

Motor Control Blockset™

Reference



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R2020a



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Motor Control Blockset™ Reference

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Revision History

March 2020	Online only	New for Version 1.0 (Release 2020a)
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1	Blocks
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Blocks

DQ Limiter

Saturate voltages (or current) in the dq reference frame

Library: Motor Control Blockset / Controls / Control Reference



Description

The DQ Limiter block generates saturated values of the input voltages (or current) in the dq reference frame, based on the phase voltage (or current) peak limit of the inverter.

The block accepts reference values of d and q axis voltages (or current) and outputs the corresponding saturated values. The block also provides the unsaturated peak value of the reference dq voltages (or current) to enable field weakening control.

Equations

These equations describe the computation of saturated dq voltage (or current) values by the block.

$$mag^{ref} = \sqrt{(d^{ref})^2 + (q^{ref})^2}$$

When $mag^{ref} \leq D - Q$ saturation limit.

- $d^{sat} = d^{ref}$
- $q^{sat} = q^{ref}$

When $mag^{ref} > D - Q$ saturation limit.

- $d^{sat} = \frac{d^{ref}}{\sqrt{(d^{ref})^2 + (q^{ref})^2}} \times D - Q$ saturation limit
- $q^{sat} = \frac{q^{ref}}{\sqrt{(d^{ref})^2 + (q^{ref})^2}} \times D - Q$ saturation limit

Ports

Input

d^{ref} — Reference d -axis voltage (or current)

scalar

Reference voltage (or current) value along the d -axis of the rotating dq reference frame.

Data Types: single | double | fixed point

q^{ref} — Reference q -axis voltage (or current)

scalar

Reference voltage (or current) value along the q -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

Output

d^{sat} — Saturated d -axis voltage (or current)

scalar

Saturated voltage (or current) value along the d -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

q^{sat} — Saturated q -axis voltage (or current)

scalar

Saturated voltage (or current) value along the q -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

mag^{ref} — Unsaturated peak value of block inputs

scalar

Unsaturated peak value of the input voltages (or current).

Data Types: `single` | `double` | `fixed point`

Parameters

D-Q saturation limit — Phase voltage (or current) peak limit

1 (default) | scalar

The maximum magnitude of the stator phase voltage (or current) that the inverter can supply to the motor.

D – Q saturation limit (current) is usually the rated current of the motor. When you work with the Per-Unit system (PU), you should convert the rated current of the motor to Per-Unit value with respect to the base current.

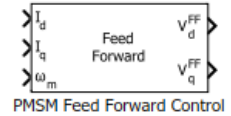
D – Q saturation limit (voltage) is the maximum phase voltage supplied by the inverter. Generally it is $\frac{V_{\text{dc}}}{\sqrt{3}}$ for Space Vector PWM and $\frac{V_{\text{dc}}}{2}$ for Sinusoidal PWM, where V_{dc} is the DC link voltage of the inverter.

Note You can enter either per unit or SI unit voltage (or current) value in this parameter. For optimum performance, we recommend that you provide a per unit value.

PMSM Feed Forward Control

Decouple d -axis and q -axis current to eliminate disturbance

Library: Motor Control Blockset / Controls / Control Reference



Description

The PMSM Feed Forward Control block decouples d -axis and q -axis current controls and generates the corresponding feed-forward voltage gains to enable field-oriented control of Permanent Magnet Synchronous Motor (PMSM).

The block accepts feedback values of d -axis and q -axis currents and the mechanical speed of the rotor.

Equations

If you select Per-Unit (PU) in the **Input units** parameter, the block converts the inputs to SI units before performing any computation. After calculating the output, the block converts the values back to per unit values.

These equations describe the computation of feed-forward gain by the block.

$$\omega_e = \left(\frac{2\pi}{60}\right) \times p \times \omega_m$$

$$V_d^{FF} = \omega_e \lambda_d = \omega_e L_d I_d + \omega_e \lambda_m$$

$$V_q^{FF} = -\omega_e \lambda_q = -\omega_e L_q I_q$$

where:

- ω_e is the electrical speed of the rotor (Radians/ sec).
- ω_m is the mechanical speed of the rotor (Radians/ sec).
- p is the number of pole pairs available in the motor.
- L_d and L_q are the d -axis and q -axis stator winding inductances (Henry).
- I_d and I_q are the d -axis and q -axis currents (Amperes).
- λ_d and λ_q are the magnetic fluxes along the d - and q -axes (Weber).
- λ_m is the permanent magnet flux linkage (Weber).

Ports

Input

I_d — D-axis current

scalar

Current along the d -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

I_q — Q-axis current

scalar

Current along the q -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

ω_m — Mechanical speed of rotor

scalar

Mechanical speed of the rotor.

Data Types: `single` | `double` | `fixed point`

Output

V_d^{FF} — D-axis feed-forward voltage gain

scalar

Feed-forward voltage gain along the d -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

V_q^{FF} — Q-axis feed-forward voltage gain

scalar

Feed-forward voltage gain along the q -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

Parameters

Number of pole pairs — Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Stator d-axis inductance (H) — D-axis stator winding inductance

1e-3 (default) | scalar

Stator winding inductance (in Henry) along the direct-axis of the rotating dq reference frame.

Stator q-axis inductance (H) — Q-axis stator winding inductance

1e-3 (default) | scalar

Stator winding inductance (in Henry) along the quadrature-axis of the rotating dq reference frame.

Permanent magnet flux linkage (Wb) — PM flux linkage

5e-3 (default) | scalar

Peak permanent magnet flux linkage (in Weber).

Output Saturation (V) — Saturation limit for output values

24/sqrt(3) (default) | scalar

Saturation limit (in Volts) for the output voltages V_d^{FF} and V_q^{FF} .

Input units – Unit of input values

Per-Unit (PU) (default) | SI Units

Unit of the input values.

Base Voltage (V) – Nominal voltage limit

$24/\sqrt{3}$ (default) | scalar

Nominal voltage (in Volts) that corresponds to one per unit voltage value.

Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

Base Current (A) – Nominal current limit

$24/\sqrt{3}$ (default) | scalar

Nominal current (in Amperes) that corresponds to one per unit current value.

Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

Base Speed (rpm) – Nominal speed limit

4000 (default) | scalar

Nominal speed (in rpm) that corresponds to one per unit speed value.

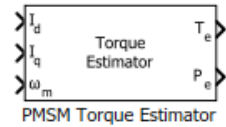
Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

PMSM Torque Estimator

Estimate electromechanical torque and power

Library: Motor Control Blockset / Controls / Control Reference



Description

The PMSM Torque Estimator block generates electromechanical torque and power estimates to enable field-oriented control of Permanent Magnet Synchronous Motor (PMSM).

The block accepts feedback values of d - and q -axis current and mechanical speed as inputs.

Equations

If you select Per-Unit (PU) in the **Input units** parameter, the block converts the inputs to SI units before performing any computation. After calculating the output, the block converts the output back to per unit values.

The following equations describe the computation of electromechanical torque and power estimates by the block.

$$T_e = \frac{3}{2}p\{\lambda_m I_q + (L_d - L_q)I_d I_q\}$$

$$P_e = T_e \times \omega_m$$

where:

- L_d and L_q are the d -axis and q -axis stator winding inductances (Henry).
- I_d and I_q are the d -axis and q -axis current (Amperes).
- λ_m is the permanent magnet flux linkage (Weber).
- p is the number of pole pairs available in the motor.
- ω_m is the mechanical speed of the rotor (Radians/ sec).

Ports

Input

I_d — D-axis current

scalar

Current along the d -axis of the rotating dq reference frame.

Data Types: single | double | fixed point

I_q — Q-axis current

scalar

Current along the q -axis of the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

ω_m — Mechanical speed of rotor

scalar

Mechanical speed of the rotor.

Data Types: `single` | `double` | `fixed point`

Output

T_e — Electromechanical torque

scalar

Electromechanical torque of the rotor.

Data Types: `single` | `double` | `fixed point`

P_e — Electromechanical power

scalar

Electromechanical power of the rotor.

Data Types: `single` | `double` | `fixed point`

Parameters

Number of pole pairs — Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Stator d-axis inductance (H) — D-axis stator winding inductance

1e-3 (default) | scalar

Stator winding inductance (henry) along the direct-axis of the rotating dq reference frame.

Stator q-axis inductance (H) — Q-axis stator winding inductance

1e-3 (default) | scalar

Stator winding inductance (henry) along the quadrature-axis of the rotating dq reference frame.

Permanent magnet flux linkage (Wb) — Permanent magnet flux linkage

5e-3 (default) | scalar

Peak permanent magnet flux linkage (weber).

Input units — Unit of input values

Per-Unit (PU) (default) | SI Units

Unit of the input values.

Base Voltage (V) — Nominal voltage limit

24/sqrt(3) (default) | scalar

Nominal voltage (in Volts) that corresponds to one per unit voltage value.

Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

Base Current (A) – Nominal current limit

10 (default) | scalar

Nominal current (in Amperes) that corresponds to one per unit current value.

Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

Base Speed (rpm) – Nominal speed limit

4000 (default) | scalar

Nominal speed (in rpm) that corresponds to one per unit speed value.

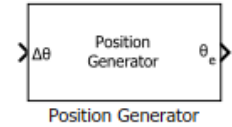
Dependencies

To enable this parameter, set **Input units** to Per-Unit (PU).

Position Generator

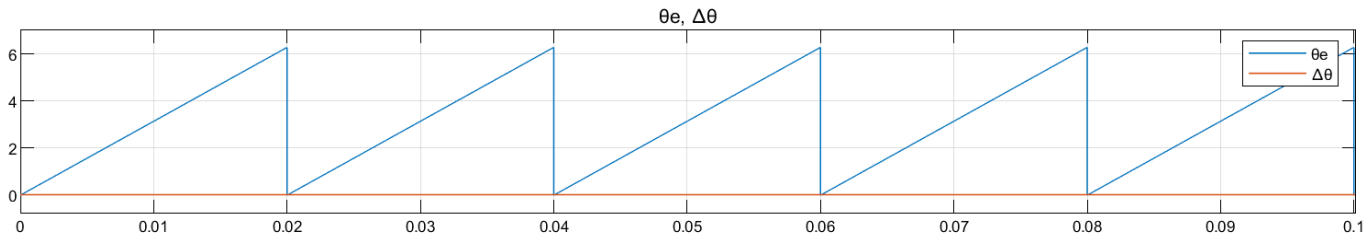
Generate position ramp of fixed frequency

Library: Motor Control Blockset / Controls / Control Reference



Description

The Position Generator block generates a position ramp signal (with a frequency that is identical to that of the reference voltage signal) using the position increment value of the reference signal.



Ports

Input

$\Delta\theta$ — Position increment value

scalar

Position increment value of a fixed frequency reference voltage signal (in either per unit, radians, or degrees). These equations describe how the block computes the position increment:

- $\Delta\theta$ (per unit) = Frequency \times Sample Time
- $\Delta\theta$ (radians) = $2\pi \times$ Frequency \times Sample Time
- $\Delta\theta$ (degrees) = $360 \times$ Frequency \times Sample Time

Data Types: single | double | fixed point

Reset — External reset signal

scalar

External pulse that resets the position ramp output based on the value of the **External reset** parameter.

Dependencies

To enable this port, set **External reset** to either active high resets to zero or active high resets to initial condition.

Data Types: single | double | fixed point

Output

θ_e — Reference voltage position

scalar

Position or phase value of the reference voltage signal (in either per unit, radians, or degrees).

Data Types: `single` | `double` | `fixed point`

Parameters

Theta Units — Unit of θ

Per-unit (default) | Radians | Degrees

Unit of the input position increment value and the output reference voltage position.

Initial theta output — Initial value of θ_e

θ (default) | scalar

Output position ramp value (in either per unit, radians, or degrees) at initial time (0 seconds).

External reset — Output value on reset

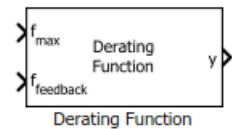
`none` (default) | `active high resets to zero` | `active high resets to initial condition`

Output position ramp value (in either per unit, radians, or degrees) at the time when the block receives an active high external reset pulse. You can reset the output to either zero or to equal the value of the **Initial theta output** parameter.

Derating Function

Compute derating factor

Library: Motor Control Blockset / Controls / Controllers



Description

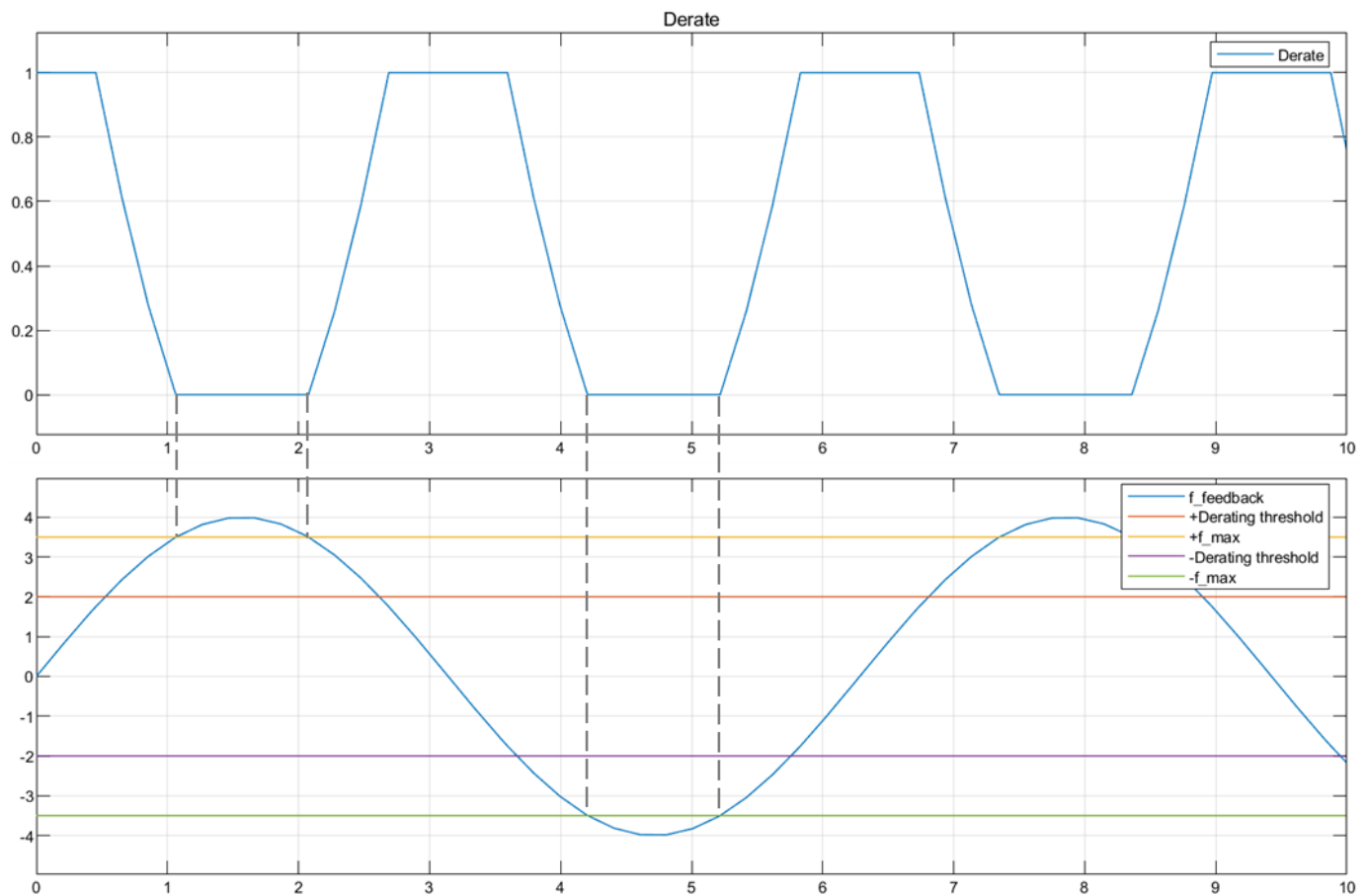
The Derating Function block generates the derating factor (y) according to the feedback (f_{feedback}) and maximum limit (f_{max}) values of the input reference signal.

The derating factor:

- Remains equal to one when f_{feedback} lies between positive and negative values of the **Derating threshold**. The derating factor varies linearly outside this range according to f_{feedback} .
- Remains equal to zero when the reference signal lies beyond (positive or negative) f_{max} .

Therefore, you can use the generated derating factor to derate a control signal after the reference signal crosses the specified **Derating threshold**.

This figure shows the block output when you use a sinusoidal wave as f_{feedback} .



Equations

The **Derating threshold** parameter, x indicates the percentage of peak amplitude for the reference signal. The **Derating threshold** is 0.5 in the block output shown, which results in a threshold value of 2 (for the peak amplitude value of 4 for the sinusoidal reference signal).

$$x = [0, 1)$$

This equation describes how the block computes the derating factor (y).

$$\text{Derating factor } (y) = 1 - \frac{f_{\text{feedback}} - x f_{\text{max}}}{(1 - x) f_{\text{max}}}$$

Ports

Input

f_{max} — Maximum reference signal limit

scalar

Maximum limit of the reference signal value beyond which the derating factor becomes zero.

Data Types: single | double | fixed point

f_{feedback} — Reference feedback signal

scalar

Reference signal that the block uses to generate the derating factor, which you can then use to derate a control signal.

Data Types: single | double | fixed point

Output **y — Derating factor**

scalar

Derating factor that the block generates based on the feedback and maximum limit values of the reference signal when the signal exceeds the value of the **Derating threshold** parameter.

Data Types: single | double | fixed point

Parameters**Derating threshold — Threshold beyond which derating must occur**

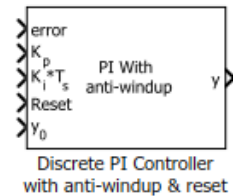
0.9 (default) | scalar in the range [0, 1)

The reference signal value beyond which the block generates the derating factor.

Discrete PI Controller with anti-windup and reset

Implement discrete PI controller with anti-windup and reset functionality

Library: Motor Control Blockset / Controls / Controllers



Description

The Discrete PI Controller with anti-windup and reset block performs discrete-time PI controller computation using the error signal and proportional and integral gain inputs. The error signal is the difference between the reference signal and the measured feedback. The block outputs a weighted sum of the input error signal and the integral of the input error signal.

You can tune the Discrete PI Controller coefficients (K_p and K_i) either manually or automatically. Automatic tuning requires Simulink® Control Design™ software.

The block also supports anti-windup functionality, which makes the block output to comply with the register size of the processor. You can reset the integrator to the initial condition (y_0).

Ports

Input

error — Variation of system output from expected value

scalar

Difference between a reference signal and the system output.

Data Types: `single` | `double` | `fixed point`

K_p — Proportional gain

scalar

Proportional gain value that you can compute either manually or automatically.

Data Types: `single` | `double` | `fixed point`

$K_i * T_s$ — Integral gain premultiplied by integrator sample time

scalar

Integral gain input that you can compute either manually or automatically. You must premultiply the integral gain value by the integrator sample time (T_s) for the block to execute within asynchronous interrupts.

Data Types: `single` | `double` | `fixed point`

Reset — External reset signal

scalar

External pulse that resets the block output to the value of the initial output from the integrator (y_0).

Data Types: `single` | `double` | `fixed point`

y_0 – Value of initial output from integrator

scalar

Initial value of the integrator or block output after receiving a reset pulse.

Data Types: `single` | `double` | `fixed point`

Output

y – PI controller output

scalar

Control signal that is identical to the reference signal.

Data Types: `single` | `double` | `fixed point`

Parameters

Upper saturation limit – Upper limit for block output

1 (default) | scalar

The block holds the output at the **Upper saturation limit** whenever the weighted sum of the proportional and integral actions exceeds this value.

Lower saturation limit – Lower limit for block output

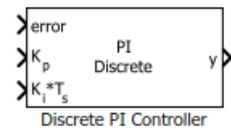
-1 (default) | scalar

The block holds the output at the **Lower saturation limit** whenever the weighted sum of the proportional and integral actions goes below this value.

Discrete PI Controller

Implement discrete PI controller

Library: Motor Control Blockset / Controls / Controllers



Description

The Discrete PI Controller block performs discrete-time PI controller computation using the error signal and proportional and integral gain inputs. The error signal is the difference between the reference signal and the measured feedback. The block outputs a weighted sum of the input error signal and the integral of the input error signal.

You can tune the Discrete PI Controller coefficients (K_p and K_i) either manually or automatically. Automatic tuning requires Simulink Control Design™ software.

Ports

Input

error — Variation of system output from expected value

scalar

Difference between a reference signal and the system output.

Data Types: `single` | `double` | `fixed point`

K_p — Proportional gain

scalar

Proportional gain value that you can compute either manually or automatically.

Data Types: `single` | `double` | `fixed point`

$K_i * T_s$ — Integral gain premultiplied by integrator sample time

scalar

Integral gain input that you can compute either manually or automatically. You must premultiply the integral gain value by the integrator sample time (T_s) for the block to execute within asynchronous interrupts.

Data Types: `single` | `double` | `fixed point`

Output

y — PI controller output

scalar

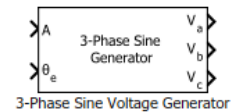
Control signal that is identical to the reference signal.

