

various speeds such as $\omega=83.73$ rad/sec (N=800 rpm), $\omega=104.6$ rad/sec (N=1000 rpm), $\omega=151.7$ rad/sec (N=1450 rpm). Even though three different speeds are available, only one speed is selected at a moment based on the requirement of the diameter of the cable [10] [12]. If the cable diameter is 4.75mm, then speed of the motor is $\omega=151.7$ rad/sec (N=1450 rpm). In case cable diameter is 7.25mm, then speed of the induction motor is reduced from $\omega=151.7$ rad/sec (N=1450 rpm) to $\omega=104.6$ rad/sec (N=1000 rpm). Suppose cable diameter is 10.35mm, then speed of the induction motor is reduced from $\omega=104.6$ rad/sec (N=1000 rpm) to $\omega=83.73$ rad/sec (N=800 rpm). Besides low torque of the motor is needed for high speed of the motor which is used to pull low diameter (4.75mm) cable. On the other hand high torque of the motor is needed for low speed of the motor which is used to pull high diameter (10.35mm) cable. Therefore motor speed depends on the diameter of the cable. Moreover the role of speed controller for induction motor in cable industry is essential [9].

3. Potentiometer (Pot) operated PID based speed controller for 3hp capstan motor: Pot operated PID controller based speed controller is shown in fig. (3). This PID Speed controller used here is controlled by pot. This pot is manually set by the human by seeing the diameter of the cable which is going to be pulled by the 3hp capstan motor.

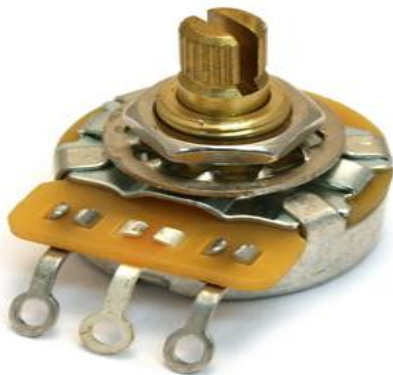


Fig. 3 Pot operated PID based speed controller

This kind of Pot operated PID based speed controller speed controller is olden day's controller because it is operated by pot setting [1], [2].

TABLE I PROPORTIONAL INTEGRAL DERIVATIVE SPEED CONTROLLER FOR 3HP CAPSTAN MOTOR

Proportional gain (K_p)	26
Integral gain (K_i)	39
Derivative gain (K_d)	0.09

PID controller block parameters are shown in table-1. This PID controller is working as speed controller for the 3hp three phase induction motor (capstan motor). In this closed loop control, proportional gain (K_p) is 26, integral gain (K_i) is 39 and derivative gain (K_d) is 0.09. These PID gain values are obtained from VFD (Variable frequency drive) which is used in cable industry.

Equation of the PID controller is of the following form,

$$u(t) = K_p e(t) + K_i \int e(t) dt + K_d (de/dt) \tag{1}$$
 Where, K_p = Proportional gain
 K_i = Integral gain
 K_d = Derivative gain
 $e(t)$ = Error between actual speed and reference speed
 $u(t)$ = Control signal

Moreover, this PID based speed controller is severely affected by the disturbance signals such as voltage sag, voltage swell and load variation. Moreover voltage sag refers to sudden voltage drop in the AC three phase supply which affects the induction motor. Voltage swell refers to sudden voltage rise in the AC three phase supply which affects the induction motor. Load variation refers to load which is applied on the three phase induction motor shaft. This load on the shaft varies when diameter of the cable varies [6], [8]. Therefore based on this study, it is found that it is better to replace this Pot operated PID based speed controller by placing fuzzy controller in the outset. Then replace this fuzzy controller by Neural network controller and Neuro-fuzzy controller. Finally attach the robust controller for this 3hp three phase induction motor out of these three controllers. (i.e. Fuzzy logic controller, Neural network controller, Neuro-fuzzy controller). Moreover, it is also recommended that while designing the controller for this 3hp three phase induction motor (capstan motor), disturbance environment such as load variation in terms of load torque in newton metre, voltage sag and voltage swell signals should be included [5], [7]. Similarly for other 1hp, 5hp, 15hp motor PID controller can be replaced by robust controller.

