

LAMPIRAN

```
Timer2.setCompare(TIMER_CH2, 1);

Timer2.attachInterrupt(TIMER_CH2,INT1);

Timer2.refresh();

Timer3.init();

Timer3.pause(); // stop timer

Timer3.setMasterMode(TIMER_MASTER_MODE_UPDATE);

Timer3.setPrescaleFactor(3); //5.2Khz

Timer3.setOverflow(setOverflow);

Timer3.setCount(0);

Timer3.setMode(TIMER_CH1, TIMER_PWM);

Timer3.refresh();

Timer2.resume();

Timer3.resume();

inADC.setSamplingTime(ADC_SMPR_3);

inADC.enableDMA();

}

void loop()

{

if (Timer3.getCount() >= 2000)

count = setOverflow-Timer3.getCount();

else

count = Timer3.getCount();
```

```
car1 = map(count, 0, 2000, 0, 2000);  
car2 = map(count, 0, 2000, 2000, 4000);  
car3 = map(count, 0, 2000, -2000, 0);  
car4 = map(count, 0, 2000, -2000, -4000);
```

```
R();
```

```
serial();
```

```
}
```

```
void INT1(void){
```

```
vsin = map(analogRead(PA2), 0, 4095, -4000, 4000);
```

```
vref = map(vsin, -4000, 4000, 4000, -4000);
```

```
act = map(analogRead(PA0), 0, 4095, -4000, 4000);
```

```
vact = map(act, -4000, 4000, 4000, -4000);
```

```
arus = map(analogRead(PA1), 0, 4095, -4000, 4000);
```

```
iact = map(arus, -4000, 4000, 4000, -4000);
```

```
}
```

```
void R(){
```

```
err_v = vref - vact;
```

```
P_v = kp_v * err_v;
```

```
itg_v = lastitg_v + err_v * 0.00001;
```

```
I_v = ki_v * itg_v;
```

```
pi_v = P_v + I_v;
```

```

if (pi_v > -4000 && pi_v < 4000) // current anti windup
{
    lastitg_v = itg_v;
}

iref = pi_v;
err = iref - iact;
P = kp * err;
itg = lastitg + err * 0.00001;
I = ki * itg;
pi = P + I;

//Bidirect 1
if (pi >= car1){
    digitalWrite(B1, 1);
}
else {
    digitalWrite(B1, 0);
}

//Saklar 1
if (pi >= car2){
    digitalWrite(S1, 1);
}
else{

```

```

    digitalWrite(S1, 0);
}

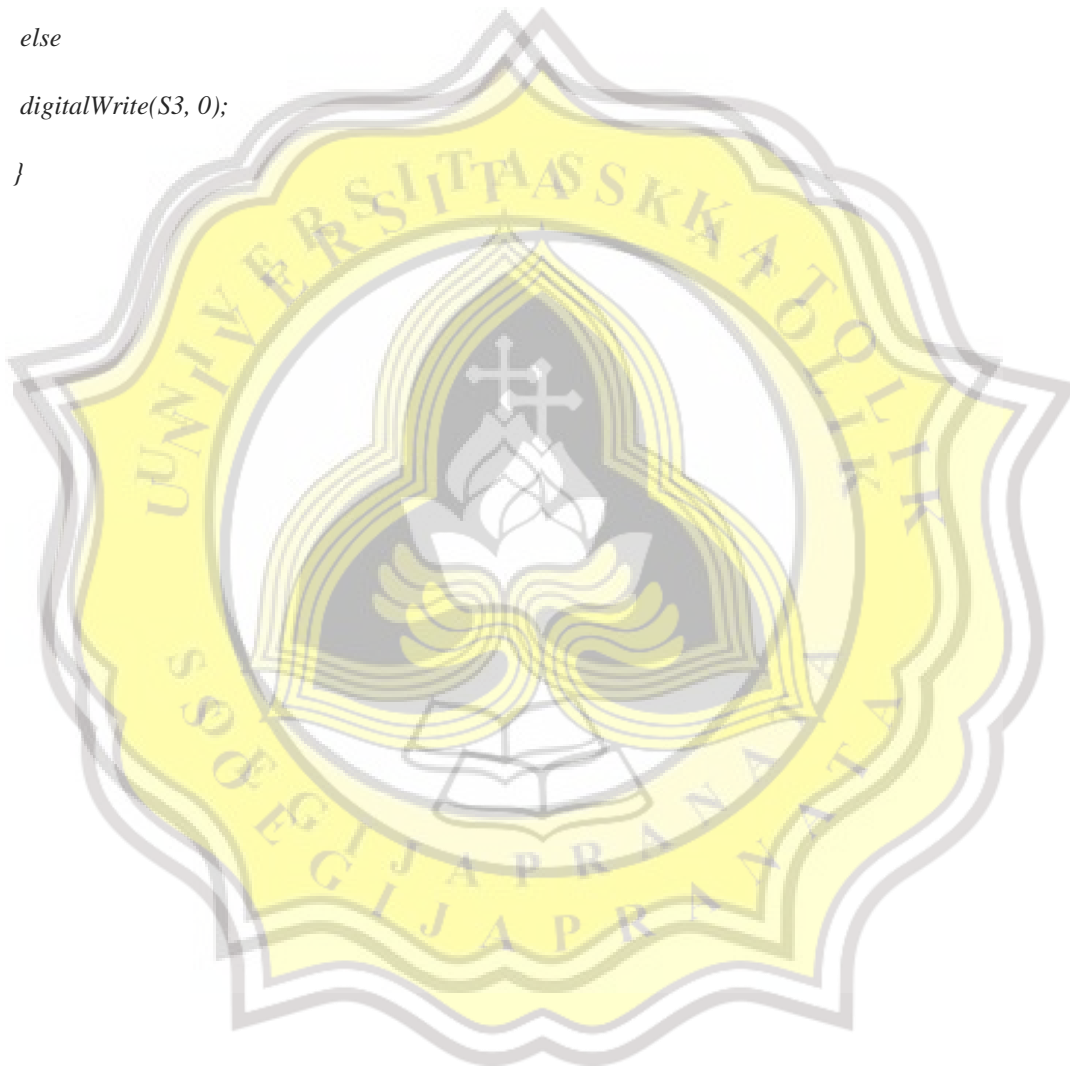
//Bidirect 2
if (pi >= car3){
    digitalWrite(B2, 0);
}
else{
    digitalWrite(B2, 1);
}

//Saklar 2
if (pi >= car4){
    digitalWrite(S2, 0);
}
else{
    digitalWrite(S2, 1);
}

////ZC////
if (pi >= DT) //zero crossing
{
    digitalWrite(S3, 0);
    digitalWrite(S4, 1);
}
else
    digitalWrite(S4, 0);

```

```
if(pi <= DT) //zero crossing
{
digitalWrite(S3, 1);
digitalWrite(S4, 0);
}
else
digitalWrite(S3, 0);
}
```



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18.f1.0013_File antiplagiasi_Laporan Tugas akhir.docx

WORD COUNT

3563 Words

CHARACTER COUNT

22546 Characters

PAGE COUNT

22 Pages

FILE SIZE

46.0KB

SUBMISSION DATE

Oct 13, 2022 8:36 AM GMT+7

REPORT DATE

Oct 13, 2022 8:37 AM GMT+7

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