Data Types: `single` | `double` | `fixed point`

3-Phase Sine Voltage Generator

Generate balanced three-phase sinusoidal signals

Library: Motor Control Blockset / Controls / Math Transforms

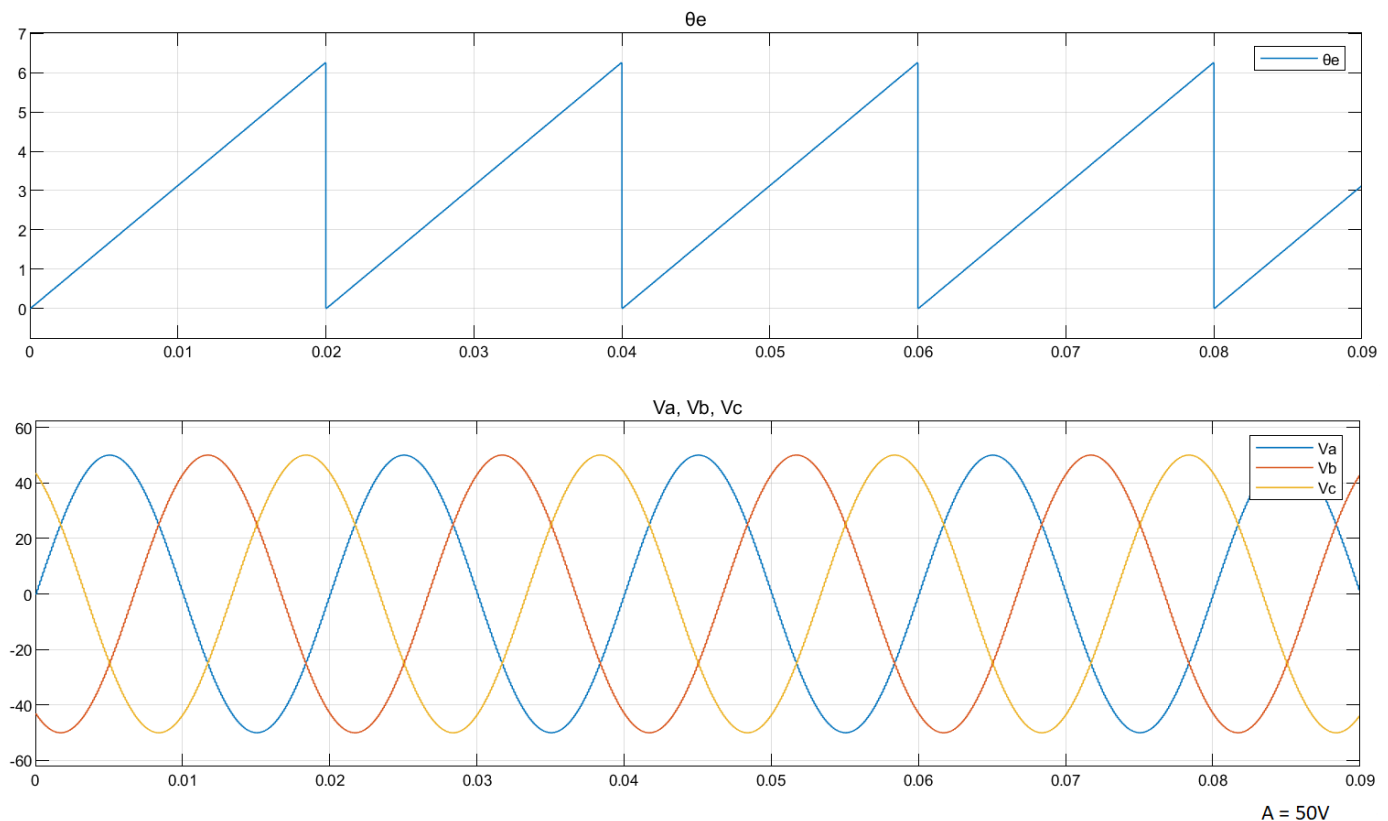


Description

The 3-Phase Sine Voltage Generator block generates balanced, three-phase sinusoidal signals using signal amplitude and position inputs.

The block uses the lookup table approach for optimized code-execution. You can specify the number of lookup table points in the **Number of data points for lookup table** parameter.

The following image shows a plot of position input and three-phase sinusoidal output signals against time.



Equations

The following equations describe how the block computes balanced, three-phase sinusoidal signals.

- $V_a = A \times \sin\omega t$
- $V_b = A \times \sin\left(\omega t - \frac{2\pi}{3}\right)$
- $V_c = A \times \sin\left(\omega t - \frac{4\pi}{3}\right)$

where:

- A is the reference voltage amplitude (volts).
- ω is the frequency of the reference voltage position input signal (θ_e) (radians/ sec).
- t is the time (seconds).

Ports

Input

A — Reference voltage amplitude

scalar

Maximum amplitude of the reference voltage signal.

Data Types: `single` | `double` | `fixed point`

θ_e — Reference voltage position

scalar

Position or phase value of the reference voltage signal.

Data Types: `single` | `double` | `fixed point`

Output

V_a — a-axis component of balanced, three-phase voltage

scalar

Balanced, three-phase voltage signal component along the a -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

V_b — b-axis component of balanced, three-phase voltage

scalar

Balanced, three-phase voltage signal component along the b -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

V_c — c-axis component of balanced, three-phase voltage

scalar

Balanced, three-phase voltage signal component along the c -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

Parameters

Theta units – Unit of θ_e

Per-unit (default) | Radians | Degrees

Unit of the reference voltage position that you provide as input.

Number of data points for lookup table – Size of lookup table

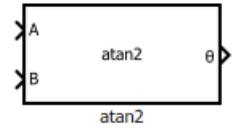
1024 (default) | scalar

Size of the lookup table.

atan2

Compute four-quadrant arctangent

Library: Motor Control Blockset / Controls / Math Transforms



Description

The atan2 block performs the four-quadrant arctangent on two real numbers.

Equations

This equation describes how the block computes the four-quadrant arctangent (θ).

$$Theta = atan2(A, B) = \begin{cases} \arctan\left(\frac{A}{B}\right) & \text{if } B > 0, \\ \arctan\left(\frac{A}{B}\right) + \pi & \text{if } B < 0 \text{ and } A \geq 0, \\ \arctan\left(\frac{A}{B}\right) - \pi & \text{if } B < 0 \text{ and } A < 0, \\ +\frac{\pi}{2} & \text{if } B = 0 \text{ and } A > 0, \\ -\frac{\pi}{2} & \text{if } B = 0 \text{ and } A < 0, \\ \text{undefined} & \text{if } B = 0 \text{ and } A = 0. \end{cases}$$

where:

$$-\pi < Theta \leq \pi \quad (\text{Radians})$$

Ports

Input

A — y-coordinate value (real number)

scalar

Real number on the y-axis that you provide as input to the block.

Data Types: single | double | fixed point

B — x-coordinate value (real number)

scalar

Real number on the x-axis that you provide as input to the block.

Data Types: single | double | fixed point

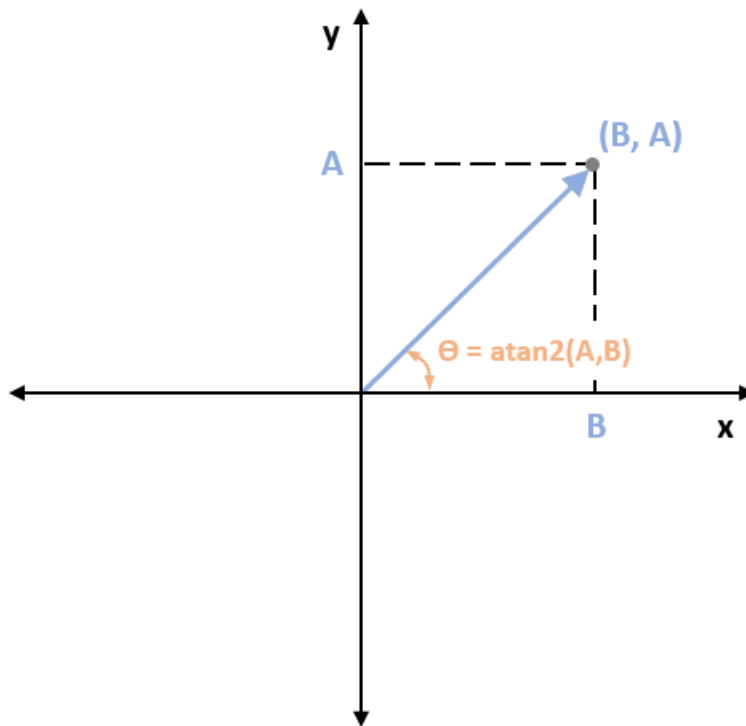
Output **θ – Angle represented by arctangent**

scalar

Angle represented by arctangent. This is the angle made by a vector from the origin to a specified point (x,y) with the positive x-axis.

Data Types: single | double | fixed point

The following figure shows the representation of input values A, B, and arctangent on the x-y coordinate plane.

**Parameters****Output unit – Unit of output values**

Radians (default) | PerUnit

Unit of the output values.

Clarke Transform

Implement ab to $\alpha\beta$ transformation

Library: Motor Control Blockset / Controls / Math Transforms



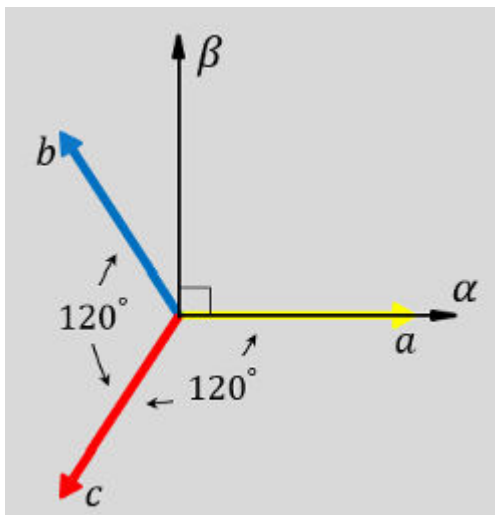
Description

The Clarke Transform block computes the Clarke transformation of balanced three-phase components in the abc reference frame and outputs the balanced two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.

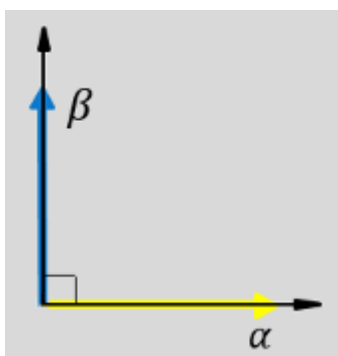
The block accepts two signals out of the three phases (abc), automatically calculates the third signal, and outputs the corresponding components in the $\alpha\beta$ reference frame.

For example, the block accepts a and b input values where the phase- a axis aligns with the α -axis.

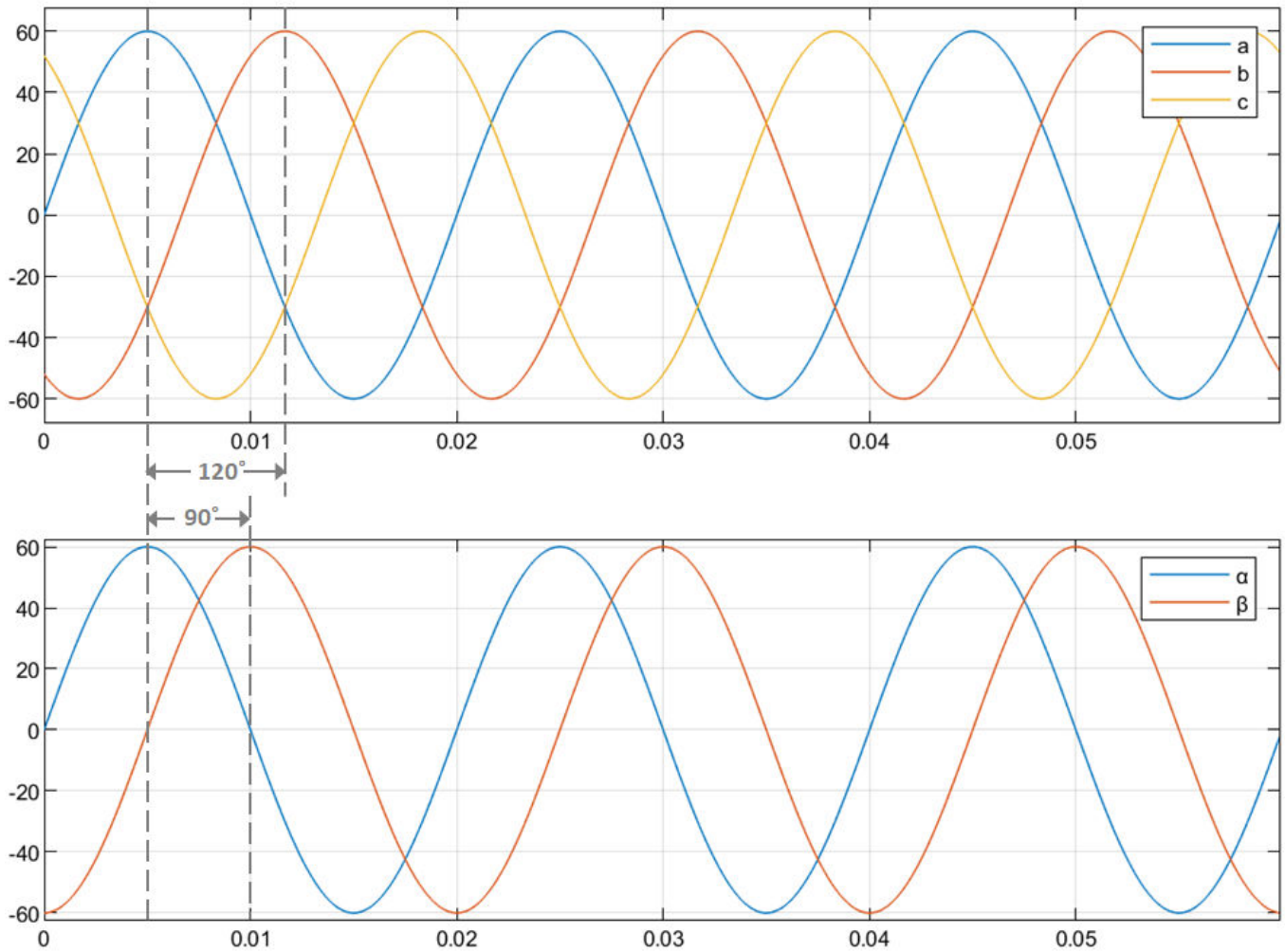
- This figure shows the direction of the magnetic axes of the stator windings in the abc reference frame and the stationary $\alpha\beta$ reference frame.



- This figure shows the equivalent α and β components in the stationary $\alpha\beta$ reference frame.



- The time-response of the individual components of equivalent balanced abc and $\alpha\beta$ systems.



Equations

The following equation describes the Clarke transform computation:

$$\begin{bmatrix} f_\alpha \\ f_\beta \\ f_0 \end{bmatrix} = \left(\frac{2}{3}\right) \times \begin{bmatrix} 1 & -\frac{1}{2} & -\frac{1}{2} \\ 0 & \frac{\sqrt{3}}{2} & -\frac{\sqrt{3}}{2} \\ \frac{1}{2} & \frac{1}{2} & \frac{1}{2} \end{bmatrix} \begin{bmatrix} f_a \\ f_b \\ f_c \end{bmatrix}$$

For balanced systems like motors, the zero sequence component calculation is always zero:

$$i_a + i_b + i_c = 0$$

Therefore, you can use only two current sensors in three-phase motor drives, where you can calculate the third phase as,

$$i_c = -(i_a + i_b)$$

By using these equations, the block implements the Clarke transform as,

$$\begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ -\frac{1}{\sqrt{3}} & \frac{2}{\sqrt{3}} \end{bmatrix} \begin{bmatrix} f_a \\ f_b \end{bmatrix}$$

where:

- f_a , f_b , and f_c are the balanced three-phase components in the abc reference frame.
- f_α and f_β are the balanced two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.
- f_0 is the zero component in the stationary $\alpha\beta$ reference frame.

Ports

Input

a — Phase component

scalar

Component of the three-phase system in the abc reference frame.

Data Types: `single` | `double` | `fixed point`

b — Phase component

scalar

Component of the three-phase system in the abc reference frame.

Data Types: `single` | `double` | `fixed point`

Output

α — Axis component

scalar

Alpha-axis component, α , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

β — Axis component

scalar

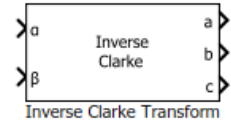
Beta-axis component, β , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

Inverse Clarke Transform

Implement $\alpha\beta$ to abc transformation

Library: Motor Control Blockset / Controls / Math Transforms

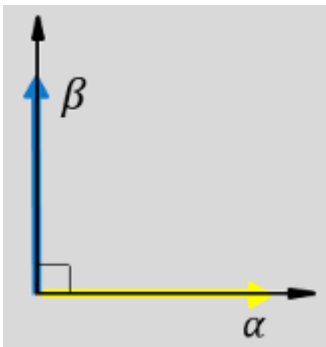


Description

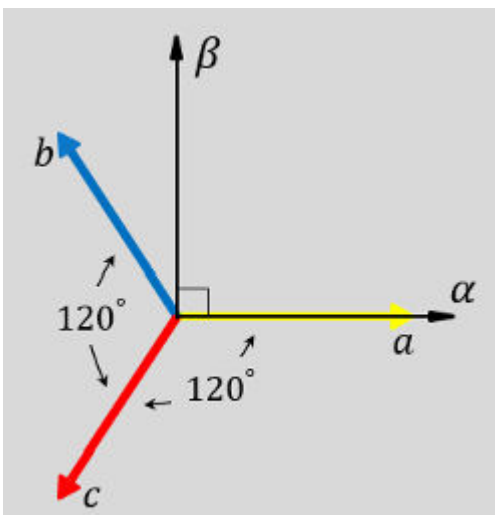
The Inverse Clarke Transform block computes the Inverse Clarke transformation of balanced, two-phase orthogonal components in the stationary $\alpha\beta$ reference frame. It outputs the balanced, three-phase components in the stationary abc reference frame.

The block accepts the α - β axis components as inputs and outputs the corresponding three-phase signals, where the phase- a axis aligns with the α -axis.

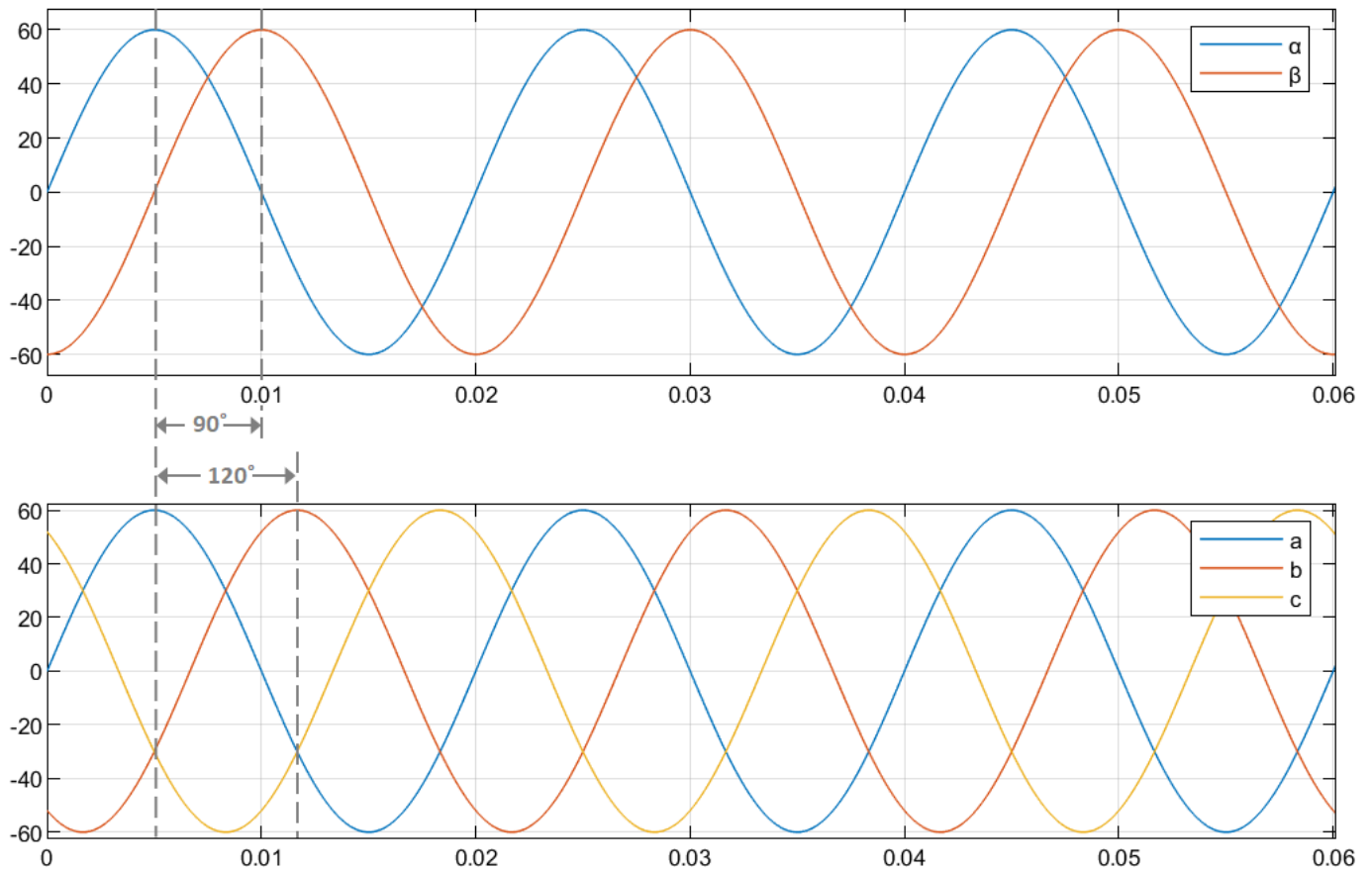
- The α and β input components in the $\alpha\beta$ reference frame.



- The direction of the equivalent a , b , and c output components in the abc reference frame and the $\alpha\beta$ reference frame.



- The time-response of the individual components of equivalent balanced $\alpha\beta$ and abc systems.



Equations

The following equation describes the Inverse Clarke transform computation:

$$\begin{bmatrix} f_a \\ f_b \\ f_c \end{bmatrix} = \begin{bmatrix} 1 & 0 & 1 \\ -\frac{1}{2} & \frac{\sqrt{3}}{2} & 1 \\ -\frac{1}{2} & -\frac{\sqrt{3}}{2} & 1 \end{bmatrix} \begin{bmatrix} f_\alpha \\ f_\beta \\ f_0 \end{bmatrix}$$

For balanced systems like motors, the zero sequence component calculation is always zero:

$$i_a + i_b + i_c = 0$$

Therefore, you can use only two current sensors in three-phase motor drives, where you can calculate the third phase as,

$$i_c = -(i_a + i_b)$$

By using these equations, the block implements the Inverse Clarke transform as,

$$\begin{bmatrix} f_a \\ f_b \\ f_c \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ -\frac{1}{2} & \frac{\sqrt{3}}{2} \\ -\frac{1}{2} & -\frac{\sqrt{3}}{2} \end{bmatrix} \begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix}$$

where:

- f_α and f_β are the balanced two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.
- f_0 is the zero component in the stationary $\alpha\beta$ reference frame.
- f_a , f_b , and f_c are the balanced three-phase components in the abc reference frame.

Ports

Input

α — Axis component

scalar

Alpha-axis component, α , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

β — Axis component

scalar

Beta-axis component, β , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

Output

a — Phase component

scalar

Component of the three-phase system in the abc reference frame.

Data Types: `single` | `double` | `fixed point`

b — Phase component

scalar

Component of the three-phase system in the abc reference frame.

Data Types: `single` | `double` | `fixed point`

c — Phase component

scalar

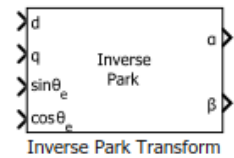
Component of the three-phase system in the abc reference frame.

Data Types: `single` | `double` | `fixed point`

Inverse Park Transform

Implement dq to $\alpha\beta$ transformation

Library: Motor Control Blockset / Controls / Math Transforms



Description

The Inverse Park Transform block computes the inverse Park transformation of the orthogonal direct and quadrature axes components in the rotating dq reference frame. You can configure the block to align either the d - or q -axis with the α -axis at time $t = 0$.

