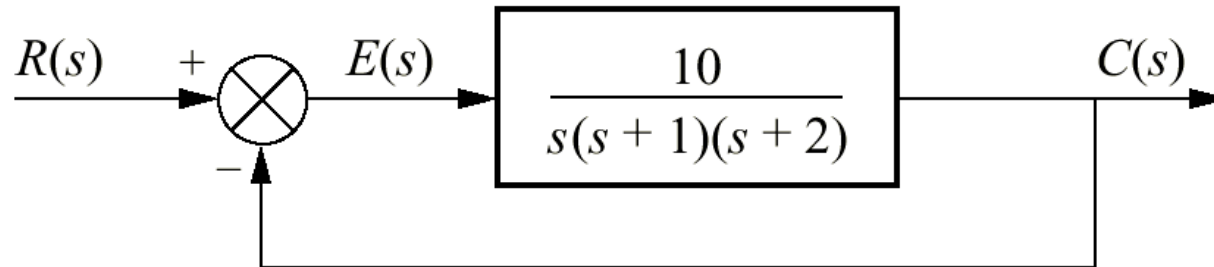


Fig. P5.26

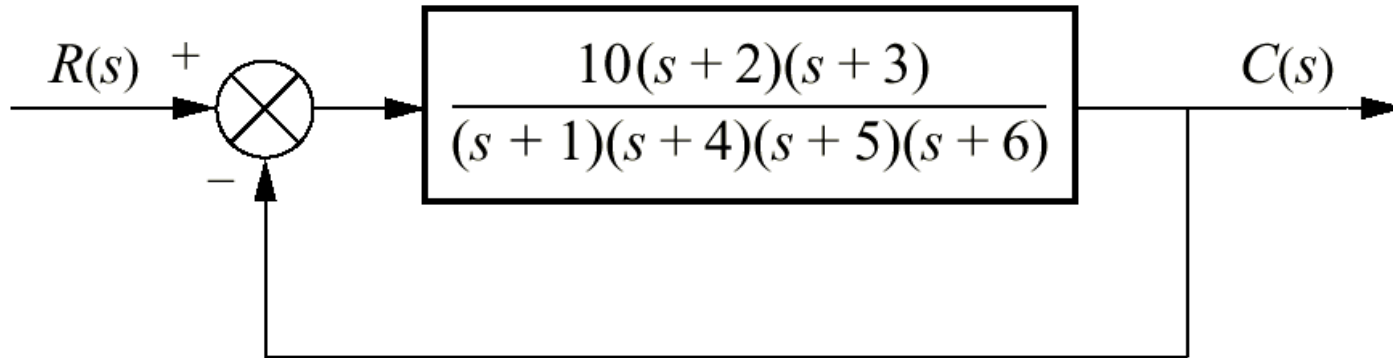


Fig. P5.27

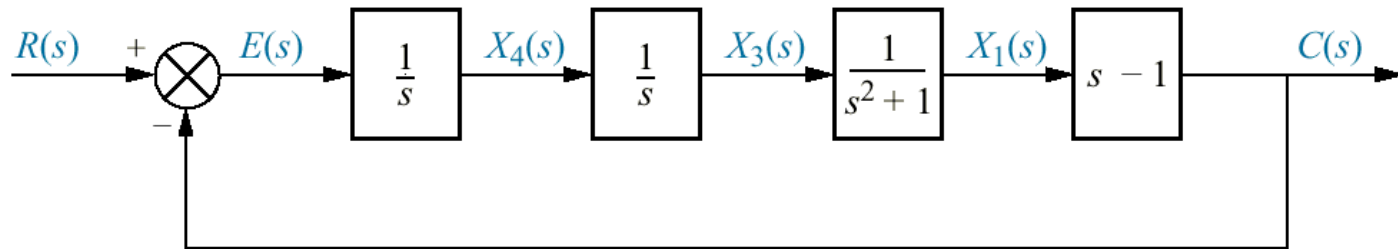


Fig. P5.28

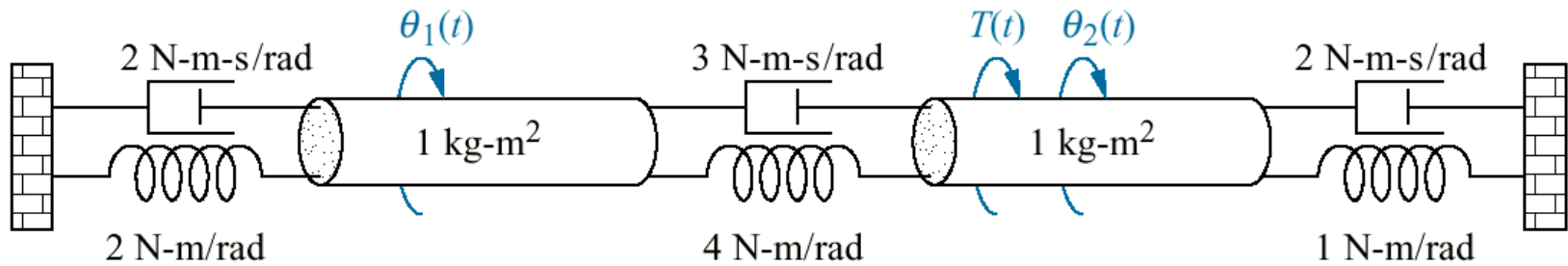


