

Title (en)

PROCESS AND DEVICE FOR THE POSITION CONTROL OF A POSITIONING DRIVE, ESPECIALLY FOR LIFTS

Publication

EP 0318660 B1 19920401 (DE)

Application

EP 88115868 A 19880927

Priority

CH 464787 A 19871127

Abstract (en)

[origin: JPH01167191A] PURPOSE: To enable a distance actual value to follow a given distance desired value with high accuracy by regulating a control stage being a basis of a positioning drive as a standard control stage influenced by an obstacle. CONSTITUTION: An armature current I_A supplied to an electric motor 1 is controlled through the final control element 7 of a cascade control device KR to be supplied to a current controller 9 connected to the front stage as a current actual value I_{Ai} by a current transformer 8. Similarly, a speed controller 10 is connected to the front stage of the current controller 9 so that this controller 10 receives the speed actual value V_i from a tachometer 12. A distance controller 13 receives the distance actual value S_i from a distance generator 14 driven by a cage 5. In a control quantity generator FG, a distance desired value is constituted by integrating an impact model RM three times according to time by integrators 15, 16, 17 so that this value is sent to the cascade control device KR as a derived distance desired value S_s .

IPC 1-7

B66B 1/30

IPC 8 full level

B66B 1/28 (2006.01); **B66B 1/30** (2006.01)

CPC (source: EP US)

B66B 1/285 (2013.01 - EP US); **B66B 1/30** (2013.01 - EP US)

Cited by

EP0477867A3; EP3421400A1; CN109205420A; EP0477976B1

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AT CH DE ES FR GB IT LI

DOCDB simple family (publication)

EP 0318660 A1 19890607; **EP 0318660 B1 19920401**; AT E74330 T1 19920415; CA 1307060 C 19920901; DE 3869744 D1 19920507; ES 2031565 T3 19921216; FI 885420 A0 19881123; FI 885420 A 19890528; FI 96674 B 19960430; FI 96674 C 19960812; HK 52593 A 19930604; JP H01167191 A 19890630; US 4887695 A 19891219

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