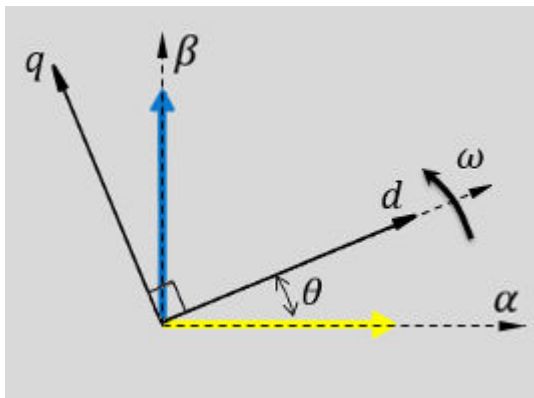
The block accepts the following inputs:

- d - q axes components in the rotating reference frame.
- Sine and cosine values of the corresponding angles of transformation.

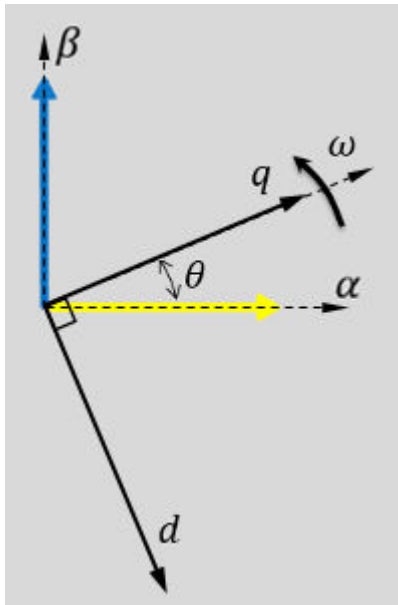
It outputs the two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.

The figures show a rotating dq reference frame and the α - β axes components in an $\alpha\beta$ reference frame for when:

- The d -axis aligns with the α -axis.



- The q -axis aligns with the α -axis.

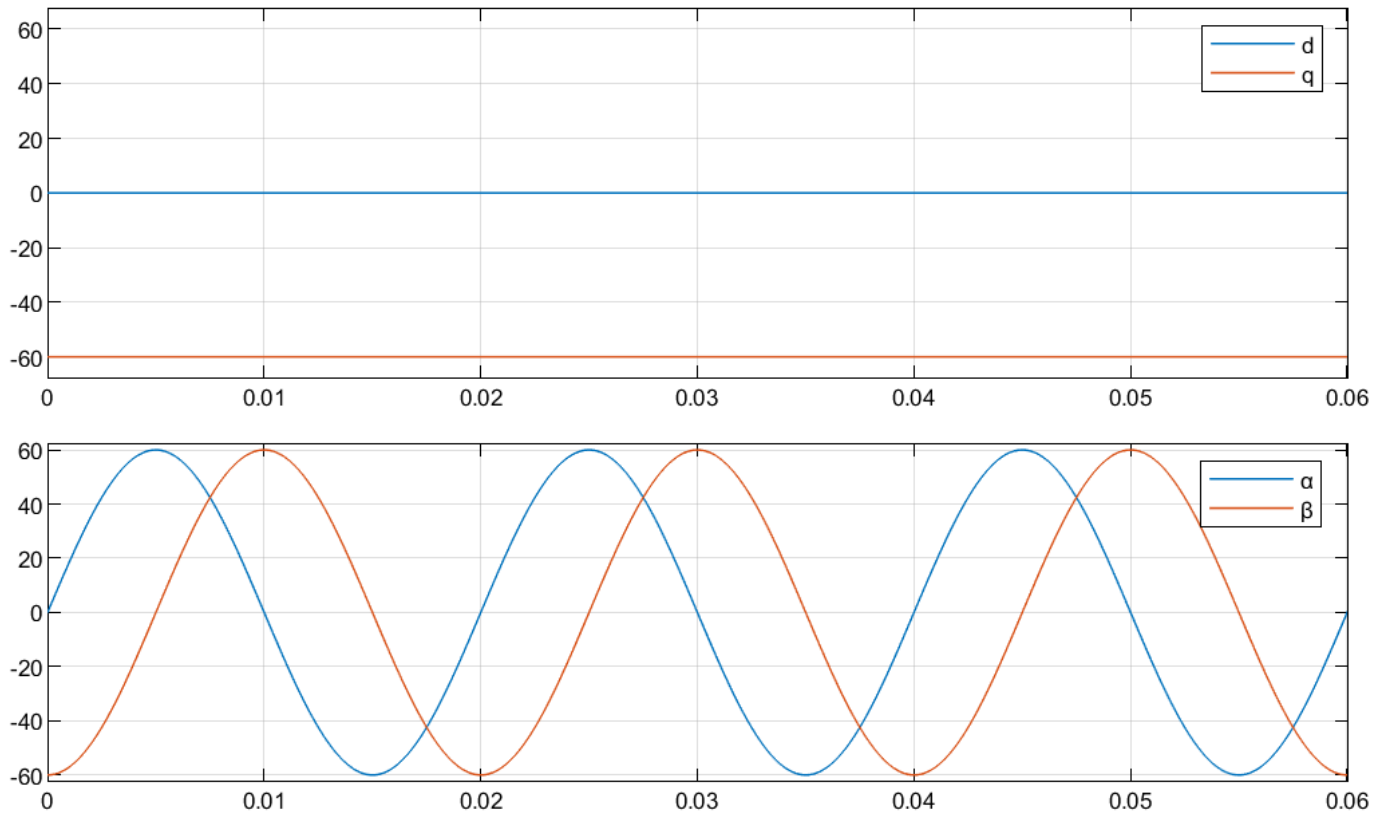


In both cases, the angle $\theta = \omega t$, where:

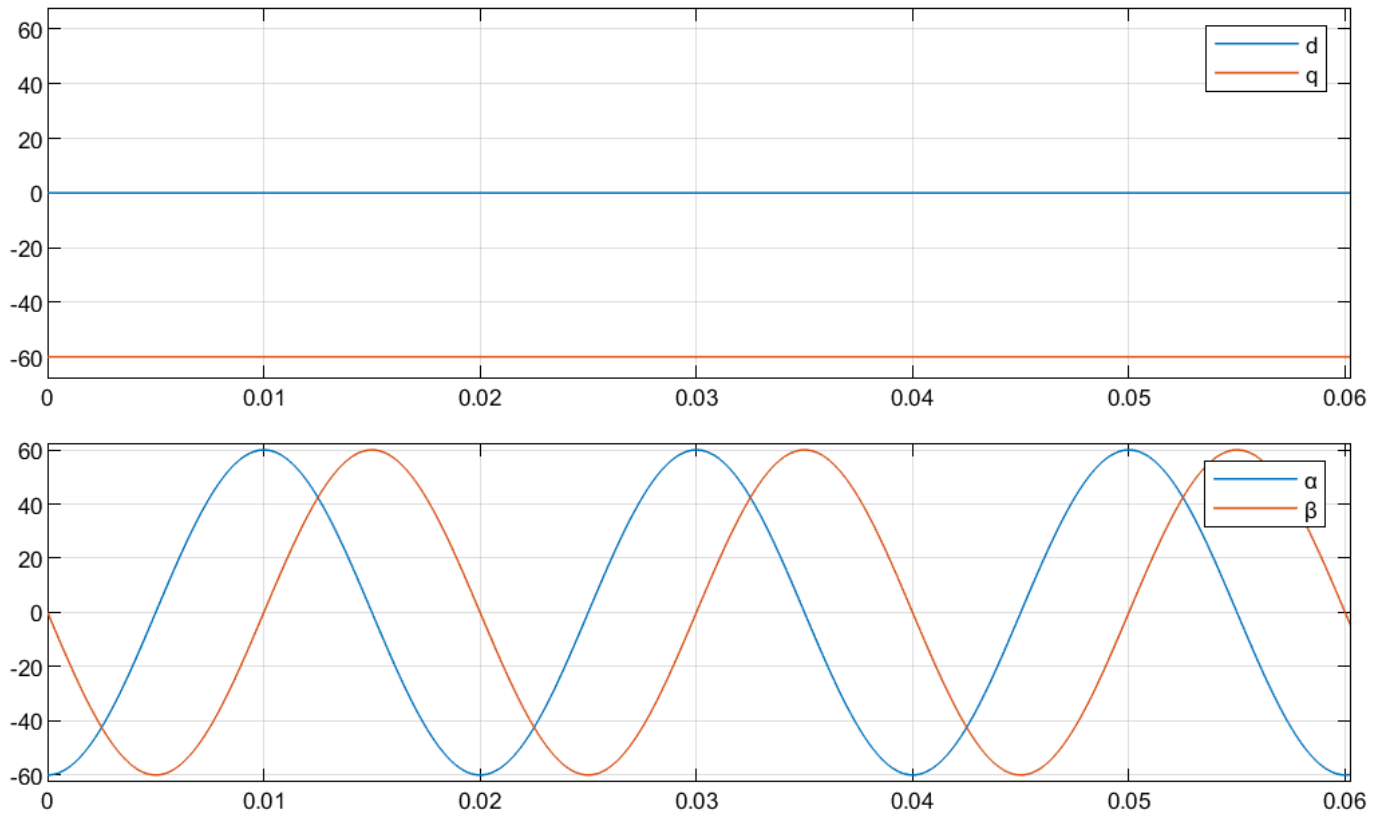
- θ is the angle between the α - and d -axes for the d -axis alignment or the angle between the α - and q -axes for the q -axis alignment. It indicates the angular position of the rotating dq reference frame with respect to the α -axis.
- ω is the rotational speed of the d - q reference frame.
- t is the time, in seconds, from the initial alignment.

The figures show the time-response of the individual components of the $\alpha\beta$ and dq reference frames when:

- The d -axis aligns with the α -axis.



- The q -axis aligns with the α -axis.



Equations

The following equations describe how the block implements inverse Park transformation.

- When the d -axis aligns with the α -axis.

$$\begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} f_d \\ f_q \end{bmatrix}$$

- When the q -axis aligns with the α -axis.

$$\begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix} = \begin{bmatrix} \sin\theta & \cos\theta \\ -\cos\theta & \sin\theta \end{bmatrix} \begin{bmatrix} f_d \\ f_q \end{bmatrix}$$

where:

- f_d and f_q are the direct and quadrature axis orthogonal components in the rotating dq reference frame.
- f_α and f_β are the two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.

Ports

Input

d – Axis component

scalar

Direct axis component, d , in the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

q – Axis component

scalar

Quadrature axis component, q , in the rotating dq reference frame.

Data Types: `single` | `double` | `fixed point`

sin θ_e – Sine value of rotational angle

scalar

Sine value of the angle of transformation, θ_e . θ_e is the angle between the rotating reference frame and the α -axis.

Data Types: `single` | `double` | `fixed point`

cos θ_e – Cosine value of rotational angle

scalar

Cosine value of the angle of transformation, θ_e . θ_e is the angle between the rotating reference frame and the α -axis.

Data Types: `single` | `double` | `fixed point`

Output

α – Axis component

scalar

Alpha-axis component, α , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

β – Axis component

scalar

Beta-axis component, β , in the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

Parameters

Alpha (phase-a) axis alignment – dq reference frame alignment

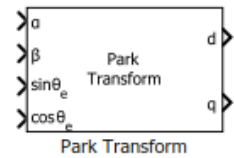
D-axis (default) | Q-axis

Align either the d - or q -axis of the rotating reference frame to the α -axis of the stationary reference frame.

Park Transform

Implement $\alpha\beta$ to dq transformation

Library: Motor Control Blockset / Controls / Math Transforms



Description

The Park Transform block computes the Park transformation of two-phase orthogonal components in a stationary $\alpha\beta$ reference frame.

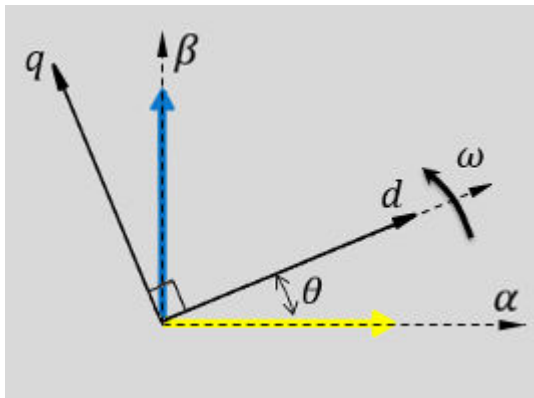
The block accepts the following inputs:

- α - β axes components in the stationary reference frame.
- Sine and cosine values of the corresponding angles of transformation.

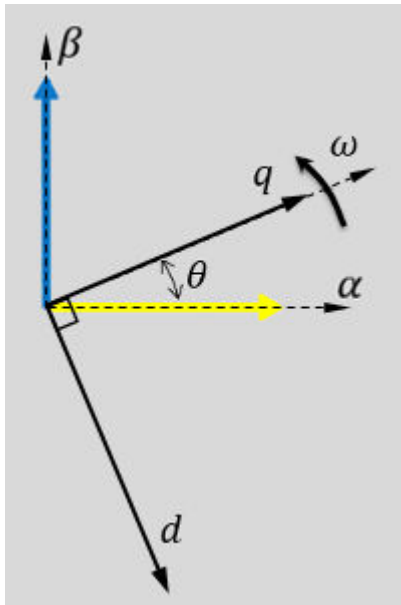
It outputs orthogonal direct and quadrature axis components in the rotating dq reference frame. You can configure the block to align either the d - or the q -axis with the α -axis at time $t = 0$.

The figures show the α - β axes components in an $\alpha\beta$ reference frame and a rotating dq reference frame for when:

- The d -axis aligns with the α -axis.



- The q -axis aligns with the α -axis.

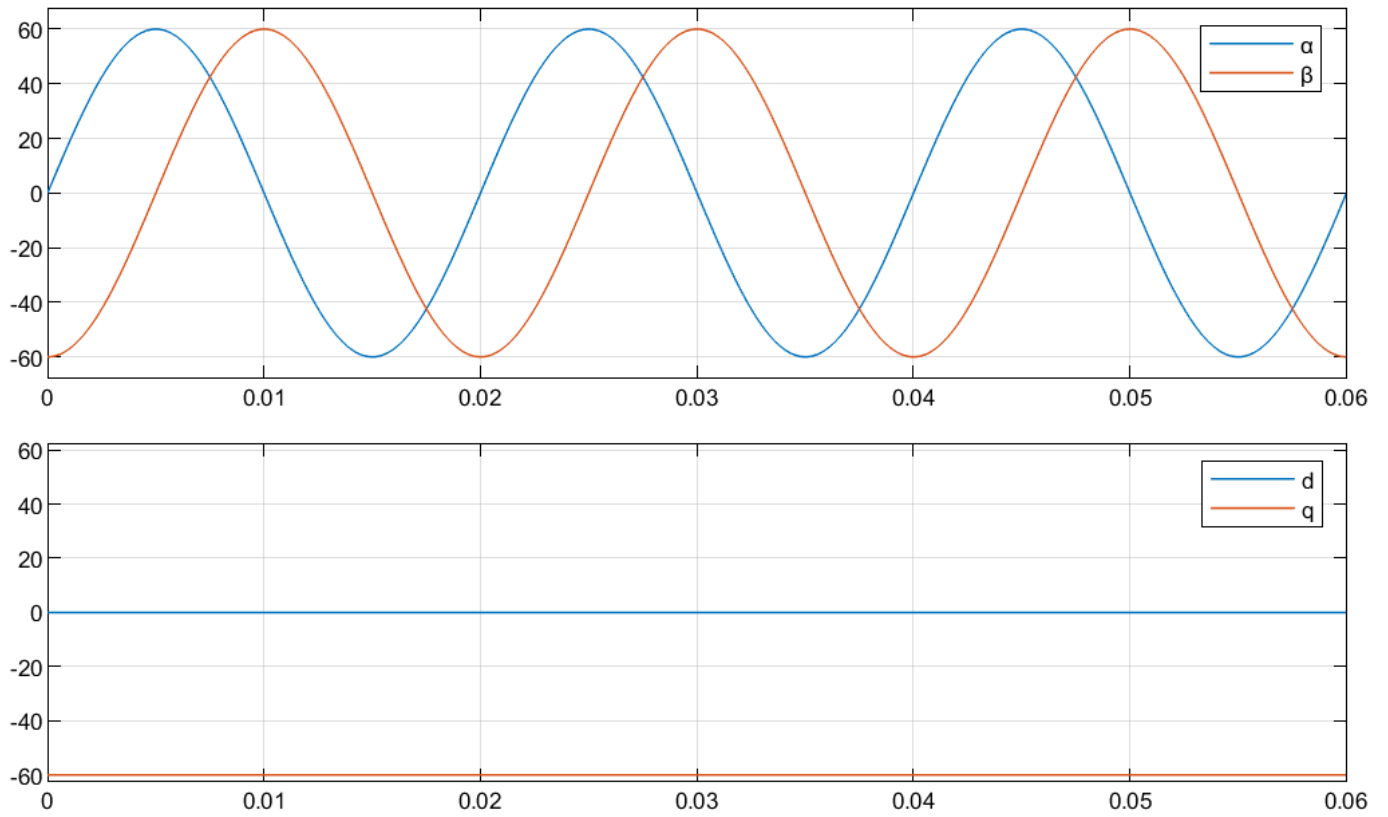


In both cases, the angle $\theta = \omega t$, where:

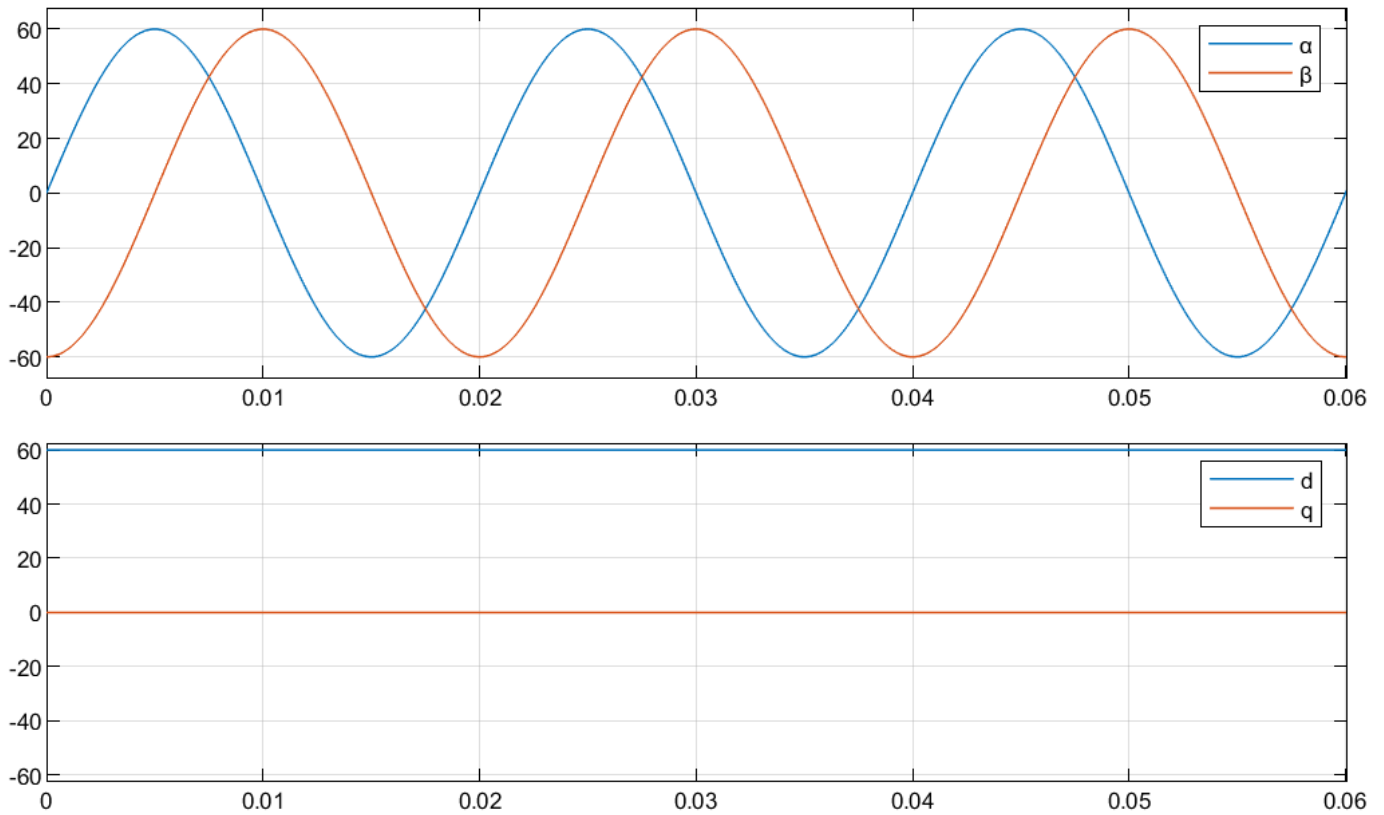
- θ is the angle between the α - and d -axes for the d -axis alignment or the angle between the α - and q -axes for the q -axis alignment. It indicates the angular position of the rotating dq reference frame with respect to the α -axis.
- ω is the rotational speed of the d - q reference frame.
- t is the time, in seconds, from the initial alignment.

The figures show the time-response of the individual components of the $\alpha\beta$ and dq reference frames when:

- The d -axis aligns with the α -axis.



- The q -axis aligns with the α -axis.



Equations

The following equations describe how the block implements Park transformation.

- When the d -axis aligns with the α -axis.

$$\begin{bmatrix} f_d \\ f_q \end{bmatrix} = \begin{bmatrix} \cos\theta & \sin\theta \\ -\sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix}$$

- When the q -axis aligns with the α -axis.

$$\begin{bmatrix} f_d \\ f_q \end{bmatrix} = \begin{bmatrix} \sin\theta & -\cos\theta \\ \cos\theta & \sin\theta \end{bmatrix} \begin{bmatrix} f_\alpha \\ f_\beta \end{bmatrix}$$

where:

- f_α and f_β are the two-phase orthogonal components in the stationary $\alpha\beta$ reference frame.
- f_d and f_q are the direct and quadrature axis orthogonal components in the rotating dq reference frame.

Ports

Input

α – Axis component

scalar

Alpha-axis component, α , in the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

β – Axis component

scalar

Beta-axis component, β , in the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

$\sin \theta_e$ – Sine value of rotational angle

scalar

Sine value of the angle of transformation, θ_e . θ_e is the angle between the rotating reference frame and the α -axis.

Data Types: single | double | fixed point

$\cos \theta_e$ – Cosine value of rotational angle

scalar

Cosine value of the angle of transformation, θ_e . θ_e is the angle between the rotating reference frame and the α -axis.