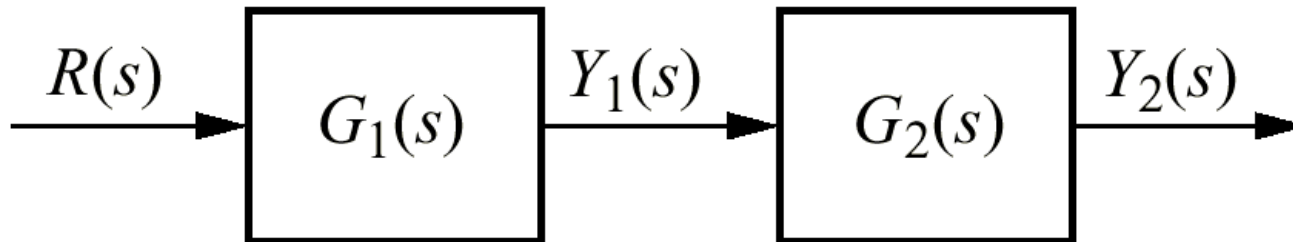
Fig. P5.29

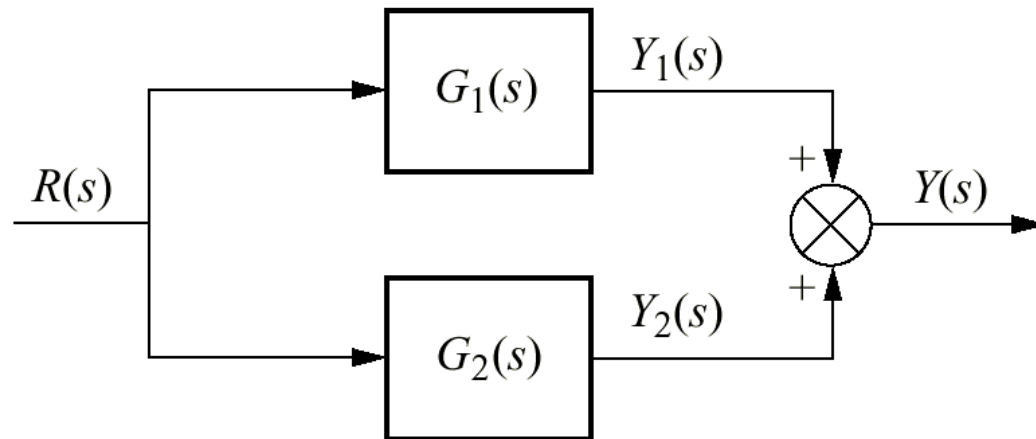
Fig. P5.30

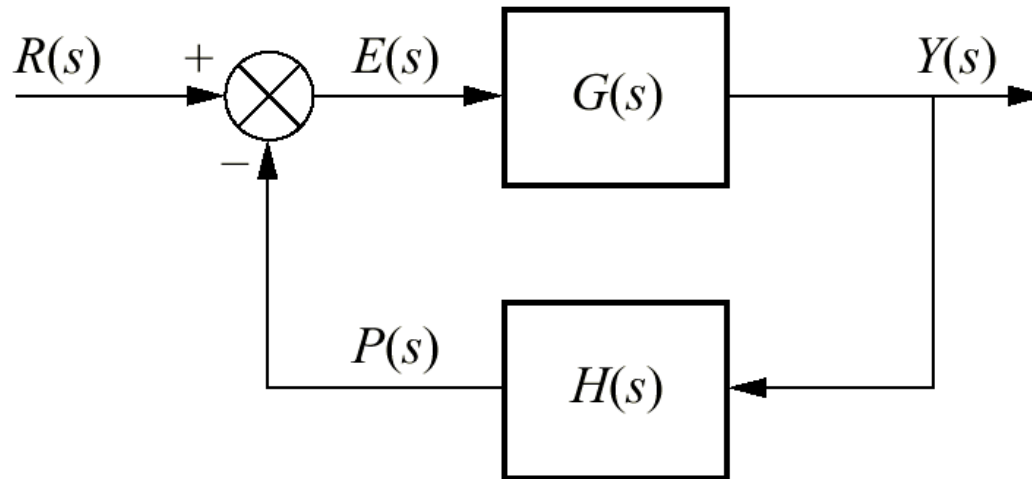
Fig. P5.31

Fig. P5.32
 Sistema de controle de arfagem do ônibus espacial (simplificado)