D. Take up controller

Take up controller comprises of the following blocks.

1. Take up machine:



Fig. 4 Pictorial representation of take up machine with PVC layer

Pictorial representation of take up machine with PVC layer is shown in fig. (4). In this there is a bobbin. This bobbin is used to take up the cable which is used for commercial purpose.

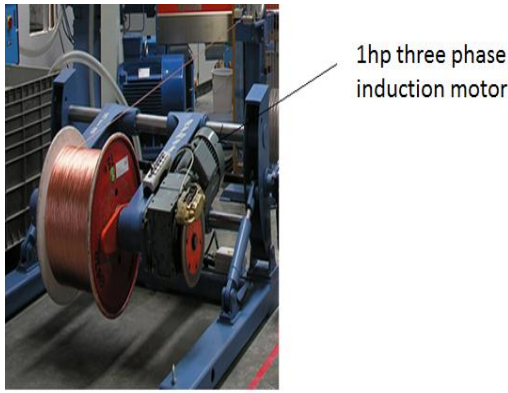


Fig. 5 Pictorial representation of take up machine without PVC layer

Pictorial representation of take up machine without PVC layer is shown in fig (5). In this machine, without PVC layer bare copper is taking up to the bobbin. This bobbin size can be selected based on the diameter of cable which is in terms of millimeters.

2. *Three phase induction motor (1hp take up motor)*: 1hp three phase induction motor is used as a taker up motor. This motor comes after the capstan motor to roll the cable in the bobbin .

III. CABLE DRAWING PROCESS

This cable drawing process comprises of the various blocks namely payoff, wire drawing, annealing and three phase induction motor with controller. Cable drawing process is shown in fig (6).

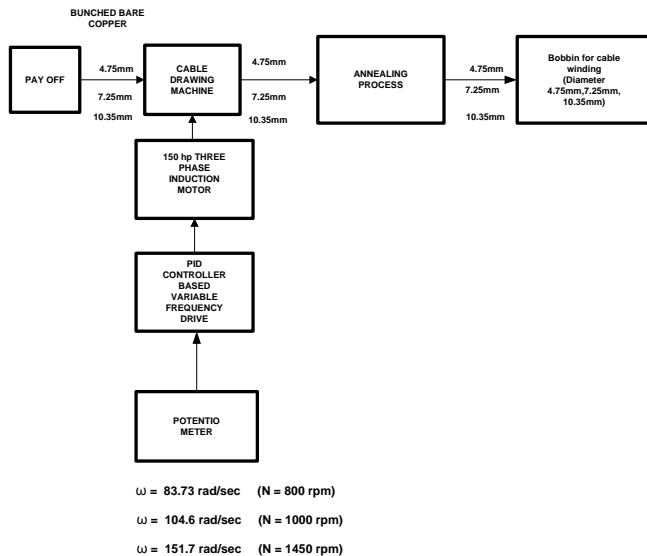


Fig. 6 Cable drawing process

A. Payoff

Cable payoff process is shown in fig (7). In this block there may be one (or) two bobbins. If one bobbin is there then it delivers cable from one bobbin. Suppose two bobbins are there, then dual cable payoff from two individual bobbin is possible. Cable drawing process is shown in fig. 6. In fig. 7,

single bobbin is used for doing payoff (i.e. cable delivery) process.