Data Types: single | double | fixed point

Output

d – Axis component

scalar

Direct axis component, d , in the rotating dq reference frame.

Data Types: single | double | fixed point

q – Axis component

scalar

Quadrature axis component, q , in the rotating dq reference frame.

Data Types: single | double | fixed point

Parameters

Alpha (phase-a) axis alignment – dq reference frame alignment

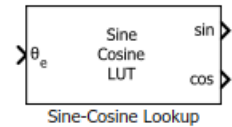
D-axis (default) | Q-axis

Align either the d - or q -axis of the rotating reference frame to the α -axis of the stationary reference frame.

Sine-Cosine Lookup

Implement sine and cosine functions using lookup table approach

Library: Motor Control Blockset / Controls / Math Transforms

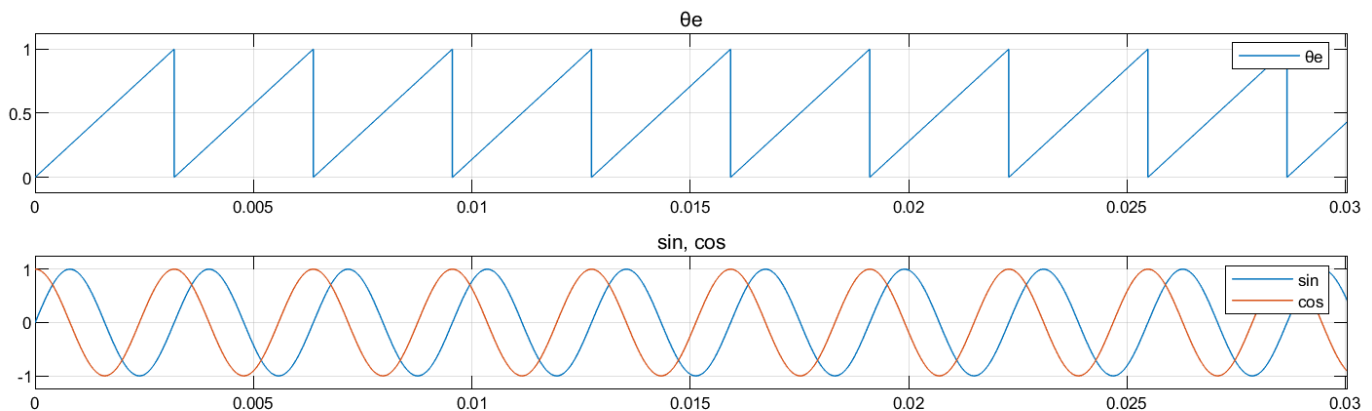


Description

The Sine-Cosine Lookup block implements sine and cosine functions using the specified position or phase input signal.

The block uses the lookup table approach for optimized code-execution. You can specify the number of lookup table points in the **Number of data points for lookup table** parameter.

This figure shows the input position and the generated sine and cosine output signals:



Ports

Input

θ_e — Reference voltage position

scalar

Position or phase value of the reference voltage signal specified as scalar in either per-unit, radians, or degrees.

Data Types: single | double | fixed point

Output

sin — Sine voltage waveform

scalar

Sine waveform output with a frequency that is identical to the position or phase signal (θ_e) frequency.

Data Types: single | double | fixed point

cos — Cosine voltage waveform

scalar

Cosine waveform output with a frequency that is identical to the position or phase signal (θ_e) frequency.

Data Types: single | double | fixed point

Parameters

Theta units — Unit of θ_e

Per-unit (default) | Radians | Degrees

Unit of the input reference voltage position.

Number of data points for lookup table — Size of lookup table array

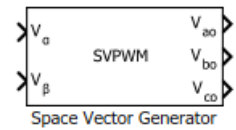
1024 (default) | scalar

Size of the lookup table array.

Space Vector Generator

Generate space vector modulation signals

Library: Motor Control Blockset / Controls / Math Transforms

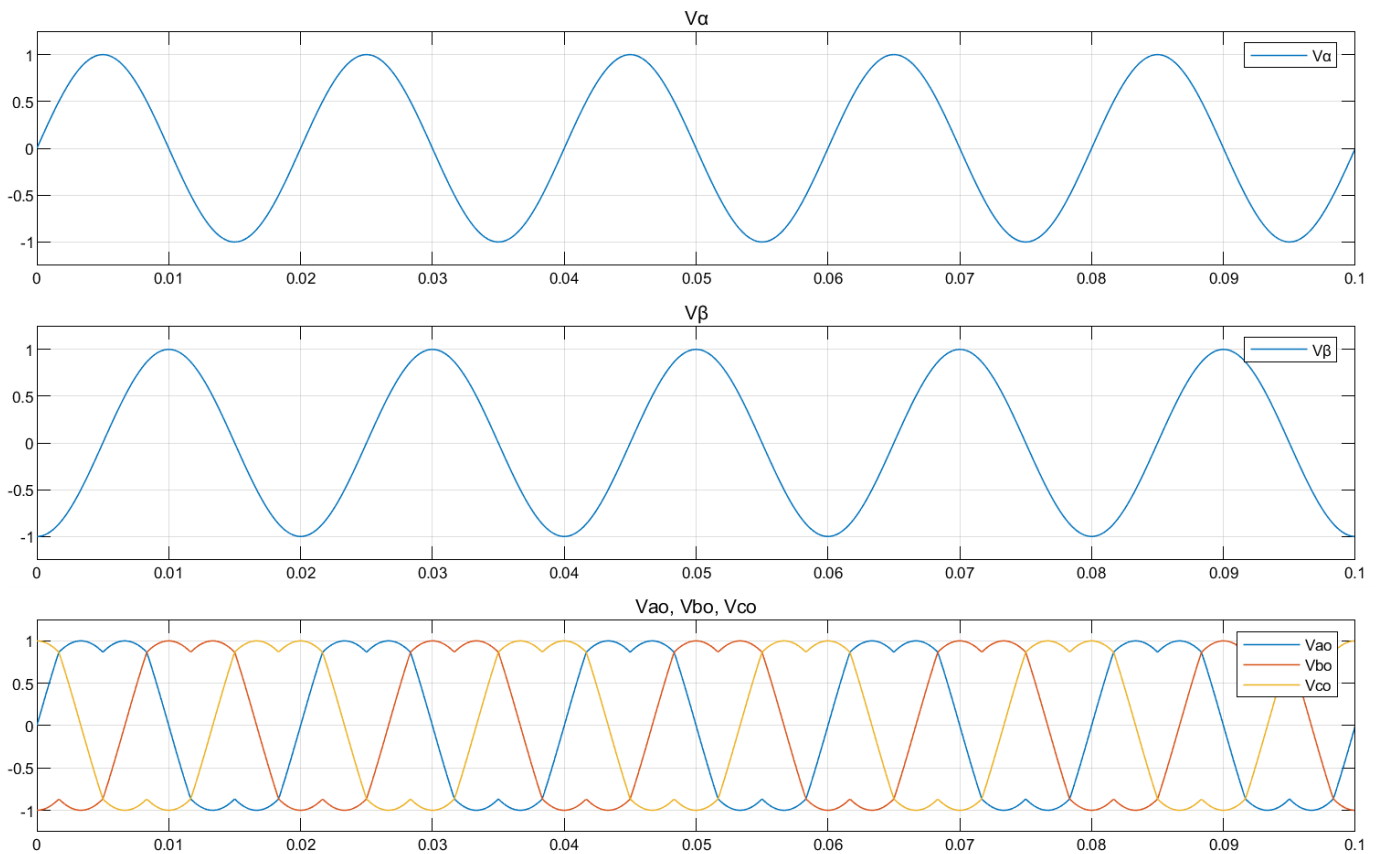


Description

The Space Vector Generator block generates space vector modulation voltage signals from stator reference voltages described by α - β voltage components.

The block uses a combination of inverse Clarke transformation and Space Vector Pulse Width Modulation (SVPWM) to compute modulated DC output voltages.

This figure shows the input reference voltages and the generated space vector modulation voltage signals:



Ports

Input

V_α — α -axis stator reference voltage component

scalar

Stator reference voltage component along α -axis of the $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

V_β — β -axis stator reference voltage component

scalar

Stator reference voltage component along β -axis of the $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

Output

V_{ao} — a -axis stator reference voltage component

scalar

Stator reference voltage component along a -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

V_{bo} — b -axis stator reference voltage component

scalar

Stator reference voltage component along b -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

V_{co} — c -axis stator reference voltage component

scalar

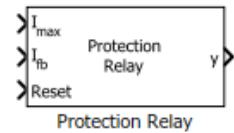
Stator reference voltage component along c -axis of the abc reference frame.

Data Types: `single` | `double` | `fixed point`

Protection Relay

Implement protection relay with definite minimum time (DMT) trip characteristics

Library: Motor Control Blockset / Protection and Diagnostics



Description

The Protection Relay block implements a protection relay for the hardware and the motor with definite minimum time (DMT) trip characteristics using the reference limit, feedback, and reset input signals. In the event of a fault, the block generates a latched fault signal that you can use to protect the hardware and the motor. You can reset the fault latch using an external reset signal.

Ports

Input

I_{max} — Upper limit for current

scalar

Upper limit for current in the feedback loop, so as to provide overcurrent protection. The block generates a latched fault signal when the current in the feedback loop (I_{fb}) exceeds this value.

Dependencies

To enable this port, set **Select Protection** to Overcurrent.

Data Types: single | double | fixed point

I_{fb} — Actual current in feedback loop

scalar

Actual current in the feedback loop at a given time.

Dependencies

To enable this port, set **Select Protection** to Overcurrent.

Data Types: single | double | fixed point

$\omega_{m \max}$ — Rotor speed limit for overspeed protection

scalar

Speed limit of the rotor (in RPM). The block generates a latched fault signal when the rotor speed (ω_{fb}) exceeds this value.

Dependencies

To enable this port, set **Select Protection** to Overspeed.

Data Types: single | double | fixed point

$\omega_{m\text{ fb}}$ — Actual rotor speed

scalar

Actual rotor speed at a given time.

Dependencies

To enable this port, set **Select Protection** to Overspeed.

Data Types: single | double | fixed point

 V_{max} — Upper voltage limit for overvoltage protection

scalar

Upper limit for voltage across the feedback loop. The block generates a latched fault signal when the voltage across the feedback loop (V_{fb}) exceeds this value.

Dependencies

To enable this port, set **Select Protection** to Overvoltage.

Data Types: single | double | fixed point

 V_{min} — Lower voltage limit for undervoltage protection

scalar

Lower limit for voltage across the feedback loop. The block generates a latched fault signal when the voltage across the feedback loop (V_{fb}) is less than this value.

Dependencies

To enable this port, set **Select Protection** to Undervoltage.

Data Types: single | double | fixed point

 V_{fb} — Actual voltage across feedback loop

scalar

Actual voltage across the feedback loop at a given time.

Dependencies

To enable this port, set **Select Protection** to either Overvoltage or Undervoltage.

Data Types: single | double | fixed point

Reset — External reset pulse

scalar

External pulse that resets the fault latch.

Data Types: single | double | fixed point

Output **y — Latched fault signal**

scalar

Latched fault signal that the block generates during the overcurrent, overspeed, overvoltage, and undervoltage conditions to protect the hardware and the motor.

Data Types: single | double | fixed point

Parameters

Select Protection — Type of protection relay

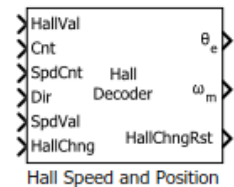
Overcurrent (default) | Overspeed | Overvoltage | Undervoltage

Available protection types to configure block behavior during the overcurrent, overspeed, overvoltage, and undervoltage conditions.

Hall Speed and Position

Compute speed and estimate position of rotor by using Hall sensors

Library: Motor Control Blockset / Sensor Decoders



Description

The Hall Speed and Position block computes the mechanical speed of the rotor by tracking changes in the Hall state. The block also estimates the electric position of the rotor by using the direction, Hall state, and external counter value inputs.

The block executes periodically after a fixed time interval that the controller algorithm defines.

Ports

Input

HallVal — Current Hall sensor output state

scalar

The Hall state at current time. For example, these are the possible valid Hall states (where the MSB represents the output of the first Hall sensor connected):

- 5 - (101)
- 4 - (100)
- 6 - (110)
- 2 - (010)
- 3 - (011)
- 1 - (001)

Data Types: single | double | fixed point

Cnt — External counter value

scalar

The external counter value that the block uses to determine the time elapsed between the Hall state change and block execution.

Data Types: single | double | fixed point

SpdCnt — Count at Hall state change

scalar

This value indicates the clock cycles (time) elapsed between two consecutive changes in the Hall state.

Data Types: single | double | fixed point

Dir — Rotor spin direction during current Hall state

scalar

The direction of the rotor spin (either +1 or -1 indicating positive or negative direction of rotation, respectively) during the current Hall state.

Data Types: single | double | fixed point

SpdVal — Validity of current and previous Hall states and speed calculation

scalar

The port value indicates Hall state validity. The value zero indicates that the current or previous Hall state is invalid and that the block cannot calculate speed and position.

The value one indicates that both the current and previous Hall states are valid and that the block can calculate speed and position.

Data Types: single | double | fixed point

HallChng — Value of Hall state change flag

scalar

The port value indicates Hall state change and block execution status. The value one indicates that the Hall state changed, but that the block execution is pending. The value zero indicates that the block has completed executing the last Hall state change.

Data Types: single | double | fixed point

Output

θ_e — Electrical position of rotor

scalar

The estimated electrical position of the rotor based on the **Expected hall sequence in positive direction** parameter and the *Direction*, *HallVal*, and *CounterValue* inputs.

Dependencies

To enable this port, set **Block output** to either *Position* or *Speed and position*.

Data Types: single | double | fixed point

ω_m — Mechanical speed of rotor

scalar

The mechanical speed of the rotor in revolutions per minute. The block calculates this value by tracking the Hall state changes.

The port returns zero if the *SpdVal* input is zero.

Dependencies

To enable this port, set **Block output** to either *Speed* or *Speed and position*.

Data Types: single | double | fixed point

HallChngRst — Resets Hall state change flag to zero

scalar

The port outputs a value of zero (sets the Hall state change flag to zero) indicating that the block has successfully executed speed and position computations for the last Hall state change.

Data Types: single | double | fixed point

Parameters**General****Block output — Select output ports**

Speed and position (default) | Speed | Position

Select the available block output ports as one of the following values:

- Speed and position
- Speed
- Position

Counter size — Size of external counter register

16 bits (default) | 8 bits | 32 bits

The register size of the external counter. The maximum counter value is $2^n - 1$, where n = counter size.

Counter clock frequency (Hz) — Clock frequency of external counter

90e6 (default) | scalar

The clock frequency of the external counter.

Block sample time (S) — Sample time after which block executes again

50e-6 (default) | scalar

The time between two consecutive instances of block execution.

Number of pole pairs — Number of pole pairs available in motor

8 (default) | scalar

Number of pole pairs available in the motor.

Minimum detectable speed (RPM) — Minimum speed that block can detect

20 (default) | scalar

The block does not calculate position for speed below this value.

Speed measurement interval — Interval over which block measures speed

Every 180 Degrees (default) | Every 60 Degrees

Rotor angular displacement that represents the interval at which the SpdCnt port value was calculated.

Speed unit — Unit of rotor angular speed output

Radians/sec (default) | Degrees/sec | RPM | Per unit

Unit of the angular velocity or mechanical speed (ω_m) output.

Dependencies

To enable this parameter, set **Block output** to either Speed or Speed and position.

Speed datatype — Data type of rotor angular speed output

single (default) | double | fixdt(1,16,0) | fixdt(1,16,2^0,0) | <data type expression>

Data type of the rotor angular speed output.

Dependencies

To enable this parameter, set **Block output** to either Speed or Speed and position.

Position

Expected hall sequence in positive direction — Sequence indicating positive direction

ABC (default) | CBA | Custom sequence

The Hall sensor sequence that represents the positive direction of rotor spin.

Dependencies

To enable this parameter, set **Block output** to either Position or Speed and position.

Sequence — Custom sequence indicating positive direction

[5,4,6,2,3,1] (default) | scalar

The custom sequence that you can enter to represent rotor spin in the positive direction.

Dependencies

To enable this parameter:

- Set **Block output** to either Position or Speed and position.
- Set **Expected hall sequence in positive direction** to Custom sequence.

Order of extrapolation of position — Indicates precision in position computation

1st Order (default) | 2nd Order

The 1st Order option is less accurate in computing position, but quick. The 2nd Order option is more accurate, but needs more computation time. These equations describe the options:

$$\theta_{1st\ Order} = \theta_{sector} + \omega t$$

$$\theta_{2nd\ Order} = \theta_{sector} + \omega t + \frac{1}{2}\alpha t^2$$

where:

$\theta_{1st\ Order}$ = Position computed by using 1st order extrapolation.

$\theta_{2nd\ Order}$ = Position computed by using 2nd order extrapolation.

θ_{sector} = Sector angle defined by the Hall sensor output.

ω = Angular velocity of the rotor.

α = Angular acceleration of the rotor.

t = Time spent in a sector.

Dependencies

To enable this parameter, set **Block output** to either Position or Speed and position.

Position unit – Unit of angular speed output

Radians (default) | Degrees | Per unit

Unit of angular speed output.

Dependencies

To enable this parameter, set **Block output** to either Position or Speed and position.

Position datatype – Data type of angular speed output

single (default) | double | fixdt(1,16,0) | fixdt(1,16,2^0,0) | <data type expression>

Data type of angular speed output.

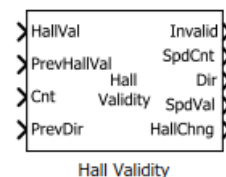
Dependencies

To enable this parameter, set **Block output** to either Position or Speed and position.

Hall Validity

Compute rotor spin direction and validity of Hall sensor sequence

Library: Motor Control Blockset / Sensor Decoders



Description

The Hall Validity block checks and validates every state of the Hall sensor output sequence. The block identifies the condition when one or more Hall sensors are in an invalid state.

The block executes when a Hall sensor output state (or Hall state) changes.

Ports

Input

HallVal — Current Hall sensor output state

scalar

The Hall state at current time. These are the possible input values (three-bit numbers where the MSB represents the output of the first Hall connected):

- 5 - (101)
- 4 - (100)
- 6 - (110)
- 2 - (010)
- 3 - (011)
- 1 - (001)

Note The output port `Invalid` indicates a bad hall sensor condition.

Data Types: `single` | `double` | `fixed point`

PrevHallVal — Previous Hall sensor output state

scalar

The Hall state prior to the current state.

Data Types: `single` | `double` | `fixed point`

Cnt — External counter value

scalar

The external counter value that the block uses to determine the time elapsed between the Hall state change and block execution.

Note The counter must reset when a Hall state changes.

Data Types: `single` | `double` | `fixed point`

PrevDir — Rotor spin direction during previous Hall state

scalar

The direction of rotor spin (either +1 or -1 indicating positive or negative direction of rotation, respectively) during the previous Hall state.

Data Types: `single` | `double` | `fixed point`

Output

Invalid — Indicator of Hall state validity

scalar

The indicator of Hall sensor validity during the current or previous Hall state. The block checks the validity of the sensors by comparing the values of the `HallVal` and `PrevHallVal` input port with the value of the **Expected hall sequence in positive direction** parameter. The port can output these values:

- 1 - (001) Indicates that one (or more) sensors are bad.
- 0 - (000) Indicates that all sensors are good.

Data Types: `single` | `double` | `fixed point`

SpdCnt — Count at Hall state change

scalar

The value of the `Cnt` input port when a Hall state changes.

Note The counter must reset when a Hall state changes. Therefore, this port indicates the number of counts during the previous Hall state.

Data Types: `single` | `double` | `fixed point`

Dir — Rotor spin direction during current Hall state

scalar

The direction of the rotor spin (either +1 or -1 indicating positive or negative direction of rotation, respectively) during the current Hall state. The block computes the direction by comparing the values of the `HallVal` and `PrevHallVal` input ports with the value of the **Expected hall sequence in positive direction** parameter.

Data Types: `single` | `double` | `fixed point`

SpdVal — Validity of current and previous Hall states and speed calculation

scalar

The port outputs zero when either one or both conditions occur:

- The block detects a bad hall sensor state (in either HallVal or PrevHallVal input port values).
- The block detects a change in the rotor spin direction.

The zero value indicates that you cannot calculate the valid speed for the current Hall state because the current value of SpdCnt is invalid. The port outputs the value one to indicate that a valid speed calculation is possible.

Data Types: single | double | fixed point

HallChng — Set flag to one, indicating Hall state change

scalar

The port outputs the value one (and sets the Hall state change flag to one) after the Hall state changes and the block has completed execution.

Data Types: single | double | fixed point

Parameters

Expected hall sequence in positive direction — Sequence indicating positive direction

ABC (default) | CBA | Custom sequence

The Hall sensor sequence that represents the positive direction of rotor spin.

Sequence — Custom sequence indicating positive direction

[5,4,6,2,3,1] (default) | scalar

The custom sequence that you can enter to represent rotor spin in the positive direction.

Dependencies

To enable this parameter, set **Expected hall sequence in positive direction** to Custom sequence.

Counter size — Size of external counter register

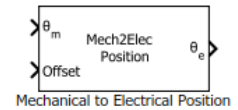
16 bits (default) | 8 bits | 32 bits

The register size of the external counter. The maximum counter value is $2^n - 1$, where n = counter size.

Mechanical to Electrical Position

Compute electrical position of rotor from mechanical position

Library: Motor Control Blockset / Sensor Decoders



Description

The Mechanical to Electrical Position block computes the electrical position of rotor by using its mechanical position and mechanical offset value.

Ports

Input

θ_m — Mechanical position of rotor

scalar

The mechanical position of rotor (as output by the rotor position sensor) in either radians (0 to 2π), degrees (0 to 360), or per unit (0 to 1).

Data Types: `single` | `double` | `fixed point`

Offset — Mechanical position offset

scalar

The deviation of the rotor's electrical zero from the mechanical zero position. Unit of offset is identical to the unit of the mechanical position input.

Dependencies

- To enable this port, set **Specify offset via** to `Input` port.
- Inputs must be of the same data type.

Data Types: `single` | `double` | `fixed point`

Output

θ_e — Electrical position of rotor

scalar

The electrical position of the rotor with a range that is identical to that of the mechanical position input. Data type of the electrical position is identical to that of the input.

Data Types: `single` | `double` | `fixed point`

Parameters

Number of pole pairs — Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Input mechanical angle unit – Unit of mechanical position of rotor

Per unit (default) | Radians | Degrees

Unit of the mechanical position of the rotor.

Offset input type – Method to specify offset

Input port (default) | Specify via dialog

The method you want to use to specify the mechanical position offset. Select `Input port` to enable and use the input port `Offset`. Select `Specify via dialog` to provide the offset value using the dialog box.