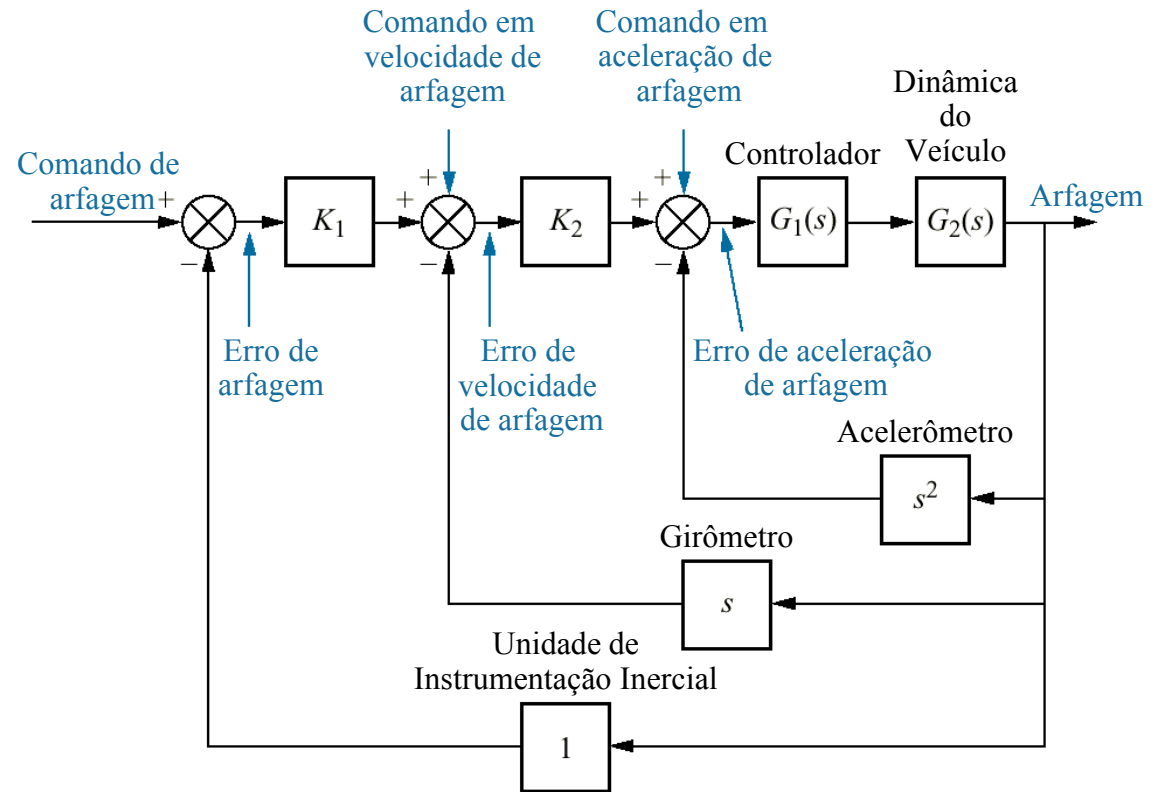


Fig. P5.33

Modulador em AM

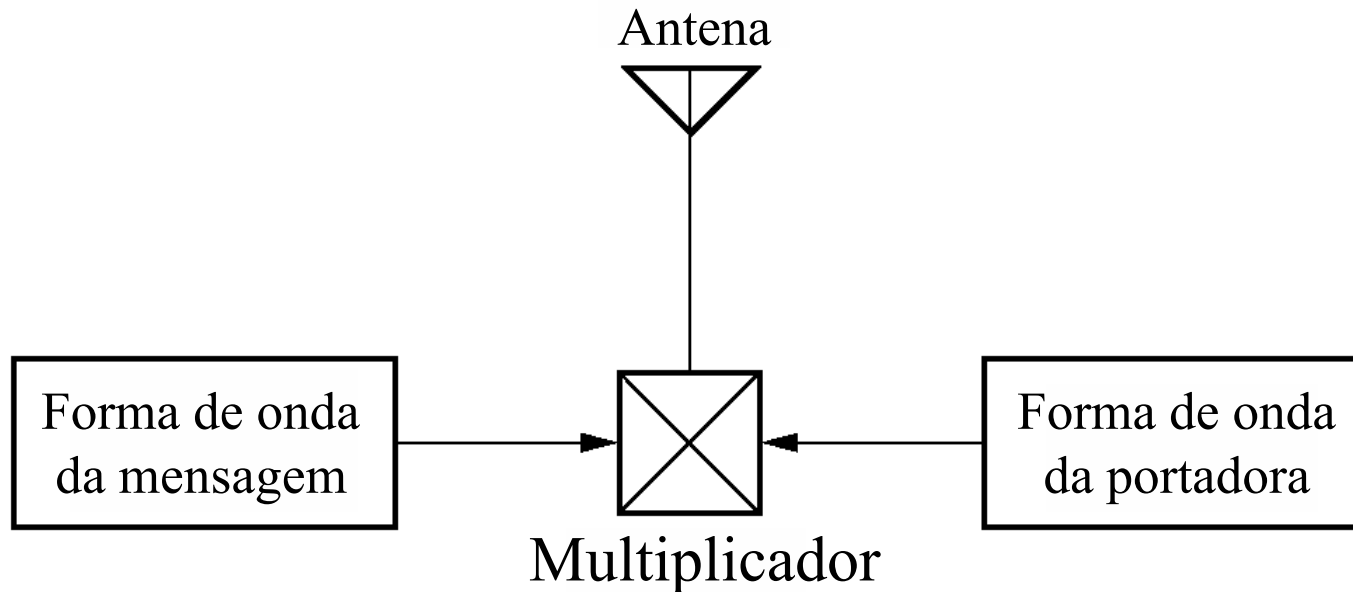


Fig. P5.34

Sistema de controle com retroação representando o movimento do olho humano

