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正 誤 表

書　名：永久磁石同期モータのベクトル制御

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刷	頁	箇所	誤	正
1	24	(2.23) 式	$S = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}]$	$S_2 = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}]$
1	24	(2.24) 式	$S = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}\ \ \boldsymbol{u}_{3c}\ \ \boldsymbol{u}_{3s}]$	$S_4 = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}\ \ \boldsymbol{u}_{3c}\ \ \boldsymbol{u}_{3s}]$
1	25	(2.25) 式	$S = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}\ \ \boldsymbol{u}_{3c}\ \ \boldsymbol{u}_{3s}\ \ \boldsymbol{u}_{5c}\ \ \boldsymbol{u}_{5s}]$	$S_6 = [\boldsymbol{u}_{1c}\ \ \boldsymbol{u}_{1s}\ \ \boldsymbol{u}_{3c}\ \ \boldsymbol{u}_{3s}\ \ \boldsymbol{u}_{5c}\ \ \boldsymbol{u}_{5s}]$
1, 2	54	(2.115)式	$\tau = N_p \boldsymbol{i}_{1r}^T \boldsymbol{J}\boldsymbol{\phi}_{rm} = N_p \Phi i_q$	$\tau = N_p \boldsymbol{i}_{1r}^T \boldsymbol{J}\boldsymbol{\phi}_{mr} = N_p \Phi i_q$
1, 2	60	(2.133)式	$$\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{i}_1 = \left[\frac{l_i\boldsymbol{I} - L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2 - L_m^2}\right][-R_1\boldsymbol{I} + 2\omega_{2n}L_m\boldsymbol{J}]\boldsymbol{i}_1 + \left[\frac{L_i\boldsymbol{I} - L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2 - L_m^2}\right][-\omega_{2n}\boldsymbol{J}\boldsymbol{\phi}_m + \boldsymbol{v}_1] \quad (2.133)$$	$$\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{\phi}_i = [L_i\boldsymbol{I} + L_m\boldsymbol{Q}(\theta_\gamma)]\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{i}_1 - 2\omega_{2n}L_m\boldsymbol{Q}(\theta_\gamma)\boldsymbol{J}\boldsymbol{i}_1 \quad (2.133a)$$ $$\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{i}_1 = \left[\frac{L_i\boldsymbol{I} - L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2 - L_m^2}\right][-R_1 I + 2\omega_{2n}L_m\boldsymbol{Q}(\theta_\gamma)\boldsymbol{J}]\boldsymbol{i}_1 + \left[\frac{L_i\boldsymbol{I} - L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2 - L_m^2}\right][-\omega_{2n}\boldsymbol{J}\boldsymbol{\phi}_m + \boldsymbol{v}_1] \quad (2.133b)$$
1	69	(2.155)式	$\phi_t = \Phi_t[\cos\theta_\alpha$	$\phi_{mt} = \Phi_t[\cos\theta_\alpha$
1	102	(4.40)式 上式	誤	$$\boldsymbol{R}^T(\theta_\alpha)\boldsymbol{S}^T = \sqrt{\frac{2}{3}}\begin{bmatrix} \cos\theta_\alpha & \cos\left(\theta_\alpha - \frac{2\pi}{3}\right) & \cos\left(\theta_\alpha + \frac{2\pi}{3}\right) \\ -\sin\theta_\alpha & -\sin\left(\theta_\alpha + \frac{2\pi}{3}\right) & -\sin\left(\theta_\alpha - \frac{2\pi}{3}\right) \end{bmatrix}$$
			正	$$\boldsymbol{R}^T(\theta_\alpha)\boldsymbol{S}^T = \sqrt{\frac{2}{3}}\begin{bmatrix} \cos\theta_\alpha & \cos\left(\theta_\alpha - \frac{2\pi}{3}\right) & \cos\left(\theta_\alpha + \frac{2\pi}{3}\right) \\ -\sin\theta_\alpha & -\sin\left(\theta_\alpha - \frac{2\pi}{3}\right) & -\sin\left(\theta_\alpha + \frac{2\pi}{3}\right) \end{bmatrix}$$
1	128	(5.13a)式	$\frac{\partial}{\partial \boldsymbol{x}} L(\boldsymbol{x},\boldsymbol{\lambda}) = 0$	$\frac{\partial}{\partial \boldsymbol{x}} L(\boldsymbol{x},\boldsymbol{\lambda}) = \boldsymbol{0}$ 補足：0 をボールドに修正
1	128	(5.13b) 式	$$\frac{\partial}{\partial \boldsymbol{x}} L(\boldsymbol{x},\boldsymbol{\lambda}) = \begin{bmatrix} f_2(x_1,x_2,\dots,x_n) \\ f_3(x_1,x_2,\dots,x_n) \\ \vdots \\ f_m(x_1,x_2,\dots,x_n) \end{bmatrix} = 0$$	$$\frac{\partial}{\partial \boldsymbol{x}} L(\boldsymbol{x},\boldsymbol{\lambda}) = \begin{bmatrix} f_2(x_1,x_2,\dots,x_n) \\ f_3(x_1,x_2,\dots,x_n) \\ \vdots \\ f_m(x_1,x_2,\dots,x_n) \end{bmatrix} = \boldsymbol{0}$$ 補足：0 をボールドに修正

1, 2	185	(6.24a)式	$\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{i}_L=\left[\frac{L_i\boldsymbol{I}-L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2-L_m^2}\right]\left[-\frac{R_1R_c}{R_1+R_c}\boldsymbol{I}+2\omega_{2n}\boldsymbol{L}_m\boldsymbol{J}\right]\boldsymbol{i}_L$ $+\left[\frac{L_i\boldsymbol{I}-L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2-L_m^2}\right]\left[-\omega_{2n}\boldsymbol{J}\boldsymbol{\phi}_m+\frac{R_c}{R_1+R_c}\boldsymbol{v}_1\right]$	$\boldsymbol{D}(s,\omega_\gamma)\boldsymbol{i}_L=\left[\frac{L_i\boldsymbol{I}-L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2-L_m^2}\right]\left[-\frac{R_1R_c}{R_1+R_c}\boldsymbol{I}\right.$ $\left.+2\omega_{2n}L_m\boldsymbol{Q}(\theta_\gamma)\boldsymbol{J}\right]\boldsymbol{i}_L$ $+\left[\frac{L_i\boldsymbol{I}-L_m\boldsymbol{Q}(\theta_\gamma)}{L_i^2-L_m^2}\right]\left[-\omega_{2n}\boldsymbol{J}\boldsymbol{\phi}_m+\frac{R_c}{R_1+R_c}\boldsymbol{v}_1\right]$
1, 2	211	(6.69a)式	$\\|\boldsymbol{i}_1\\|^2=\left(i_{Ld}-\frac{\omega_{2n}L_qi_{Lq}}{R_c}\right)^2+\left(i_{Lq}+\frac{\omega_{2n}(L_di_{Lq}+\Phi)}{R_c}\right)^2$	$\\|\boldsymbol{i}_1\\|^2=\left(i_{Ld}-\frac{\omega_{2n}L_qi_{Lq}}{R_c}\right)^2+\left(i_{Lq}+\frac{\omega_{2n}(L_di_{Ld}+\Phi)}{R_c}\right)^2$

以上