Mechanical offset – Value of mechanical position offset

0 (default) | scalar

The unit of the offset is identical to that of the unit of the mechanical position input.

Dependencies

To enable this parameter, set **Specify offset via** to `Specify via dialog`.

Input data type – Data type of input ports

single (default) | double | fixed point

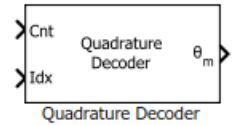
The data type that you want to use for the input ports.

Note The block runs faster, if you select either `fixdt(1,16,0)` or `fixdt(1,16,2^0,0)` input data type and provide fixed point values to the input ports.

Quadrature decoder

Compute position of quadrature encoder

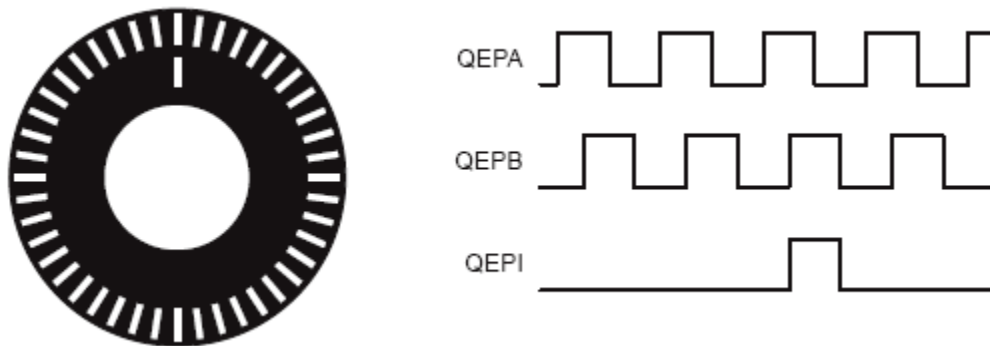
Library: Motor Control Blockset / Sensor Decoders



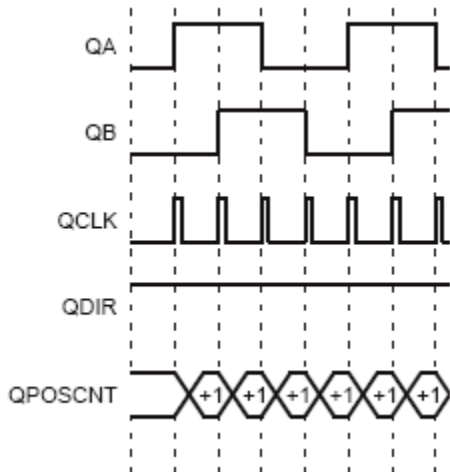
Description

The Quadrature Decoder block computes the position of the quadrature encoder. The block uses the current encoder counter value and encoder counter value at the previous index pulse to calculate the angular position of the quadrature encoder (and the rotor) in either degrees, radians, or per-unit.

This figure shows a quadrature encoder disk with two channels (QEPA and QEPB) and an index pulse (QEPI):



In this example, the timer driven by the QEP increments by four for each slit:



Equations

The block computes the angular position (in counts) of the quadrature encoder as:

When the encoder rotates in the clockwise direction:

- If $Idx \leq Cnt$,
 $Position\ count = (Cnt - Idx)$
- If $Idx > Cnt$ and the shaft rotation direction does not change,
 $Position\ count = (Cnt - Idx)$
- If $Idx > Cnt$ and the shaft rotation direction reverses,
 $Position\ count = Counts\ per\ revolution - (Idx - Cnt)$

When the encoder rotates in the anticlockwise direction:

- If $Idx \geq Cnt$,
 $Position\ count = Counts\ per\ revolution - (Idx - Cnt)$
- If $Idx < Cnt$ and the shaft rotation direction does not change,
 $Position\ count = Counts\ per\ revolution - (Idx - Cnt)$
- If $Idx < Cnt$ and the shaft rotation direction reverses,
 $Position\ count = (Cnt - Idx)$

When you clear the **External index count** parameter, the **Idx** pulse resets **Cnt** to zero, therefore:

$$Position\ count = Cnt$$

where:

- *Position count* is the angular position of the quadrature encoder in counts.
- *Counts per revolution* is the number of counts in one rotation cycle of the quadrature encoder.

The block computes the output θ_m as:

$$Position = 360 \times Position\ count / (Encoder\ slits \times Encoder\ counts\ per\ slit) \text{ (in degrees)}$$

$$Position = 2\pi \times Position\ count / (Encoder\ slits \times Encoder\ counts\ per\ slit) \text{ (in radians)}$$

$$Position = Cnt / (Encoder\ slits \times Encoder\ counts\ per\ slit) \text{ (in per-unit)}$$

Ports

Input

Cnt — Quadrature encoder counter value

scalar

Value that the quadrature encoder counter generates with respect to the slit-position. The port only accepts a scalar unsigned integer based on the **Counter size** parameter. For example, if you select **8 bits** for **Counter size**, the input data type must be uint8.

Data Types: uint8 | uint16 | uint32

Idx — Quadrature encoder counter value at last index pulse

scalar

Value that the quadrature encoder counter generated with respect to the slit-position at the time of the last index pulse. The port only accepts a scalar unsigned integer based on the **Counter size** parameter. For example, if you select 8 bits for **Counter size**, the input data type must be uint8.

Dependencies

To enable this port, select the **External index count** parameter.

Data Types: uint8 | uint16 | uint32

Note The input data types for both Cnt and Idx must be identical.

Output **θ_m — Angular position of quadrature encoder**

scalar

Angular position that the block computes based on the Cnt and Idx inputs.

Data Types: single | double | fixed point

Parameters**Encoder slits — Number of slits per phase**

1000 (default) | scalar

The number of slits available in each phase of the quadrature encoder.

Encoder counts per slit — Number of counts generated for every slit

4 (default) | 1 | 2

The number of counts that the quadrature encoder generates for every slit. A count indicates a slit position. For example, select 4 if you want the encoder to generate four counts corresponding to 00, 10, 11, and 01 slit positions or values.

Counter size — Size of quadrature encoder counter

16 bits (default) | 8 bits | 32 bits

Size of the quadrature encoder counter.

External index count — Enable Idx input port

on (default) | off

The block enables the Idx input port only if you select this parameter. The block expects that the Cnt input port value resets at the time of the Idx pulse.

Position unit — Unit of angular position output

Radians (default) | Degrees | Per unit

Unit of the angular position output.

Position data type – Data type of angular position output`single (default) | double | fixdt(1,16,0) | fixdt(1,16,2^0,0) | <data type expression>`

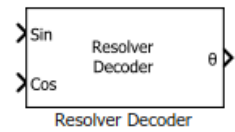
The data type for the angular position output.

Note The Quadrature Decoder block may occasionally display the warning message 'Wrap on overflow detected.'

Resolver Decoder

Compute electrical angular position of resolver

Library: Motor Control Blockset / Sensor Decoders



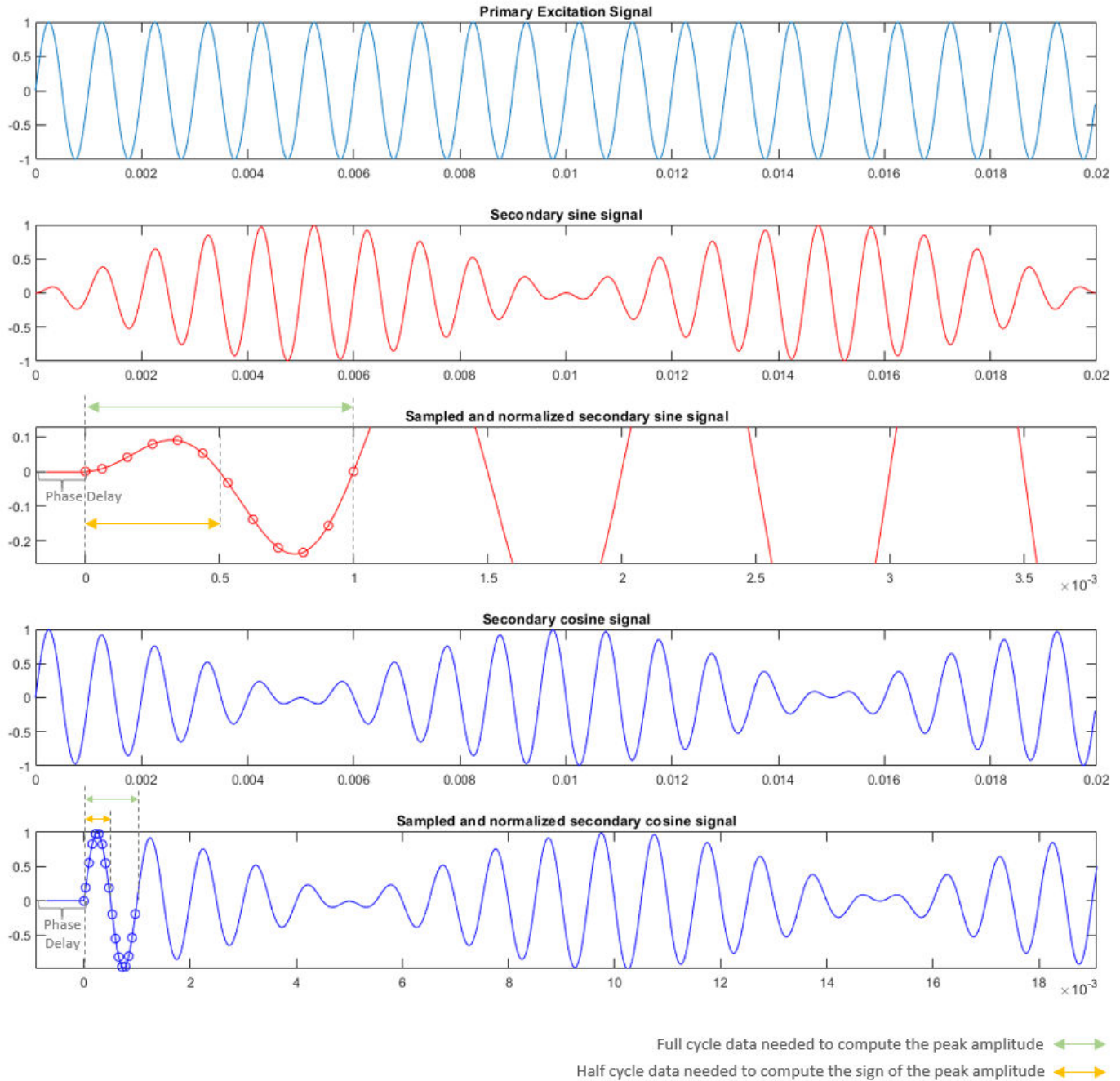
Description

The Resolver Decoder block calculates the electrical angular position of the resolver from the resolver sine and cosine output signals.

The resolver uses a primary sinusoidal excitation input signal to generate the modulated secondary sine and cosine waveforms.

You must normalize these waveforms (within the range of $[-1,1]$ and centered at 0) and sample them to obtain the secondary sine and cosine input signals of the Resolver Decoder block.

The block computes and outputs the resolver position in $[0, 2\pi]$ radians. The block can also add a phase delay to the sampled sine and cosine signals with respect to the excitation signal.



Note The block inputs should have identical amplitude and data types (either signed fixed or floating point).

Equations

The block computes the average, peak amplitude values, and the sign of the peak amplitude of a signal cycle as

$$\hat{A}_{average} = \frac{1}{n} \sum_{i=0}^{n-1} (|\hat{A}_i|)$$

$$\hat{A}_{peak} = \hat{A}_{average} \times \frac{\pi}{2}$$

$$\text{Sign of Peak} = \text{Sign of} \left[\sum_{i = \text{phase delay}}^{\frac{n}{2} - 1 + \text{phase delay}} \hat{A}_i \right]$$

where:

- $\hat{A}_{average}$ is the average amplitude value of a signal cycle
- n is the number of samples per excitation cycle
- \hat{A}_{peak} is the peak amplitude value of a signal cycle

The block computes the electrical angular position of the resolver as

$$\theta = \text{atan2} \frac{u_{\sin_peak}}{u_{\cos_peak}}$$

where:

- u_{\sin_peak} is the \hat{A}_{peak} of the secondary sine signal
- u_{\cos_peak} is the \hat{A}_{peak} of the secondary cosine signal
- θ is the electrical angular position of the resolver

Ports

Input

Sin — Sampled and normalized secondary sine signal

vector

Secondary sine waveform output from the resolver that is sampled and normalized within the range of [-1, 1] and centered at 0.

Data Types: single | double | fixed point

Cos — Sampled and normalized secondary cosine signal

vector

Secondary cosine waveform output from the resolver that is sampled and normalized within the range of [-1, 1] and centered at 0.

Data Types: single | double | fixed point

Output

θ — Resolver position

scalar

Electrical angular position of the resolver (and the rotor) in $[0, 2\pi]$ radians.

Data Types: `single` | `double` | `fixed point`

Parameters

Phase delay (electrical radians) – Phase delay for input signals

0.1746 (default) | scalar

The phase delay that the block must add to the Sin and Cos input port signals.

Number of samples per excitation signal – Samples per cycle of input signal

16 (default) | even scalar greater than zero

Number of samples available in one cycle of the Sin and Cos input port signals.

Output data type – Data type of resolver position output

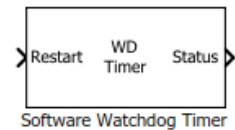
`single` (default) | `double` | `fixed point`

The data type of the resolver position output θ .

Software Watchdog Timer

Output true until counter reaches maximum count limit

Library: Motor Control Blockset / Sensor Decoders



Description

The Software Watchdog Timer block increments the counter value until either the block receives a Restart input pulse, or the count reaches the value of the **Maximum count** parameter.

On receiving the Restart pulse, the block restarts the counter and starts incrementing the counter value again when the Restart pulse falls.

The block maintains the true Status output until the counter value remains less than the value of **Maximum count** parameter. When the counter reaches **Maximum count**, the block stops the counter and turns the Status false.

Ports

Input

Restart — Pulse to restart watchdog timer counter

scalar

The pulse (true value) that restarts the watchdog timer counter. The counter resumes counting when the pulse falls (false value).

Data Types: `single` | `double` | `fixed point`

Output

Status — Watchdog timer status

scalar

The watchdog timer status indicated as one of the following:

- True indicates that the counter value is less than the value of the **Maximum count** parameter.
- False indicates that the counter value is equal to the value of the **Maximum count** parameter and the block has stopped the counter.

Data Types: `single` | `double` | `fixed point`

Parameters

Maximum count — Maximum limit of watchdog timer value

10 (default) | scalar

The maximum limit of the watchdog timer counter value that causes the block to stop the counter and turn the watchdog timer status to false.

Counter data type – Data type of Status output

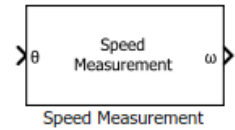
uint8 (default) | uint16 | uint32

The data type of the watchdog timer status output.

Speed Measurement

Compute speed from rotor angular position

Library: Motor Control Blockset / Sensor Decoders



Description

The Speed Measurement block calculates the angular speed from the angular position of the rotor by calculating the change in the angular position with respect to time.

Ports

Input

θ — Angular position of rotor

scalar

Angular position of the rotor specified in either radians, degrees, or per-unit.

Data Types: `single` | `double` | `fixed point`

Output

ω — Angular speed of rotor

scalar

Angular speed that the block computes based on the angular position input.

Data Types: `single` | `double` | `fixed point`

Parameters

Position unit — Unit of angular position

Radians (default) | Degrees | Per unit

Unit of the angular position θ .

Speed calculation criteria — Method of speed calculation

Maximum application speed (default) | Speed resolution | Time interval for speed calculation

The speed calculation method used in the block. The selected method determines the range of the rotor speed that the block can measure.

These parameters change values according to the **Speed calculation criteria** parameter:

Parameter name	Maximum application speed	Speed Resolution	Time interval for speed calculation
Delays for speed calculation (number of samples)	299	28	28
Maximum measurable speed (RPM)	1000	10344.8276	10713.2857
Measurable speed resolution (RPM)	4.6566e-07	4.9892e-06	4.9892e-06

Block sample time (S) – Sample time after which block executes again

100e-6 (default) | scalar

The fixed time interval (in seconds) between every two consecutive instances of block execution.

These parameters change values according to the **Block sample time (S)** parameter value:

- **Delays for speed calculation (number of samples)**
- **Maximum measurable speed (RPM)**
- **Measurable speed resolution (RPM)**

Maximum application speed (RPM) – Maximum measurable rotor speed

1000 (default) | scalar

The maximum rotor speed (in rotations per minute) that the block can measure.

These parameters change values according to the **Maximum application speed (RPM)** parameter value:

- **Delays for speed calculation (number of samples)**
- **Maximum measurable speed (RPM)**
- **Measurable speed resolution (RPM)**

Dependencies

To enable this parameter, set **Speed calculation criteria** to Maximum application speed.

Speed Resolution (RPM) – Minimum detectable value of change in angular position

5e-6 (default) | scalar

The minimum value of the θ input that the block can detect.

These parameters change values according to the **Speed Resolution (RPM)** parameter value:

- **Delays for speed calculation (number of samples)**
- **Maximum measurable speed (RPM)**
- **Measurable speed resolution (RPM)**

Delays for speed calculation (number of samples) – Number of angular position samples measured

299 or 28 (default) | scalar

The number of samples of the angular position input that the block measures to compute the average position value.

These parameters change values according to the **Delays for speed calculation (number of samples)** parameter value:

- **Maximum measurable speed (RPM)**
- **Measurable speed resolution (RPM)**

Dependencies

To enable this parameter, set **Speed calculation criteria** to Time interval for speed calculation.

Speed unit – Unit of angular speed output

RPM (default) | Degrees/Sec | Radians/Sec | Per unit based on maximum measurable speed | Per unit based on dialog

Unit of the angular speed output.

Speed data type – Data type of angular speed output

single (default) | double | fixed point

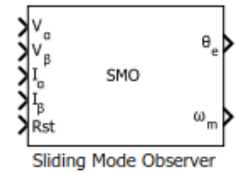
The data type of the angular speed output ω .

Note The Speed Measurement block may occasionally display the warning message 'Wrap on overflow detected.'

Sliding Mode Observer

Compute electrical position and mechanical speed of rotor

Library: Motor Control Blockset / Sensorless Estimators



Description

The Sliding Mode Observer block computes the electrical position and mechanical speed of a PMSM by using the per unit voltage and current values along the α - and β -axes of the stationary $\alpha\beta$ reference frame.

Equations

These equations describe the computation of the electrical position and mechanical speed by the block.

$$\frac{di_{\alpha\beta}}{dt} = \Phi i_{\alpha\beta} + \Gamma V_{\alpha\beta} - \Gamma e_{\alpha\beta}$$

$$i_{\alpha\beta} = [i_{\alpha} \ i_{\beta}]^T$$

$$V_{\alpha\beta} = [V_{\alpha} \ V_{\beta}]^T$$

$$e_{\alpha\beta} = [e_{\alpha} \ e_{\beta}]^T = \begin{bmatrix} -\psi\omega_e \sin\theta_e \\ \psi\omega_e \cos\theta_e \end{bmatrix}$$

$$\Phi = \begin{bmatrix} -\frac{R}{L} & 0 \\ 0 & -\frac{R}{L} \end{bmatrix}$$

$$\Gamma = \begin{bmatrix} \frac{1}{L} & 0 \\ 0 & \frac{1}{L} \end{bmatrix}$$

These equations describe the discrete-time sliding mode observer operation by using per-unit values:

$$\widehat{i}_{\alpha\beta(k+1)P.U} = A \widehat{i}_{\alpha\beta(k)P.U} + \frac{V_{rated}}{I_{rated}} B (v_{\alpha\beta(k)P.U} - \vartheta_{\alpha\beta(k)P.U})$$

$$\vartheta_{\alpha\beta(k+1)P.U} = \vartheta_{\alpha\beta(k)P.U} + 2\pi f_0 \times (\mathbf{Z}(I_{rated}(\widehat{i}_{\alpha\beta(k)P.U} - i_{\alpha\beta(k)P.U})) - \vartheta_{\alpha\beta(k)P.U})$$

$$A = e^{\Phi T_s}$$

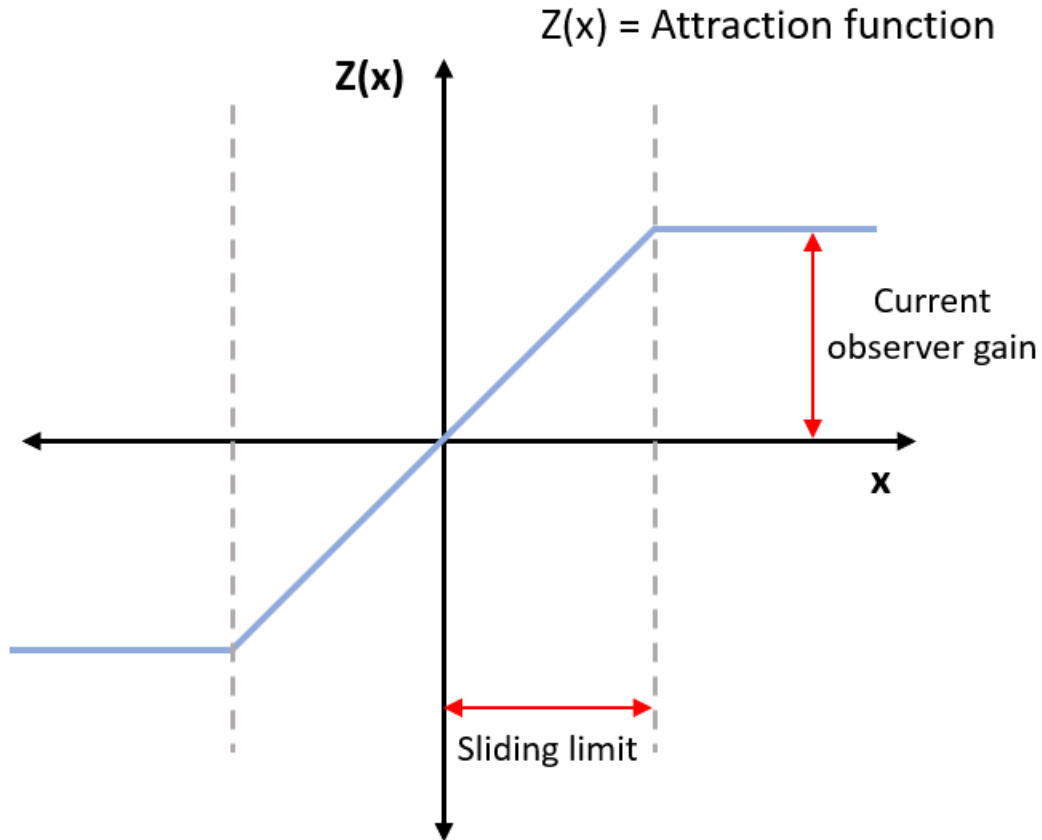
$$B = \int_0^{T_s} e^{\Phi\tau} d\tau$$

$$f_0 = \frac{F_0}{F_s}$$

$$F_s = \frac{1}{T_s}$$

where:

- e_α, i_α are the stator back EMF and current for the α axis.
- e_β, i_β are the stator back EMF and current for the β axis.
- v_α, v_β are the stator supply voltages.
- R is the stator resistance.
- L is the stator inductance.
- ψ is the flux linkage due to permanent magnet.
- ω_e is the electrical angular velocity.
- θ_e is the electrical position of the rotor.
- t is the time.
- T_s is the sampling period.
- k is the sample count.
- V_{rated} is the nominal voltage corresponding to 1 per-unit.
- I_{rated} is the nominal current corresponding to 1 per-unit.
- Z is the attraction function.