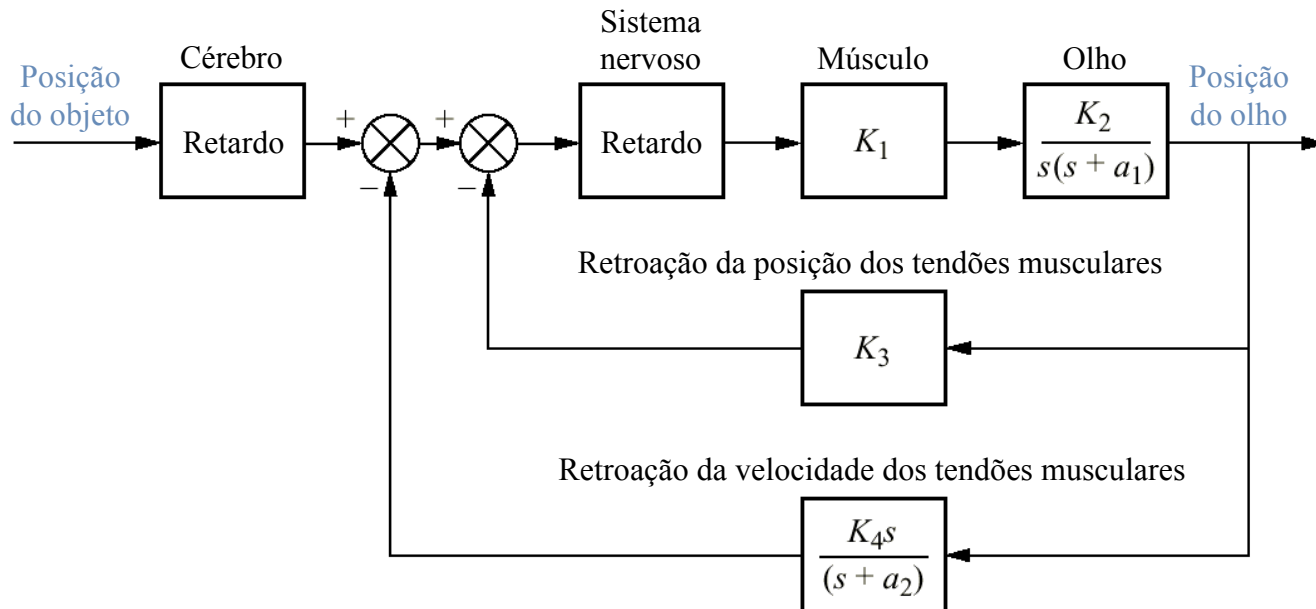


Fig. P5.35

- a. Robô assistente usado para serviço de entrega em hospitais;
- b. diagramas de blocos simplificado para o controle do ângulo de rumo



Cortesia de Hank Morgan/Rainbow/PNI.