Fig. 7 Cable payoff process

B. Cable annealing process

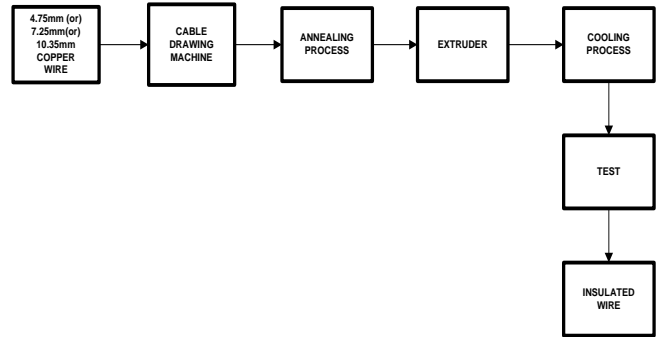


Fig. 8 Cable annealing process

Cable annealing process is shown in fig (8). In this process, 4.75mm, 7.25mm, 10.35mm copper wire is drawn from the bobbin (or) wire storage. Then wire drawing can be done with the help of wire drawing machine which is operated by 150hp three phase induction motor. After wire drawing, wire is taken into annealing process. Annealing is a heat treatment process which alters the microstructure of a material to change its mechanical or electrical properties. During this annealing process, wire (or) cable is exposed with heat followed by cooling slowly in order to remove internal stress and toughen it. Moreover, cable taken from annealing process is passed via extruder and testing unit. Finally, insulated wire take up is done by the bobbin.

IV. TWISTING AND STRANDING

Twisting and stranding is shown in fig (9). In this process, insulated wire take up by the bobbin in the previous stage is delivered (i.e. pay off) to the twister unit. Two bobbins (i.e. bobbin1 and bobbin2) are involved for delivering wires to the twister unit for twisting. Then twisted wire is taking up by another bobbin say bobbin 3. Besides like this bobbin 3, bobbin 4, bobbin 5 and bobbin 6 are formed by twisted pair wires. Finally, these bobbins 3,4,5,6 which are having twisted pair of cables which are passed via strander.

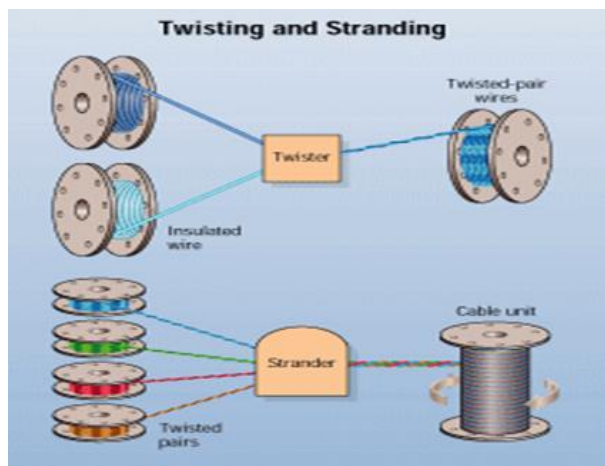


Fig. 9 Twisting and stranding

This strander merges bobbin 3,4,5,6 twisted pairs to form an ultimate cable unit.

V. CONCLUSION

Cable manufacturing industry (Ravicab cables private limited) at Bidadi is discussed. Cable industry operation has been studied with the help of extruder, diameter controller, capstan controller, take up controller, speed controller. Cable drawing process is explained by using payoff, wire drawing and annealing process, twisting and stranding process. In this cable industry three phase 1hp, 3hp, 5hp, 15hp and 150hp induction motors are utilized for making the various diameter cables such as 4.75mm, 7.25mm and 10.35mm. Moreover, it is found that PID controller based speed controller is used for all these three phase induction motors. This PID based speed controllers are greatly affected by disturbance signals such as voltage sag, voltage swell, and load variations. Hence, it is necessary to select and employ a novel robust controller for these induction motors. In order to find the robust controller, there is a necessary to interface various speed controllers individually. As a result of this study three phase induction motor is going to be interfaced with fuzzy logic, neural network and neuro-fuzzy controller separately. Eventually this study contributes, a novel robust controller for vector controlled induction motor drive as a future work. Moreover in future, matlab Simulink based simulation and hardware implementation will be

carried out for any one of the horse power motor (i.e. 1hp, 3 hp, 5 hp, 15 hp, 150hp).

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