- f_0 is the cut-off frequency of the filter in cycles per sample.
- F_0 is the cut-off frequency in cycles per second.
- F_s is the sample frequency in samples per second.
- $\vartheta_{\alpha\beta(k)}$ is the estimated back EMF.

Ports

Input

V_α – α -axis voltage

scalar

Per-unit voltage component along the α -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

V_β – β -axis voltage

scalar

Per-unit voltage component along the β -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

I_α – α -axis current

scalar

Per-unit current component along the α -axis of the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

I_β — β -axis current

scalar

Per-unit current component along the β -axis of the stationary $\alpha\beta$ reference frame.

Data Types: `single` | `double` | `fixed point`

Rst — Reset the block

scalar

The pulse (true value) that resets and restarts the processing of the block algorithm.

Data Types: `single` | `double` | `fixed point`

Output

θ_e — Electrical position of PMSM

scalar

The estimated electrical position of the rotor.

Data Types: `single` | `double` | `fixed point`

ω_m — Mechanical speed of PMSM

scalar

The estimated mechanical speed of the rotor.

Data Types: `single` | `double` | `fixed point`

Parameters

Observer parameters

Current observer gain — Sliding mode observer gain for current

0.05 (default) | scalar

The attraction function gain.

Sliding surface limit — Maximum limit of sliding surface of SMO

2 (default) | scalar

The boundary layer limit of the attraction function's domain.

Position unit — Unit of position output

Radians (default) | Degrees | Per unit

Unit of the position output.

Position data type — Data type of position output

`single` (default) | `double` | `fixdt(1,16)` | `fixdt(1,16,0)` | `fixdt(1,16,2^0,0)` | <data type expression>

Data type of the position output.

Speed unit – Unit of speed output

RPM (default) | Degrees/sec | Radians/sec | Per unit

Unit of the speed output.

Speed data type – Data type of speed output

single (default) | double | fixdt(1,16) | fixdt(1,16,0) | fixdt(1,16,2^0,0) | <data type expression>

Data type of the speed output.

Block sample time (S) – Sample time after which block executes again

50e-6 (default) | scalar

The fixed time interval (in seconds) between every two consecutive instances of block execution.

Motor parameters**Stator resistance (ohm) – Resistance**

0.4836 (default) | scalar

Stator phase winding resistance (in ohm).

Stator inductance (H) – Inductance

1e-3 (default) | scalar

Stator phase winding inductance (in Henry).

Maximum application speed (RPM) – Maximum supported speed value

6000 (default) | scalar

Maximum value of speed (in RPM) that the block can support. For a speed beyond this value, the block generates incorrect outputs.

Number of pole pairs – Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Per unit reference stator voltage – Nominal voltage corresponding to one per unit

68 (default) | scalar

The maximum peak-to-peak line-to-line voltage applied to PMSM.

Per unit reference stator current – Nominal current corresponding to one per unit

10 (default) | scalar

The maximum peak-to-peak line-to-line current applied to PMSM.

Note The Sliding Mode Observer block may occasionally display the warning message 'Wrap on overflow detected.'

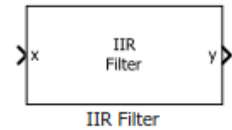
References

- [1] Y. Kung, N. V. Quynh, C. Huang and L. Huang, "Design and simulation of adaptive speed control for SMO-based sensorless PMSM drive," 2012 4th International Conference on Intelligent and Advanced Systems (ICIAS2012), Kuala Lumpur, 2012, pp. 439-444 (doi: 10.1109/ICIAS.2012.6306234)
- [2] Zhang Yan and V. Utkin, "Sliding mode observers for electric machines-an overview," IEEE 2002 28th Annual Conference of the Industrial Electronics Society. IECON 02, Sevilla, 2002, pp. 1842-1847 vol.3. (doi: 10.1109/IECON.2002.1185251)
- [3] T. Bernardes, V. F. Montagner, H. A. Gründling and H. Pinheiro, "Discrete-Time Sliding Mode Observer for Sensorless Vector Control of Permanent Magnet Synchronous Machine," in IEEE Transactions on Industrial Electronics, vol. 61, no. 4, pp. 1679-1691, April 2014 (doi: 10.1109/TIE.2013.2267700)
- [4] Z. Guo and S. K. Panda, "Design of a sliding mode observer for sensorless control of SPMSM operating at medium and high speeds," 2015 IEEE Symposium on Sensorless Control for Electrical Drives (SLED), Sydney, NSW, 2015, pp. 1-6. (doi: 10.1109/SLED.2015.7339255)

IIR Filter

Implement infinite impulse response (IIR) filter

Library: Motor Control Blockset / Signal Management



Description

The IIR Filter block implements a discrete infinite impulse response (IIR) low pass filter on the specified input signal. The block supports fixed point and floating point data types.

Equations

The block uses this equation to implement the IIR filter:

$$y(k) = a \times x_k + (1 - a) \times y_{k-1}$$

where:

- a is the filter coefficient in the range (0, 1].
- $y(k)$ is the filtered output value at time k .
- y_{k-1} is the filtered output value at time $k - 1$.
- x_k is the sampled input value at time k .

You can define a filter coefficient in the block parameter. A lower filter coefficient gives better filtering, but it increases the delay in the response time.

Ports

Input

x — Sampled input signal

scalar

Sampled values of the raw input signal in the time domain.

Data Types: `single` | `double` | `fixed point`

Output

y — Filtered output signal

scalar

Filtered output signal returned by the IIR Filter block in the time domain.

Data Types: `single` | `double` | `fixed point`

Parameters

Filter co-efficient – Filter coefficient of IIR block

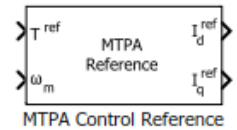
0.01 (default) | scalar in the range (0,1]

Filter coefficient of the IIR block.

MTPA Control Reference

Compute reference currents for Maximum Torque Per Ampere (MTPA) and field-weakening operation

Library: Motor Control Blockset / Controls / Control Reference



Description

The MTPA Control Reference block computes the d -axis and q -axis reference current values for MTPA and field-weakening operations. The computed reference current values results in efficient output for the Permanent Magnet Synchronous Motor (PMSM).

The block accepts the reference torque and feedback mechanical speed of the rotor and outputs the reference d and q axis phase current values for MTPA and field-weakening operations.

The block computes the reference current values by solving mathematical relationships. The calculations use SI unit system. When working with the Per-Unit (PU) system, the block converts PU input signals to SI units to perform computations, and converts them back to PU values at the output.

These equations describe the computation of reference d -axis and q -axis current values by the block:

Mathematical Model of PMSM

These model equations describe dynamics of PMSM in the rotor flux reference frame:

$$v_d = i_d R_s + \frac{d\lambda_d}{dt} - \omega_e L_q i_q$$

$$v_q = i_q R_s + \frac{d\lambda_q}{dt} + \omega_e L_d i_d + \omega_e \lambda_{pm}$$

$$\lambda_d = L_d i_d + \lambda_{pm}$$

$$\lambda_q = L_q i_q$$

$$T_e = \frac{3}{2} p (\lambda_{pm} i_q + (L_d - L_q) i_d i_q)$$

$$T_e - T_L = J \frac{d\omega_m}{dt} + B \omega_m$$

where:

- v_d is the d -axis voltage.
- v_q is the q -axis voltage.
- i_d is the d -axis current.
- i_q is the q -axis current.
- R_s is the stator phase winding resistance.

- λ_{pm} is the permanent magnet flux linkage.
- λ_d is the d -axis flux linkage.
- λ_q is the q -axis flux linkage.
- ω_e is the rotor electrical speed.
- ω_m is the rotor mechanical speed.
- L_d is the d -axis winding inductance.
- L_q is the q -axis winding inductance.
- T_e is the electromechanical torque produced by PMSM.
- T_L is the load torque.
- p is the number of motor pole pairs.
- J is the inertia coefficient.
- B is the friction coefficient.

Base Speed

These equations describe the computation of the motor base speed:

If $\omega_m \leq \omega_{base}$, i_d is zero. Therefore, we compute the d -axis and q -axis voltages as:

$$v_{d0} = -\omega_e L_q i_q$$

$$v_{q0} = i_q R_s + \omega_e \lambda_{pm}$$

$$v_{max} = \frac{v_{dc}}{\sqrt{3}} - R_s i_{max} \geq \sqrt{v_{d0}^2 + v_{q0}^2}$$

$$i_{max}^2 = i_d^2 + i_q^2$$

$$\omega_{base} = \frac{v_{max}}{\sqrt{(L_q i_q)^2 + (L_d i_d + \lambda_{pm})^2}}$$

where:

- ω_e is the rotor electrical speed.
- ω_{base} is the maximum motor speed outside field weakening region.
- i_d is the d -axis current.
- i_q is the q -axis current.
- v_{d0} is the d -axis voltage when i_d is zero.
- v_{q0} is the q -axis voltage when i_d is zero.
- L_d is the d -axis winding inductance.
- L_q is the q -axis winding inductance.
- R_s is the stator phase winding resistance.
- λ_{pm} is the permanent magnet flux linkage.

- v_d is the d -axis voltage.
- v_q is the q -axis voltage.
- v_{max} is the maximum voltage that the inverter can provide.
- v_{dc} is the DC bus voltage.
- i_{max} is the maximum current that the inverter can provide.

Surface PMSM

For a surface PMSM, you can achieve maximum torque by using zero d -axis current when the motor is below the base speed. For field-weakening operation, the reference d -axis current is computed by Constant-voltage-constant-power control (CVCP) algorithm defined by these equations:

If $\omega_m \leq \omega_{base}$:

- $i_{d_mtpa} = 0$
- $i_{q_mtpa} = \frac{T^{ref}}{\frac{3}{2} \cdot p \cdot \lambda_{pm}}$
- $i_{d_sat} = i_{d_mtpa} = 0$
- $i_{q_sat} = \text{sat}(i_{q_mtpa}, i_{max})$

If $\omega_m > \omega_{base}$:

- $i_{d_fw} = \frac{(\omega_{e_base} - \omega_e)\lambda_{pm}}{\omega_e L_d}$
- $i_{d_sat} = \max(i_{d_fw}, -i_{max})$
- $i_{q_fw} = \frac{T^{ref}}{\frac{3}{2} \cdot p \cdot \lambda_{pm}}$
- $i_{q_lim} = \sqrt{i_{max}^2 - i_{d_sat}^2}$
- $i_{q_sat} = \text{sat}(i_{q_fw}, i_{q_lim})$

The saturation function used to compute i_{q_sat} is described below:

If $i_{q_fw} < -i_{q_lim}$,

$$i_{q_sat} = -i_{q_lim}$$

If $i_{q_fw} > i_{q_lim}$,

$$i_{q_sat} = i_{q_lim}$$

If $-i_{q_lim} \leq i_{q_fw} \leq i_{q_lim}$,

$$i_{q_sat} = i_{q_fw}$$

The block outputs the following values:

$$I_d^{ref} = i_{d_sat}$$

$$I_q^{ref} = i_{q_sat}$$

where:

- ω_e is the rotor electrical speed.
- ω_m is the rotor mechanical speed.
- ω_{base} is the maximum motor speed outside field weakening region.
- ω_{e_base} is the maximum electrical speed of motor outside the field weakening region.
- i_{d_mtpa} is the d -axis phase current MTPA.
- i_{q_mtpa} is the q -axis phase current MTPA.
- T^{ref} is the reference torque (block input).
- p is the number of motor pole pairs.
- λ_{pm} is the permanent magnet flux linkage.
- i_{d_fw} is the d -axis field weakening current.
- i_{q_fw} is the q -axis field weakening current.
- L_d is the d -axis winding inductance.
- i_{max} is the maximum current that the inverter can provide.
- i_{d_sat} is the d -axis saturation current.
- i_{q_sat} is the q -axis saturation current.
- I_d^{ref} is the d -axis current component corresponding to the reference torque and reference speed (block inputs).
- I_q^{ref} is the q -axis current component corresponding to the reference torque and reference speed (block inputs).

Interior PMSM

For an interior PMSM, you can achieve maximum torque by computing the d -axis and q -axis reference currents from the torque equation.

$$i_{m_ref} = \frac{2 \cdot T^{ref}}{3 \cdot p \cdot \lambda_{pm}}$$

$$i_m = \max(i_{m_ref}, i_{max})$$

$$i_{d_mtpa} = \frac{\lambda_{pm}}{4(L_q - L_d)} - \sqrt{\frac{\lambda_{pm}^2}{16(L_q - L_d)^2} + \frac{i_m^2}{2}}$$

$$i_{q_mtpa} = \sqrt{i_m^2 - (i_{d_mtpa})^2}$$

$$v_{d0} = -\omega_e L_q i_q$$

$$v_{q0} = \omega_e (L_d i_d + \lambda_{pm})$$

$$v_{d0}^2 + v_{q0}^2 = v_{max}^2$$

$$(L_q i_q)^2 + (L_d i_d + \lambda_{pm})^2 \leq \frac{v_{max}^2}{\omega_e^2}$$

$$i_q = \sqrt{i_{max}^2 - i_d^2}$$

$$(L_d^2 - L_q^2) i_d^2 + 2\lambda_{pm} L_d i_d + \lambda_{pm}^2 + L_q^2 i_{max}^2 - \frac{v_{max}^2}{\omega_e^2} = 0$$

$$i_{d_fw} = \frac{-\lambda_{pm} L_d + \sqrt{(\lambda_{pm} L_d)^2 - (L_d^2 - L_q^2) \left(\lambda_{pm}^2 + L_q^2 i_{max}^2 - \frac{v_{max}^2}{\omega_e^2} \right)}}{(L_d^2 - L_q^2)}$$

$$i_{q_fw} = \sqrt{i_{max}^2 - i_{d_fw}^2}$$

If $\omega_m \leq \omega_{base}$,

$$I_d^{ref} = i_{d_mtpa}$$

$$I_q^{ref} = i_{q_mtpa}$$

If $\omega_m > \omega_{base}$,

$$I_d^{ref} = \max(i_{d_fw}, -i_{max})$$

$$i_{q_fw} = \sqrt{i_{max}^2 - i_{d_fw}^2}$$

If $i_{q_fw} < i_m$,

$$I_q^{ref} = i_{q_fw}$$

If $i_{q_fw} \geq i_m$,

$$I_q^{ref} = i_m$$

For negative reference torque values, the sign of i_m and I_q^{ref} are updated and equations are modified accordingly.

where:

- i_{m_ref} is the estimated maximum current to produce the reference torque.
- i_m is the saturated value of estimated maximum current.
- i_{d_max} is the maximum permissible d -axis current.
- i_{q_max} is the maximum permissible q -axis current.
- T^{ref} is the reference torque (block input).
- I_d^{ref} is the d -axis current component corresponding to the reference torque and reference speed (block inputs).

- I_q^{ref} is the q -axis current component corresponding to the reference torque and reference speed (block inputs).
- p is the number of motor pole pairs.
- λ_{pm} is the permanent magnet flux linkage.
- i_{d_mtpa} is the d -axis phase current MTPA.
- i_{q_mtpa} is the q -axis phase current MTPA.
- L_d is the d -axis winding inductance.
- L_q is the q -axis winding inductance.
- i_{max} is the maximum current that the inverter can provide.
- v_{max} is the maximum voltage that the inverter can provide.
- v_{d0} is the d -axis voltage when i_d is zero.
- v_{q0} is the q -axis voltage when i_d is zero.
- ω_e is the rotor electrical speed.
- i_d is the d -axis current.
- i_q is the q -axis current.
- i_{d_fw} is the d -axis field weakening current.
- i_{q_fw} is the q -axis field weakening current.
- ω_{base} is the maximum motor speed outside the field weakening region.

Ports

Input

T^{ref} — Reference torque value

scalar

Reference torque input value for which the block computes the reference current.

Data Types: single | double | fixed point

ω_m — Reference feedback speed

scalar

Reference mechanical speed value for which the block computes the reference current.

Data Types: single | double | fixed point

Output

I_d^{ref} — Reference d -axis current

scalar

Reference d -axis phase current that can efficiently generate the input torque and speed values.

Data Types: single | double | fixed point

I_q^{ref} — Reference q -axis current

scalar

Reference q -axis phase current that can efficiently generate the input torque and speed values.

Data Types: single | double | fixed point

Parameters**Type of motor — Type of PMSM based on location of permanent magnets**

Interior PMSM (default) | Surface PMSM

Type of PMSM based on the location of the permanent magnets.

Number of pole pairs — Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Stator resistance per phase (Ohm) — Resistance of stator phase winding (ohms)

0.36 (default) | scalar

Resistance of the stator phase winding (ohms).

DependenciesTo enable this parameter, set **Type of motor** to Interior PMSM.**Stator d -axis inductance (H) — d -axis stator winding inductance**

0.2e-3 (default) | scalar

Stator winding inductance (henry) along the d -axis of the rotating dq reference frame.**Stator q -axis inductance (H) — q -axis stator winding inductance**

0.4e-3 (default) | scalar

Stator winding inductance (henry) along the q -axis of the rotating dq reference frame.**Dependencies**To enable this parameter, set **Type of motor** to Interior PMSM.**Permanent magnet flux linkage (Wb) — Magnetic flux linkage of rotor's permanent magnets**

6.4e-3 (default) | scalar

Magnetic flux linkage between the stator windings and the rotor's permanent magnets (weber).

Max current (A) — Maximum phase current limit for motor (amperes)

7.1 (default) | scalar

Maximum phase current limit for the motor (amperes).

DC voltage (V) — DC bus voltage (volts)

24 (default) | scalar

DC bus voltage (volts)

Dependencies

To enable this parameter, set **Type of motor** to Interior PMSM.

Input signal units – Unit of block input values

Per-Unit (PU) (default) | SI Units

Unit of the block input values.

Base speed (rpm) – Base speed of motor (rpm)

3182 (default) | scalar

Speed of the motor at the rated voltage and rated current outside the field weakening region.

Base current (A) – Base current for per-unit conversion (amperes)

19.3 (default) | scalar

Current corresponding to 1 per-unit. We recommend you to use the maximum current detected by Analog to Digital Converter (ADC) as the base current.

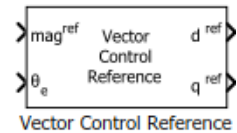
Dependencies

To enable this parameter, set **Input signal units** to Per-Unit (PU).

Vector Control Reference

Compute d and q axis components of a reference vector

Library: Motor Control Blockset / Controls / Control Reference



Description

The Vector Control Reference block calculates the d -axis and q -axis components of the reference voltage, current, or flux vector that you provide as an input to the block.

The block accepts magnitude and position of the reference vector as inputs. The block outputs the reference vector components along the direct and quadrature axes of the rotating dq reference frame.

Equations

The block uses the following equations to compute the d -axis and q -axis vector component outputs.

$$d^{ref} = mag^{ref} \times \cos\theta_e$$

$$q^{ref} = mag^{ref} \times \sin\theta_e$$

where:

- d^{ref} is the d -axis component of the reference vector.
- q^{ref} is the q -axis component of the reference vector.
- mag^{ref} is the magnitude of the reference vector.
- θ_e is the electrical position of the reference vector.

Ports

Input

mag^{ref} — Magnitude of reference vector

scalar

Magnitude of the reference voltage, current, or flux vector that you provide as an input to the block.

Data Types: single | double | fixed point

θ_e — Electrical position of reference vector

scalar

Electrical position of the reference voltage, current, or flux vector that you provide as an input to the block.

Data Types: single | double | fixed point

Output

d^{ref} — d -axis component of reference vector

scalar

Reference voltage, current, or flux vector component along the direct axis of the rotating dq reference frame.

Data Types: single | double | fixed point

q^{ref} — q -axis component of reference vector

scalar

Reference voltage, current, or flux vector component along the quadrature axis of the rotating dq reference frame.

Data Types: single | double | fixed point

Parameters

Alpha (phase- a) axis alignment — dq reference frame alignment

D-axis (default) | Q-axis

Align either the d - or q -axis of the rotating reference frame to the α -axis of the stationary reference frame.

Theta units — Unit of input position value

Per-unit (default) | Radians | Degrees

Unit of the input electrical position of the reference voltage, current, or flux vector.

Number of data points for trigonometric lookup table — Size of lookup table array

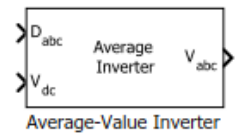
1024 (default) | scalar

Size of the lookup table array.

Average Value Inverter

Compute three-phase AC voltage from inverter DC voltage

Library: Motor Control Blockset / Electrical Systems / Inverters



Description

The Average Value Inverter block models an average-value and full-wave inverter. It computes the three-phase AC voltage output from inverter DC voltage by using the duty cycle information.

Equations

The following equations describe the computation of the three-phase AC voltage by the block.

$$D_0 = \frac{(D_a + D_b + D_c)}{3}$$

$$V_a = V_{dc} \times (D_a - D_0)$$

$$V_b = V_{dc} \times (D_b - D_0)$$

$$V_c = V_{dc} \times (D_c - D_0)$$

where:

- D_a , D_b , and D_c are the modulation indices ranging between 0 and 1.
- V_{dc} is the DC bus voltage of the inverter (Volts).
- V_a , V_b , and V_c are the output three-phase voltages (Volts).

Ports

Input

D_{abc} — Duty cycle for three phase voltage

scalar

Normalized duty cycle [0, 1] for the three-phase voltage supply that runs the motor.

Data Types: `single` | `double` | `fixed point`

V_{dc} — Inverter DC voltage

scalar

DC bus voltage input to the inverter.

Data Types: `single` | `double` | `fixed point` | `uint8` | `uint16` | `uint32`

Output

V_{abc} — Three-phase voltage output

scalar

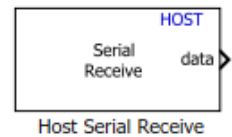
Three-phase voltage (Volts) corresponding to the input duty cycle that runs the motor.

Data Types: `single` | `double` | `fixed point`

Host Serial Receive

Configure host-side serial communications interface to receive data from serial port

Library: Motor Control Blockset / Protection and Diagnostics



Description

The Host Serial Receive block specifies the configuration of the data that it receives from the target hardware.