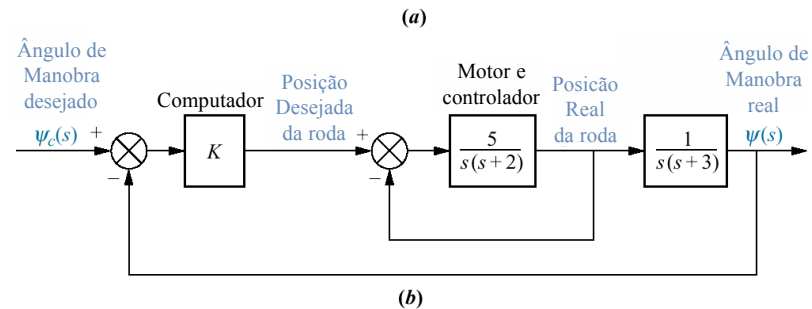


Fig. P5.36

a. Máquina de ensaio de carga (© 1992 IEEE);
 b. diagrama de blocos aproximado

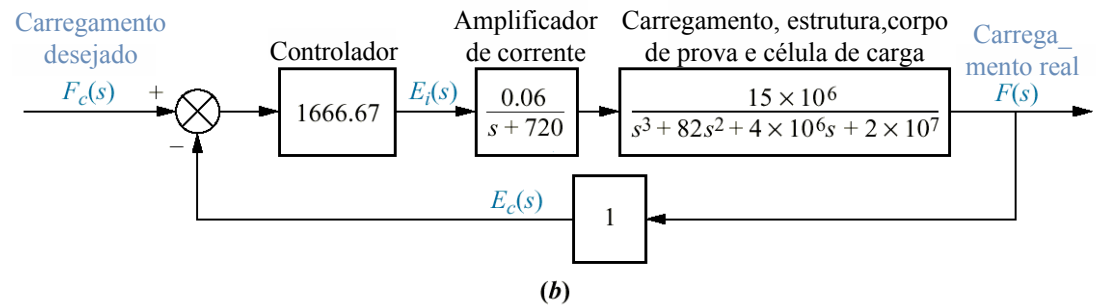
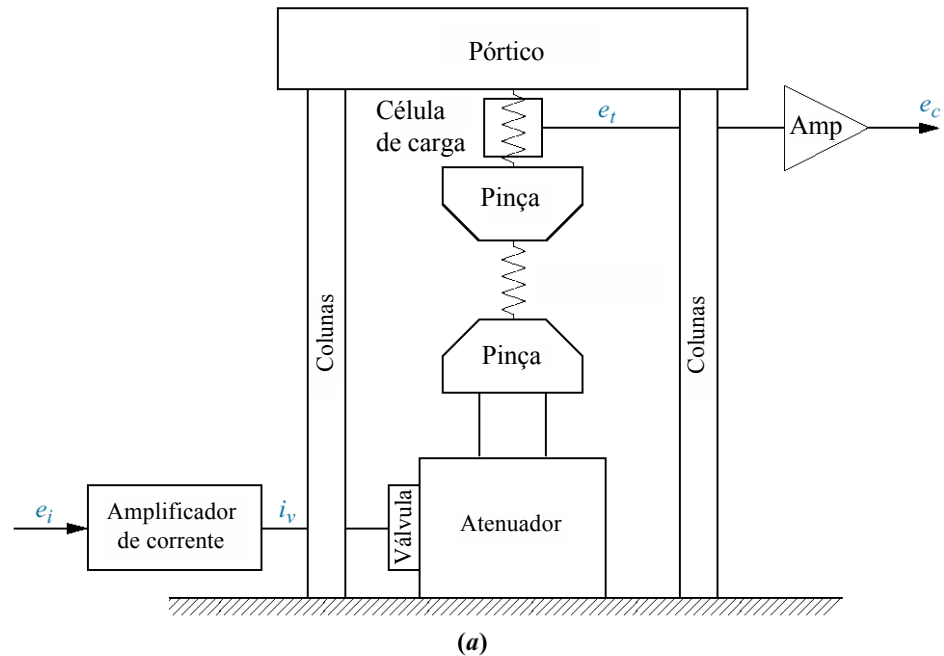