The data package that the block receives is limited to 16 bytes of ASCII characters, including package headers and terminators. Calculate the size of a package by including the package header, or terminator, or both, and the data size. The following table shows the number of bytes in each data type.

Data Type	Byte Count
single	4 bytes
int8 and uint8	1 byte
int16 and uint16	2 bytes
int32 and uint32	4 bytes

For example, if your data package has a package header 'S' (1 byte) and package terminator 'E' (1 byte), that leaves 14 bytes for the actual data. If your data is of type int8, there is space in the data package for 14 int8s. If your data is of type uint16, there is space in the data package for 7 uint16s. If your data is of type int32, there is space in the data package for only 3 int32s, with 2 bytes left over. Even though you could fit two int8s or one uint16 in the remaining space, you may not, because you cannot mix data types in the same package.

The number of data types that can fit into a data package determine the data size. In the preceding example, data size is 14 for int8 and 7 for uint16. When the data size exceeds 16 bytes, unexpected behavior, including run-time errors may occur.

Ports

Output

data — Port outputs received data

scalar

A First In, First Out (FIFO) buffer receives the data. At every time step, the data port outputs the requested values from the buffer.

Data Types: single | int8 | uint8 | int16 | uint16 | int32 | uint32

status — Transaction status

scalar

The status of the transaction. The status can be one of the following values:

- 0 - No errors
- 1 - A time-out occurred when the block was waiting to receive data
- 2 - There is an error in the received data (checksum error)
- 3 - SCI parity error flag — Occurs when a character is received with a mismatch
- 4 - SCI framing error flag — Occurs when an expected stop bit is not found

Dependencies

To enable this port, select the **Output receiving status** parameter.

Data Types: uint16

Parameters

Serial Connection — Serial port used for receiving data

Serial 1 (default) | Serial 2 | Serial 3 | Serial 4

Specifies a serial port that you want to use for receiving communication from the target hardware. Select an available serial port from the list. You can configure the selected port using the Host Serial Setup block. If you do not configure a serial port, the block prompts you to do so. Each Host Serial Receive block must have a configured serial port. If you use multiple ports in your simulation, you must configure each port separately.

Additional package header — Package header data

'S' (default) | scalar

Specifies the data located at the front of the received data package, which is not part of the data being received, and generally indicates start of data. The additional package header must be an ASCII value. You can use text or a number (0-255). You must put single quotes around the text that you enter in this field, but the quotes are not received and they are not included in the total byte count.

Additional package terminator — Package terminator data

'E' (default) | scalar

Specifies the data located at the end of the received data package, which is not part of the data being received, and generally indicates end of data. The additional package terminator must be an ASCII value. You can use text or a number (0-255). You must put single quotes around text entered in this field, but the quotes are not received and they are not included in the total byte count.

Data type — Output data type

single (default) | int8 | uint8 | int16 | uint16 | int32 | uint32

Specifies the data type of the block output.

Data size — Output data size

1 (default) | scalar | matrix

Specifies the output data size, or the number of values that should be read at every simulation time step.

Initial output – Default block output value

0 (default) | scalar

Specifies the initial or default output value of the block. This value is used, for example, if a connection time-out occurs and the **Action taken when connection times out** parameter is set to Output the last received value, but nothing is received yet.

Action taken when connection times out – Action taken by block when connection times out

Output the last received value (default) | Output custom value | Error

Specifies what to output if a connection time-out occurs.

- **Output the last received value** - The block outputs the value it received at the preceding time step when it does not receive data at current time step. If the block did not receive a value previously, it outputs the **Initial output** parameter value.
- **Output custom value** - The block outputs a user-defined value when it does not receive data at current time step. Use the **Output value when connection times out** parameter to define a custom value.
- **Error** - The block outputs an error when it does not receive the current data.

Output value when connection times out – Custom value output when the connection times out

0 (default) | scalar

Specifies a custom value that the block outputs when a connection time-out occurs.

Dependencies

To enable this parameter, set **Action taken when connection times out** to either Output custom value or Error.

Sample time – Custom

-1 (default) | scalar

Determines how often the Host Serial Receive block is called (in seconds). When you set this value to -1, the model inherits the sample time value of the model. To execute this block asynchronously, set **Sample Time** to -1.

Output receiving status – Enable the status output port

off (default) | on

Select this parameter to enable the status output port that provides the status of the transaction. If you clear this parameter, the block hides the status port.

Enable blocking mode – Block simulation while receiving data

on (default) | off

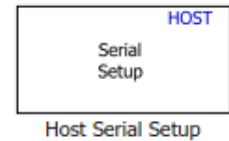
Select this parameter to block the simulation while receiving data. Clear this parameter if you do not want the read operation to block the simulation.

If you enable blocking mode, the model blocks the simulation while it is waiting to receive the requested data. When you do not enable blocking mode, the simulation runs continuously.

Host Serial Setup

Configure COM ports for the host-side Host Serial Receive and Host Serial Transmit blocks

Library: Motor Control Blockset / Protection and Diagnostics



Description

The Host Serial Setup block is a stand-alone block that standardizes the COM port settings used by the Host Serial Receive and Host Serial Transmit blocks.

Setting the COM port configurations globally by using the Host Serial Setup block avoids conflicts (for example, the Host Serial Transmit block cannot use COM1 with settings different than those the COM1 settings used by the Host Serial Receive block). You need to set configurations only once for each COM port.

Parameters

Port name — Port that you want to configure

'Please_select_a_port' (default) | 'COM3'

Select an available serial port that you want to configure. By default no port is selected and this field displays 'Please_select_a_port'. Use a configured port in the Host Serial Transmit and Host Serial Receive blocks. Both transmit and receive blocks must have a configured serial configuration. If you use multiple serial ports in your simulation, you must configure each port using a separate serial setup block.

Baud rate — Baud rate for the serial communication

115200 (default) | scalar

Enter the rate at which the model transmits the bits through the serial interface.

Number of stop bits — Number of stop bits

1 (default) | 2

Enter the number of bits that the model uses to indicate the end of a byte.

Parity mode — Method used to check parity bits

none (default) | odd | even

Specify how you want to check parity bits in the data bits that the model transmits through the serial port.

- none - Model does not perform parity check.
- odd - Model sets the parity bit to 0 if the number of ones in a given set of bits is even.
- even - Model sets the parity bit to 1 if the number of ones in a given set of bits is odd.

Timeout — Time interval before a one-way communication times out

1.0 (default) | scalar

Enter values greater than or equal to zero (seconds). When the COM port involved is using the protocol mode, this value indicates how long the transmitting side waits for an acknowledgement from the receiving side or how long the receiving side waits for data.

The system displays a warning message if the time-out exceeds, every n number of seconds, where n is the **Timeout** value.

Byte order – Byte order for the serial communication

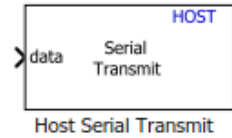
LittleEndian (default) | BigEndian

Specify the byte order as either `LittleEndian` or `BigEndian`. If byte order is `LittleEndian`, the model stores the first byte in the first memory address. If byte order is `BigEndian`, the model stores the last byte in the first memory address. You should configure the byte order to an appropriate value for your model before performing a read or write operation.

Host Serial Transmit

Configure host-side serial communications interface to transmit data to serial port

Library: Motor Control Blockset / Protection and Diagnostics



Description

The Host Serial Transmit block specifies the configuration of data that it transmits to the target hardware.

The data package that the block sends is limited to 16 bytes of ASCII characters, including package headers and terminators. Calculate the size of a package by including the package header, or terminator, or both, and the data size. The following table shows the number of bytes in each data type.

Data Type	Byte Count
single	4 bytes
int8 and uint8	1 byte
int16 and uint16	2 bytes
int32 and uint32	4 bytes

For example, if your data package has a package header 'S' (1 byte) and package terminator 'E' (1 byte), that leaves 14 bytes for the actual data. If your data is of type int8, there is space in the data package for 14 int8s. If your data is of type uint16, there is space in the data package for 7 uint16s. If your data is of type int32, there is space in the data package for only 3 int32s, with 2 bytes left over. Even though you could fit two int8s or one uint16 in the remaining space, you may not, because you cannot mix data types in the same package.

The number of data types that can fit into a data package determine the data size. In the preceding example, data size is 14 for int8 and 7 for uint16. When the data size exceeds 16 bytes, unexpected behavior, including run-time errors may occur.

Ports

Input

data — Port receives data to be transmitted

scalar

The port accepts both one-dimensional and matrix data for transmission to the target hardware.

Data Types: single | int8 | uint8 | int16 | uint16 | int32 | uint32

Parameters

Serial Connection — Serial port used for transmitting data

Serial 1 (default) | Serial 2 | Serial 3 | Serial 4

Specifies a serial port that you want to use for sending communication to the target hardware. Select an available serial port from the list. You can configure the selected port using the Host Serial Setup block. If you do not configure a serial port, the block prompts you to do so. Each Host Serial Transmit block must have a configured serial port. If you use multiple ports in your simulation, you must configure each port separately.

Additional package header — Package header data

'S' (default) | scalar

Specifies the data located at the front of the transmitted data package, which is not part of the data being transmitted, and generally indicates start of data. The additional package header must be an ASCII value. You can use text or a number (0-255). You must put single quotes around the text that you enter in this field, but the quotes are not transmitted and they are not included in the total byte count.

Additional package terminator — Package terminator data

'E' (default) | scalar

Specifies the data located at the end of the transmitted data package, which is not part of the data being transmitted, and generally indicates end of data. The additional package terminator must be an ASCII value. You can use text or a number (0-255). You must put single quotes around text entered in this field, but the quotes are not transmitted and they are not included in the total byte count.

Enable blocking mode — Block simulation while sending data

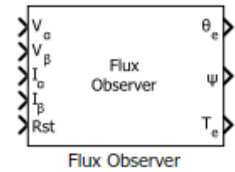
off (default) | on

Select this parameter to block the simulation while transmitting data. Clear this parameter if you do not want the write operation to block the simulation.

Flux Observer

Compute electrical position, magnetic flux, and electrical torque of rotor

Library: Motor Control Blockset / Sensorless Estimators



Description

The Flux Observer block computes the electrical position, magnetic flux, and electrical torque of a PMSM by using the per unit voltage and current values along the α - and β -axes of the stationary $\alpha\beta$ reference frame.

Equations

The following equations describe the computation of the electrical position, magnetic flux, and electrical torque by the block.

$$\psi_{1\alpha} = \int (V_{\alpha} - I_{\alpha}R)dt$$

$$\psi_{1\beta} = \int (V_{\beta} - I_{\beta}R)dt$$

$$\psi = \sqrt{\psi_{1\alpha}^2 + \psi_{1\beta}^2}$$

$$T_e = \frac{3}{2}P(\psi_{1\alpha}I_{\beta} - \psi_{1\beta}I_{\alpha})$$

$$\theta_e \cong \tan^{-1} \frac{\psi_{1\beta}}{\psi_{1\alpha}}$$

where:

- V_{α} and V_{β} are the α -axis and β -axis voltages.
- I_{α} and I_{β} are the α -axis and β -axis currents.
- R is the stator resistance of the motor.
- P is the number of motor pole pairs.
- ψ is the magnetic stator flux.
- T_e is the electrical torque of the rotor.
- θ_e is the electrical position of the rotor.

Ports

Input

V_α — α -axis voltage

scalar

Voltage component along the α -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

V_β — β -axis voltage

scalar

Voltage component along the β -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

I_α — α -axis current

scalar

Current component along the α -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

I_β — β -axis current

scalar

Current component along the β -axis of the stationary $\alpha\beta$ reference frame.

Data Types: single | double | fixed point

Rst — Reset the block

scalar

The pulse (true value) that resets and restarts the processing of the block algorithm.

Data Types: single | double | fixed point

Output

θ_e — Electrical position of PMSM

scalar

The electrical position of the rotor estimated by the block.

Dependencies

To enable this port, select **Position** value of the **Block output** parameter.

Data Types: single | double | fixed point

Ψ — Rotor flux of PMSM

scalar

The magnetic flux of the rotor estimated by the block.

Dependencies

To enable this port, select Flux value of the **Block output** parameter.

Data Types: single | double | fixed point

 T_e — Electrical torque of PMSM

scalar

The electrical torque of the rotor estimated by the block.

Dependencies

To enable this port, select Torque value of the **Block output** parameter.

Data Types: single | double | fixed point

Parameters**Motor parameters****Input units — Unit of voltage and current inputs**

SI unit (default) | Per-unit

Select the unit of the α and β -axis voltage and current input values.

Block output — Select outputs that block should compute

Position (default) | Flux | Torque

Select one or more output quantities that the block should compute and display as block output.

Note You must select at least one value. The block displays an error message if you click **Ok** or **Apply** without selecting any value.

Pole pairs — Number of pole pairs available in motor

4 (default) | scalar

Number of pole pairs available in the motor.

Dependencies

To enable this parameter, select Torque value of the **Block output** parameter.

Stator resistance (ohm) — Stator winding resistance

0.36 (default) | scalar

Stator phase winding resistance (ohm) of the motor.

Block sample time (S) — Sample time after which block executes again

50e-6 (default) | scalar

The fixed time interval (in seconds) between every two consecutive instances of block execution.

Datatypes

Position unit — Unit of electrical position output

Radians (default) | Degrees | Per-unit

Unit of the electrical position output.

Dependencies

To enable this parameter, select Position value of the **Block output** parameter.

Position datatype — Data type of electrical position output

single (default) | double | fixed point

Data type of the electrical position output.

Dependencies

To enable this parameter, select Position value of the **Block output** parameter.

Flux unit — Unit of magnetic flux output

Weber (default) | Per-unit

Unit of the magnetic flux output.

Dependencies

To enable this parameter, select Flux value of the **Block output** parameter.

Flux datatype — Data type of magnetic flux output

single (default) | double | fixed point

Data type of the magnetic flux output.

Dependencies

To enable this parameter, select Flux value of the **Block output** parameter.

Torque unit — Unit of electrical torque output

Nm (default) | Per-unit

Unit of the electrical torque output.

Dependencies

To enable this parameter, select Torque value of the **Block output** parameter.

Torque datatype — Data type of electrical torque output

single (default) | double | fixed point

Data type of the electrical torque output.

Dependencies

To enable this parameter, select Torque value of the **Block output** parameter.

References

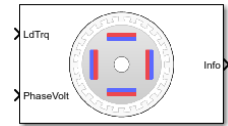
- [1] O. Sandre-Hernandez, J. J. Rangel-Magdaleno and R. Morales-Caporal, "Simulink-HDL cosimulation of direct torque control of a PM synchronous machine based FPGA," *2014 11th International Conference on Electrical Engineering, Computing Science and Automatic Control (CCE), Campeche, 2014*, pp. 1-6. (doi: 10.1109/ICEEE.2014.6978298)

- [2] Y. Inoue, S. Morimoto and M. Sanada, "Control method suitable for direct torque control based motor drive system satisfying voltage and current limitations," *The 2010 International Power Electronics Conference - ECCE ASIA -, Sapporo, 2010*, pp. 3000-3006. (doi: 10.1109/IPEC.2010.5543698)

Interior PMSM

Three-phase interior permanent magnet synchronous motor with sinusoidal back electromotive force

Library: Powertrain Blockset / Propulsion / Electric Motors
Motor Control Blockset / Electrical Systems / Motors



Description

The Interior PMSM block implements a three-phase interior permanent magnet synchronous motor (PMSM) with sinusoidal back electromotive force. The block uses the three-phase input voltages to regulate the individual phase currents, allowing control of the motor torque or speed.

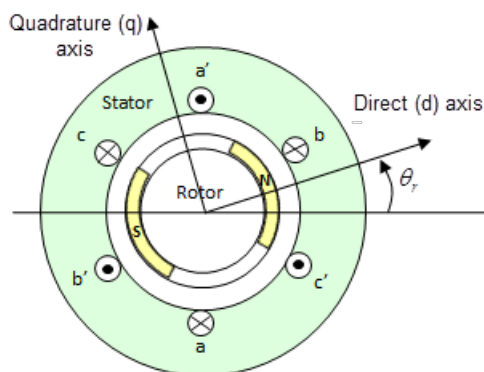
By default, the block sets the **Simulation type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

On the **Parameters** tab, if you select **Back - emf**, the block implements this equation to calculate the permanent flux linkage constant.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Motor Construction

This figure shows the motor construction with a single pole pair on the motor.



The motor magnetic field due to the permanent magnets creates a sinusoidal rate of change of flux with motor angle.

For the axes convention, the *a*-phase and permanent magnet fluxes are aligned when motor angle θ_r is zero.

Three-Phase Sinusoidal Model Electrical System

The block implements these equations, expressed in the motor flux reference frame (dq frame). All quantities in the motor reference frame are referred to the stator.

$$\omega_e = P\omega_m$$

$$\frac{d}{dt}i_d = \frac{1}{L_d}v_d - \frac{R}{L_d}i_d + \frac{L_q}{L_d}P\omega_m i_q$$

$$\frac{d}{dt}i_q = \frac{1}{L_q}v_q - \frac{R}{L_q}i_q - \frac{L_d}{L_q}P\omega_m i_d - \frac{\lambda_{pm}P\omega_m}{L_q}$$

$$T_e = 1.5P[\lambda_{pm}i_q + (L_d - L_q)i_d i_q]$$

The L_q and L_d inductances represent the relation between the phase inductance and the motor position due to the saliency of the motor.

The equations use these variables.

L_q, L_d	q- and d-axis inductances
R	Resistance of the stator windings
i_q, i_d	q- and d-axis currents
v_q, v_d	q- and d-axis voltages
ω_m	Angular mechanical velocity of the motor
ω_e	Angular electrical velocity of the motor
λ_{pm}	Permanent flux linkage constant
K_e	Back electromotive force (EMF)
P	Number of pole pairs
T_e	Electromagnetic torque
Θ_e	Electrical angle

Mechanical System

The motor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of motor and load
F	Combined viscous friction of motor and load
θ_m	Motor mechanical angular position
T_m	Motor shaft torque
T_e	Electromagnetic torque

T_f	Motor shaft static friction torque
ω_m	Angular mechanical velocity of the motor

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	$P_{bus} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	$P_{elec} = -\frac{3}{2}(R_s i_{sd}^2 + R_s i_{sq}^2)$
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMechLoss	Mechanical power loss	<p>When Port Configuration is set to Torque:</p> $P_{mech} = -(\omega_m^2 F + \omega_m T_f)$ <p>When Port Configuration is set to Speed:</p> $P_{mech} = 0$
PwrStored — Stored energy rate of change	PwrMtrStored	Stored motor power	P_{str}	$P_{str} = P_{bus} + P_{mot} + P_{elec} + P_{mech}$
<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 				

The equations use these variables.

R_s	Stator resistance
i_a, i_b, i_c	Stator phase a, b, and c current
i_{sq}, i_{sd}	Stator q- and d-axis currents
v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage
ω_m	Angular mechanical velocity of the rotor
F	Combined motor and load viscous damping

T_e Electromagnetic torque
 T_f Combined motor and load friction torque

Ports

Input

LdTrq – Motor shaft torque

scalar

Motor shaft input torque, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port Configuration** parameter.

Spd – Motor shaft speed

scalar

Angular velocity of the motor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port Configuration** parameter.

PhaseVolt – Stator terminal voltages

1-by-3 array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Dependencies

To create this port, select Speed or Torque for the **Port Configuration** parameter.

Output

Info – Bus signal

bus

The bus signal contains these block calculations.

Signal	Description	Variable	Units
IaStator	Stator phase current A	i_a	A
IbStator	Stator phase current B	i_b	A
IcStator	Stator phase current C	i_c	A
IdSync	Direct axis current	i_d	A
IqSync	Quadrature axis current	i_q	A
VdSync	Direct axis voltage	v_d	V
VqSync	Quadrature axis voltage	v_q	V
MtrSpd	Angular mechanical velocity of the motor	ω_m	rad/s

Signal			Description	Variable	Units
MtrPos			Motor mechanical angular position	θ_m	rad
MtrTrq			Electromagnetic torque	T_e	N·m
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr — Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq — Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Mechanical input configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Mechanical input configuration** parameter.

Parameters

Block Options

Mechanical input configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd
Speed	Spd	MtrTrq

Simulation type — Select simulation type

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to **Discrete**.

Dependencies

Setting **Simulation type** to **Discrete** creates the **Sample Time, Ts** parameter.

Sample Time (Ts) – Sample time for discrete integration

scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation type** to **Discrete** creates the **Sample Time, Ts** parameter.

Load Parameters**File – Path to motor parameter ".m" or ".mat" file**

scalar

Enter the path to the motor parameter ".m" or ".mat" file that you saved using the Motor Control Blockset parameter estimation tool. You can also click the **Browse** button to navigate and select the ".m" or ".mat" file, and update **File** parameter with the file name and path. For details related to the motor parameter estimation process, see "Estimate Motor Parameters by Using Motor Control Blockset Parameter Estimation Tool".

- **Load from file** - Click this button to read the estimated motor parameters from the ".m" or ".mat" file (indicated by the **File** parameter) and load them to the motor block.
- **Save to file** - Click this button to read the motor parameters from the motor block and save them into a ".m" or ".mat" file (with a file name and location that you specify in the **File** parameter).

Note Before you click **Save to file** button, ensure that the target file name in the **File** parameter has either ".m" or ".mat" extension. If you use any other file extension, the block displays an error message.

Parameters**Number of pole pairs (P) – Pole pairs**

scalar

Motor pole pairs, P .

Stator phase resistance per phase (Rs) – Resistance

scalar

Stator phase resistance per phase, R_s , in ohm.

Stator d-axis and q-axis inductance (Ldq) – Inductance

vector

Stator d-axis and q-axis inductance, L_d , L_q , in H.

Permanent flux linkage constant (lambda_pm) – Flux

scalar

Permanent flux linkage constant, λ_{pm} , in Wb.

Back-emf constant (Ke) – Back electromotive force
scalar

Back electromotive force, EMF, K_e , in Vpk_LL/krpm. Vpk_LL is the peak voltage line-to-line measurement.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Physical inertia, viscous damping, and static friction (mechanical) – Inertia, damping, friction
vector

Mechanical properties of the motor:

- Inertia, J , in kgm^2
- Viscous damping, F , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction, T_f , in $\text{N}\cdot\text{m}$

Dependencies

To enable this parameter, select the Torque configuration parameter.

Initial Values

Initial d-axis and q-axis current (idq0) – Current
vector

Initial q- and d-axis currents, i_q, i_d , in A.

Initial mechanical position (theta_init) – Angle
scalar

Initial motor angular position, θ_{m0} , in rad.

Initial mechanical speed (omega_init) – Speed
scalar

Initial angular velocity of the motor, ω_{m0} , in rad/s.

Dependencies

To enable this parameter, select the Torque configuration parameter.