Fig. P5.37

Circuito de bobina de um solenóide

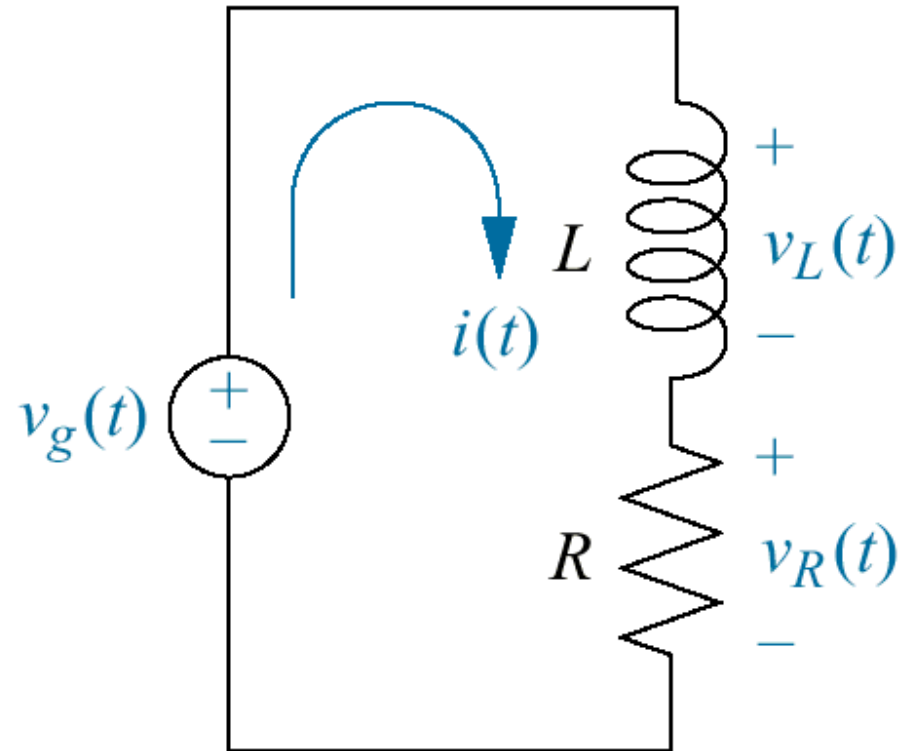


Fig. P5.38

Controle de posição:

a. motor e carga

b. diagrama de blocos

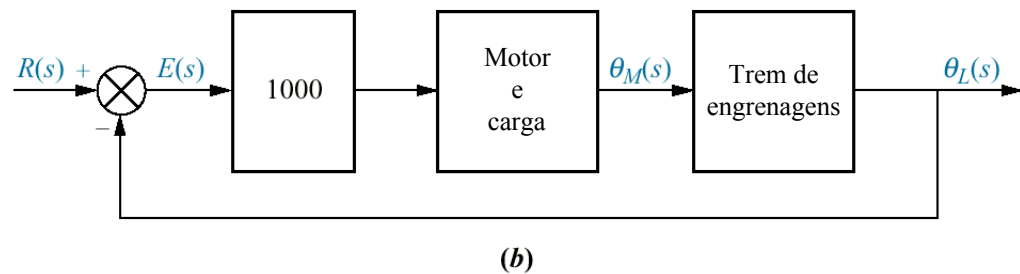
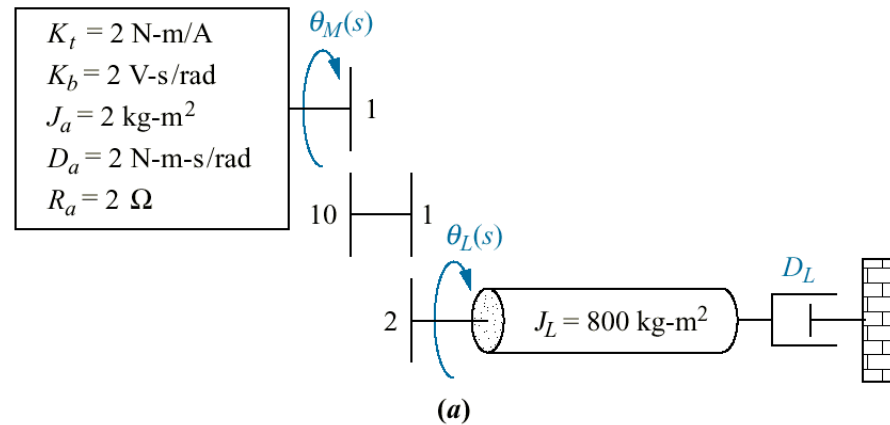


Fig. P5.39
a. Controle de posição;
b. controle de posição com tacômetro

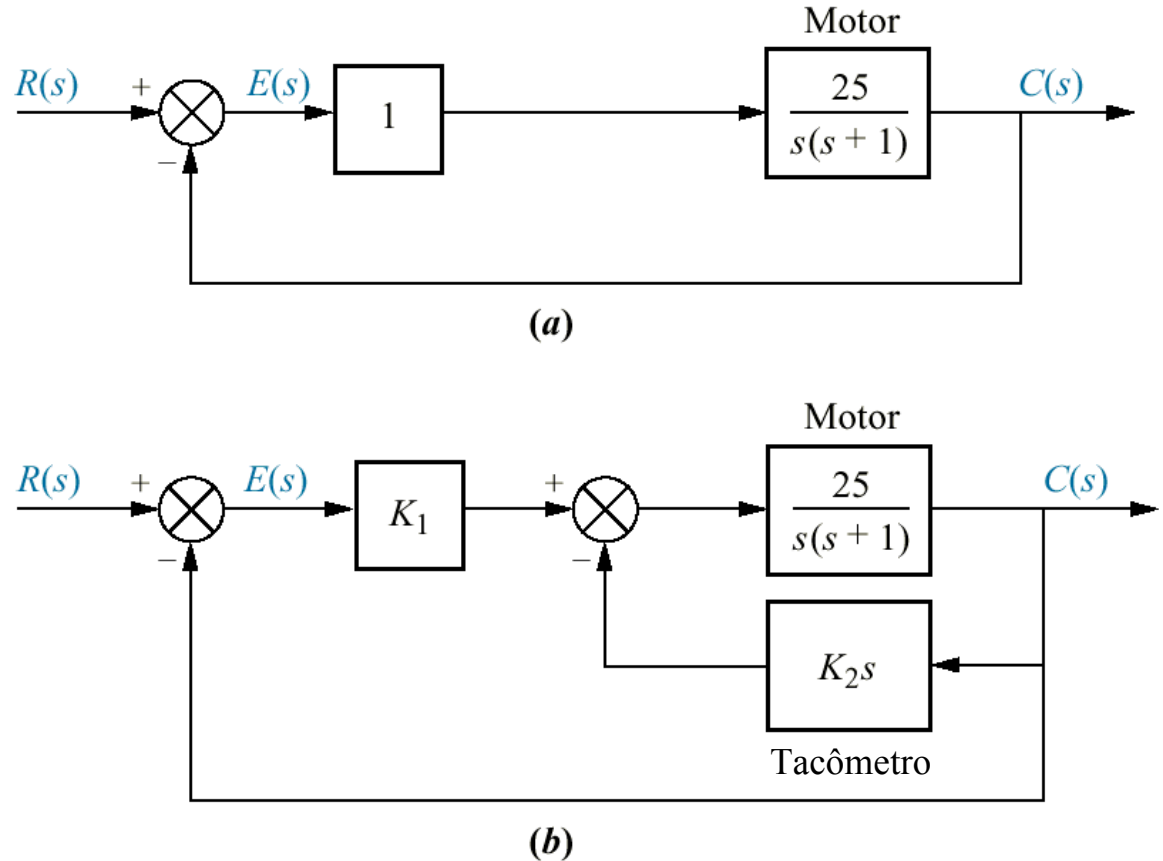


Fig. P5.40
 Controle de posição

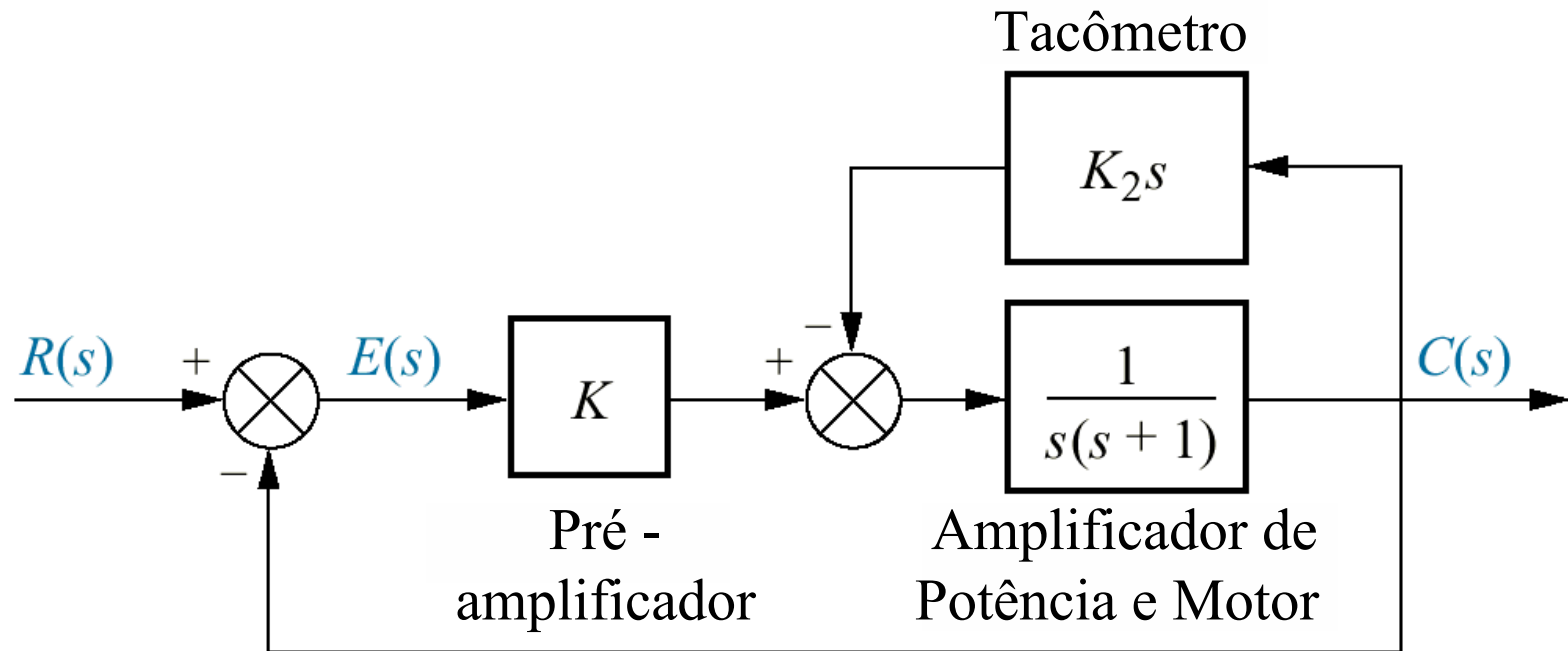


Fig. P5.41

a. Motor e carga;
 b. Motor e carga no sistema com retroação