References

- [1] Kundur, P. *Power System Stability and Control*. New York, NY: McGraw Hill, 1993.
- [2] Anderson, P. M. *Analysis of Faulted Power Systems*. Hoboken, NJ: Wiley-IEEE Press, 1995.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

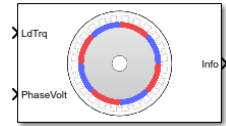
See Also

Introduced in R2017a

Surface Mount PMSM

Three-phase exterior permanent magnet synchronous motor with sinusoidal back electromotive force

Library: Powertrain Blockset / Propulsion / Electric Motors
Motor Control Blockset / Electrical Systems / Motors



Description

The Surface Mount PMSM block implements a three-phase exterior permanent magnet synchronous motor (PMSM) with sinusoidal back electromotive force. The block uses the three-phase input voltages to regulate the individual phase currents, allowing control of the motor torque or speed.

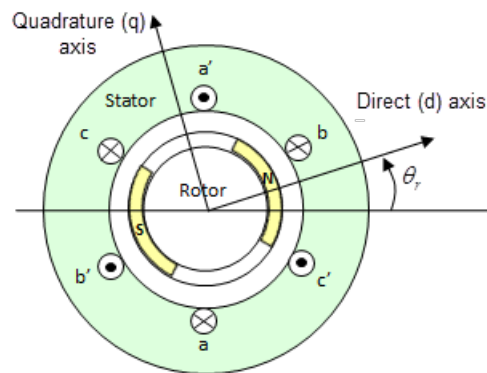
By default, the block sets the **Simulation type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

On the **Parameters** tab, if you select **Back-emf** or **Torque constant**, the block implements one of these equations to calculate the permanent flux linkage constant.

Setting	Equation
Back-emf	$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$
Torque constant	$\lambda_{pm} = \frac{2}{3} \cdot \frac{K_t}{P}$

Motor Construction

This figure shows the motor construction with a single pole pair on the motor.



The motor magnetic field due to the permanent magnets creates a sinusoidal rate of change of flux with motor angle.

For the axes convention, the a -phase and permanent magnet fluxes are aligned when motor angle θ_e is zero.

Three-Phase Sinusoidal Model Electrical System

The block implements these equations, expressed in the motor flux reference frame (dq frame). All quantities in the motor reference frame are referred to the stator.

$$\omega_e = P\omega_m$$

$$\frac{d}{dt}i_d = \frac{1}{L_d}v_d - \frac{R}{L_d}i_d + \frac{L_q}{L_d}P\omega_m i_q$$

$$\frac{d}{dt}i_q = \frac{1}{L_q}v_q - \frac{R}{L_q}i_q - \frac{L_d}{L_q}P\omega_m i_d - \frac{\lambda_{pm}P\omega_m}{L_q}$$

$$T_e = 1.5P[\lambda_{pm}i_q + (L_d - L_q)i_d i_q]$$

The L_q and L_d inductances represent the relation between the phase inductance and the motor position due to the saliency of the motor magnets. For the surface mount PMSM, $L_d = L_q$.

The equations use these variables.

L_q, L_d	q- and d-axis inductances
R	Resistance of the stator windings
i_q, i_d	q- and d-axis currents
v_q, v_d	q- and d-axis voltages
ω_m	Angular mechanical velocity of the motor
ω_e	Angular electrical velocity of the motor
λ_{pm}	Permanent magnet flux linkage
K_e	Back electromotive force (EMF)
K_t	Torque constant
P	Number of pole pairs
T_e	Electromagnetic torque
Θ_e	Electrical angle

Mechanical System

The motor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of motor and load
F	Combined viscous friction of motor and load

θ_m	Motor mechanical angular position
T_m	Motor shaft torque
T_e	Electromagnetic torque
T_f	Motor shaft static friction torque
ω_m	Angular mechanical velocity of the motor

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	P_{mot}	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	P_{bus}	$P_{bus} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	P_{elec}	$P_{elec} = -\frac{3}{2}(R_s i_{sd}^2 + R_s i_{sq}^2)$
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMechLoss	Mechanical power loss	P_{mech}	When Port Configuration is set to Torque: $P_{mech} = -(\omega_m^2 F + \omega_m T_f)$ When Port Configuration is set to Speed: $P_{mech} = 0$
PwrStored — Stored energy rate of change	PwrMtrStored	Stored motor power	P_{str}	$P_{str} = P_{bus} + P_{mot} + P_{elec} + P_{mech}$	
<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 					

The equations use these variables.

R_s	Stator resistance
i_a, i_b, i_c	Stator phase a, b, and c current
i_{sq}, i_{sd}	Stator q- and d-axis currents

v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage
ω_m	Angular mechanical velocity of the motor
F	Combined motor and load viscous damping
T_e	Electromagnetic torque
T_f	Combined motor and load friction torque

Ports

Input

LdTrq — Motor shaft torque

scalar

Motor shaft input torque, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port Configuration** parameter.

Spd — Motor shaft speed

scalar

Angular velocity of the motor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port Configuration** parameter.

PhaseVolt — Stator terminal voltages

1-by-3 array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Output

Info — Bus signal

bus

The bus signal contains these block calculations.

Signal	Description	Variable	Units
IaStator	Stator phase current A	i_a	A
IbStator	Stator phase current B	i_b	A
IcStator	Stator phase current C	i_c	A
IdSync	Direct axis current	i_d	A
IqSync	Quadrature axis current	i_q	A
VdSync	Direct axis voltage	v_d	V
VqSync	Quadrature axis voltage	v_q	V

Signal			Description	Variable	Units
MtrSpd			Angular mechanical velocity of the motor	ω_m	rad/s
MtrPos			Motor mechanical angular position	θ_m	rad
MtrTrq			Electromagnetic torque	T_e	N·m
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr — Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq — Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Mechanical input configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Mechanical input configuration** parameter.

Parameters

Block Options

Mechanical input configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd
Speed	Spd	MtrTrq

Simulation type – Select simulation type

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to **Discrete**.

Dependencies

Setting **Simulation type** to **Discrete** creates the **Sample Time, Ts** parameter.

Sample Time (Ts) – Sample time for discrete integration

scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation type** to **Discrete** creates the **Sample Time, Ts** parameter.

Load Parameters**File – Path to motor parameter ".m" or ".mat" file**

scalar

Enter the path to the motor parameter ".m" or ".mat" file that you saved using the Motor Control Blockset parameter estimation tool. You can also click the **Browse** button to navigate and select the ".m" or ".mat" file, and update **File** parameter with the file name and path. For details related to the motor parameter estimation process, see "Estimate Motor Parameters by Using Motor Control Blockset Parameter Estimation Tool".

- **Load from file** - Click this button to read the estimated motor parameters from the ".m" or ".mat" file (indicated by the **File** parameter) and load them to the motor block.
- **Save to file** - Click this button to read the motor parameters from the motor block and save them into a ".m" or ".mat" file (with a file name and location that you specify in the **File** parameter).

Note Before you click **Save to file** button, ensure that the target file name in the **File** parameter has either ".m" or ".mat" extension. If you use any other file extension, the block displays an error message.

Parameters**Number of pole pairs (P) – Pole pairs**

scalar

Motor pole pairs, P .

Stator phase resistance per phase (Rs) – Resistance

scalar

Stator phase resistance per phase, R_s , in ohm.

Stator d-axis inductance (Ldq_) – Inductance

scalar

Stator inductance, L_{dq} , in H.

Permanent flux linkage constant (lambda_pm) – Flux
scalar

Permanent flux linkage constant, λ_{pm} , in Wb.

Back-emf constant (Ke) – Back electromotive force
scalar

Back electromotive force, EMF, K_e , in peak Vpk_LL/krpm. Vpk_LL is the peak voltage line-to-line measurement.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Torque constant (Kt) – Torque constant
scalar

Torque constant, K_t , in N·m/A.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{2}{3} \cdot \frac{K_t}{P}$$

Physical inertia, viscous damping, and static friction (mechanical) – Inertia, damping, friction
vector

Mechanical properties of the motor:

- Inertia, J , in kgm²
- Viscous damping, F , in N·m/(rad/s)
- Static friction, T_f , in N·m

Dependencies

To enable this parameter, select the Torque configuration parameter.

Initial Values**Initial d-axis and q-axis current (idq0) – Current**
vector

Initial q- and d-axis currents, i_q , i_d , in A.

Initial mechanical position (theta_init) – Angle
scalar

Initial motor angular position, θ_{m0} , in rad.

Initial mechanical speed (omega_init) – Speed
scalar

Initial angular velocity of the motor, ω_{m0} , in rad/s.

Dependencies

To enable this parameter, select the Torque configuration parameter.

References

- [1] Kundur, P. *Power System Stability and Control*. New York, NY: McGraw Hill, 1993.
- [2] Anderson, P. M. *Analysis of Faulted Power Systems*. Hoboken, NJ: Wiley-IEEE Press, 1995.

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

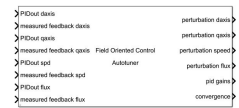
See Also

Introduced in R2017a

Field Oriented Control Autotuner

Automatically and sequentially tune multiple PID control loops in field-oriented control application

Library: Motor Control Blockset / Controls / Controllers



Description

The Field Oriented Control Autotuner block allows you to automatically tune PID control loops in your field-oriented control (FOC) application in real time. For more information on field-oriented control, see “Implement Motor Speed Control Using Field-Oriented Control (FOC)”.

You can automatically tune PID controllers associated with the following loops:

- Direct-axis (d-axis) current loop
- Quadrature-axis (q-axis) current loop
- Speed loop
- Flux loop

For each loop the block tunes, the Field Oriented Control Autotuner block performs the autotuning experiment in closed-loop without a parametric model associated with that loop. The block allows you to specify the order in which the control loops are tuned. When the tuning experiment is running for one loop, the block has no effect on the other loops. During the experiment, the block:

- 1 Injects a test signal into the plant associated with that loop to collect plant input-output data and estimate frequency response in real time. The test signal is combination of sinusoidal perturbation signals added on top of the plant input.
- 2 At the end of the experiment, tunes PID controller parameters based on estimated plant frequency responses near the target bandwidth.
- 3 Writes updated PID gains at the block output, allowing you to transfer the new gains to existing controllers and validate the closed-loop performance.

You can use the Field Oriented Control Autotuner block to tune the existing PID controllers in your FOC structure. If you do not have the initial PID controllers, you can use the “Estimate Control Gains from Motor Parameters” workflow to obtain them. You can then use the Field Oriented Control Autotuner block for refinement or retuning.

If you have a code-generation product such as Simulink Coder™, you can generate code that implements the tuning algorithm on hardware, letting you tune in real time, using or without using Simulink to manage the autotuning process.

If you have a machine modeled in Simulink with Motor Control Blockset and an initial FOC structure with PID controllers, you can perform closed-loop PID autotuning against the modeled machine. Doing so lets you preview the plant response and adjust the settings for PID autotuning before tuning the controller in real time.

The block supports code generation with Simulink Coder, Embedded Coder®, and Simulink PLC Coder™. It does not support code generation with HDL Coder™. For real-time applications, deploy the generated code on a rapid prototyping hardware such as Speedgoat real-time target machine.

For more information about using the Field Oriented Control Autotuner block, see “Tune PID Controllers by Using Field-Oriented Control Autotuner”.

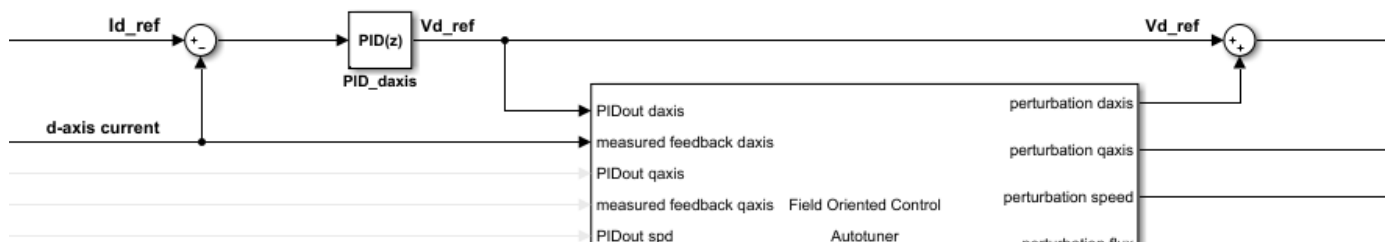
Ports

Input

PIDout_daxis — Signal from direct-axis current controller

scalar

This port accepts the output of the d-axis controller `PID_daxis`, which is the output of PID controller that regulates the d-axis current of the motor. The controller generates the d-axis voltage reference `Vd_ref`, while the FOC autotuner block generates perturbations used during the tuning experiment for the d-axis current loop.



Dependencies

To enable this port, select **Tune D-axis current loop**.

Data Types: `single` | `double`

measured feedback_daxis — Measured direct-axis current

scalar

This port accepts the d-axis current obtained from the measured (sensed or estimated) motor currents.

Dependencies

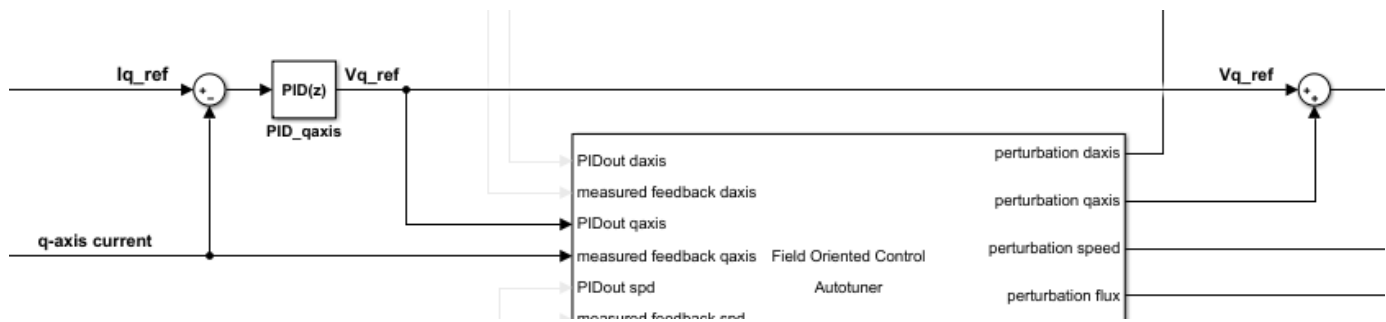
To enable this port, select **Tune D-axis current loop**.

Data Types: `single` | `double`

PIDout_qaxis — Signal from quadrature-axis current controller

scalar

This port accepts the output of the q-axis controller `PID_qaxis`, which is the output of PID controller that regulates the q-axis current of the motor. The controller generates the q-axis voltage reference `Vq_ref`, while the FOC autotuner block generates perturbations used during the tuning experiment for the q-axis current loop.



Dependencies

To enable this port, select **Tune Q-axis current loop**.

Data Types: single | double

measured feedback_qaxis – Measured quadrature-axis current

scalar

This port accepts the q-axis current obtained from the measured (sensed or estimated) motor currents.

Dependencies

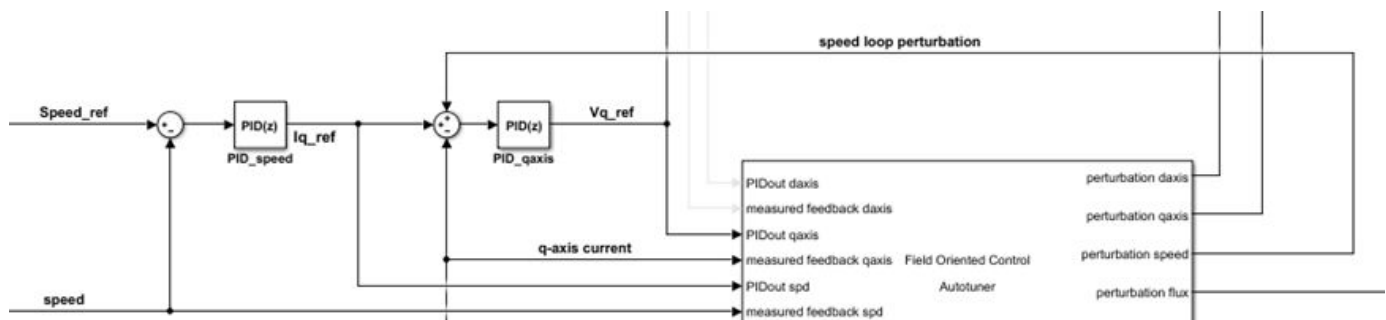
To enable this port, select **Tune Q-axis current loop**.

Data Types: single | double

PIDout_spd – Signal from speed controller

scalar

This port accepts the output of the speed controller `PID_speed`, which is the output of PID controller that regulates the speed of the motor. The controller generates the q-axis current reference `Iq_ref`, while the FOC autotuner block generates perturbations used during the tuning experiment for the speed loop.



Dependencies

To enable this port, select **Tune speed loop**.

Data Types: single | double

measured feedback_spd – Measured speed

scalar

This port accepts the measured (sensed or estimated) speed from the motor.

Dependencies

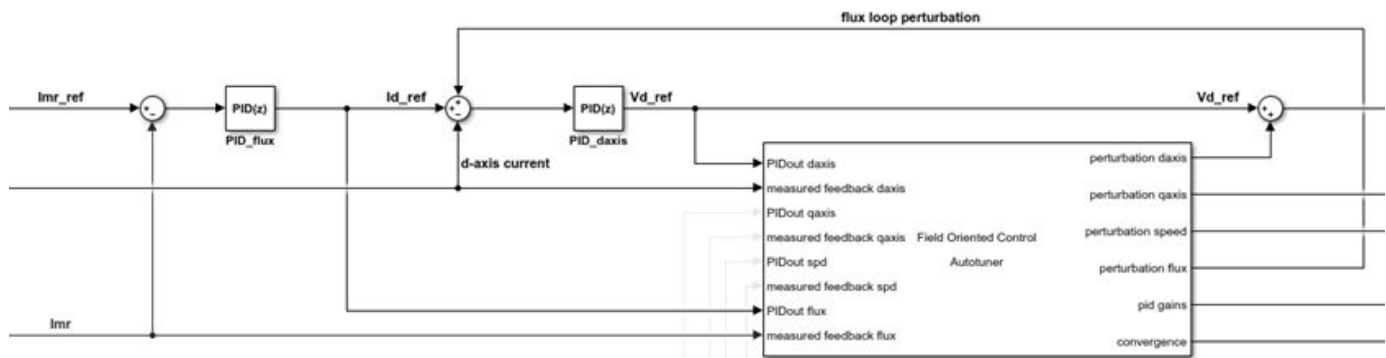
To enable this port, select **Tune speed loop**.

Data Types: `single` | `double`

PIDout_flux — Signal from flux controller

scalar

This port accepts the output of the flux controller `PID_flux`, which is the output of PID controller that regulates the flux of the motor. The controller generates the d-axis current reference `Id_ref`, while the FOC autotuner block generates perturbations used during the tuning experiment for the flux loop.



For a permanent magnet synchronous motor (PMSM), there is no flux loop controller as the rotor flux is fixed and `Id_ref` is set to zero. In some applications you can provide a negative `Id_ref` value to implement field-weakening control and achieve higher rotor speeds at the cost of a higher current.

Dependencies

To enable this port, select **Tune flux loop**.

Data Types: `single` | `double`

measured_feedback_flux — Measured flux

scalar

This port accepts the measured (sensed or estimated) flux from the motor.

Dependencies

To enable this port, select **Tune flux loop**.

Data Types: `single` | `double`

start/stop — Start and stop autotuning experiment

scalar

To externally start and stop the autotuning process, provide a signal at the `start/stop` port and the `ActiveLoop` port.

- The experiment starts when the value of the signal changes from negative or zero to positive.

- The experiment stops when the value of the signal changes from positive to negative or zero.

For the duration of the experiment, for each loop, the block injects sinusoidal perturbations at the plant input associated with the loop, near the nominal operating point, to collect input-output data and estimate frequency response. When the experiment stops, the block computes PID gains based on the plant frequency responses estimated near the target bandwidth.

When the experiment is not running, the block does not inject any perturbations at the plant inputs. In this state, the block has no impact on plant or controller behavior.

Typically, you can use a signal that changes from 0 to 1 to start the experiment, and from 1 to 0 to stop it. Consider the following when you configure the `start/stop` signal.

- Start the experiment when the motor is at the desired equilibrium operating point. Use the initial controller to drive the motor to the operating point.
- Avoid any input or output disturbance on the motor during the experiment. If your existing closed-loop system has good disturbance rejection, then the experiment can handle small disturbances. Otherwise, large disturbances can distort the plant output and reduce the accuracy of the frequency-response estimation.
- Let the experiment run long enough for the algorithm to collect sufficient data for a good estimate at all frequencies it probes. There are two ways to determine when to stop the experiment:
 - Determine the experiment duration in advance. A conservative estimate for the experiment duration is $200/\omega_c$, where ω_c is your target bandwidth.
 - Observe the signal at the convergence output, and stop the experiment when the signal stabilizes near 100%.
- When you stop the experiment, the block computes tuned PID gains and updates the signal at the `pid gains` port.

You can configure any logic appropriate for your application to control the start and stop times of the experiment. The `start/stop` signal is specified along with `ActiveLoop`. `ActiveLoop` takes integer values 1 to 4 and specifies which loop to tune.

Alternatively, if you are tuning in simulation or external mode, you can specify the tuning experiment sequence, start time and duration in the block parameters.

Dependencies

To enable this port, on the Block tab under **Parameters Source**, select **Use external source for start/stop of experiment**.

Data Types: `single` | `double`

ActiveLoop — Specify active loop for autotuning experiment

scalar

Set the `ActiveLoop` value to specify which loop to tune when providing an external source for the start and stop times of the tuning experiment.

ActiveLoop Value	Loop to Tune
1	D-axis current loop
2	Q-axis current loop

ActiveLoop Value	Loop to Tune
3	Speed loop
4	Flux loop

You can configure any logic appropriate for your application along with the `start/stop` port to control the sequence and the time at which the loop tuning experiment runs. `ActiveLoop` takes integer values from 1 to 4 and specifies which loop to tune. Any other number will result in no tuning taking place regardless of the `start/stop` signal. For example, when you supply a constant value 2 at `ActiveLoop` and the signal at `start/stop` rises, the block starts the tuning experiment for the q-axis current loop.

Alternatively, you can specify the tuning experiment sequence, start time, and duration in the block parameters.

Dependencies

To enable this port, on the Block tab under **Parameters Source**, select **Use external source for start/stop of experiment**.

Data Types: `single` | `double`

bandwidth — Target bandwidth for tuning

scalar | vector | bus

Supply the values for the `Target bandwidth (rad/sec)` parameter for each loop to be tuned. If you are tuning multiple loops, you can specify the bandwidth as a vector or bus, entries of which correspond to the target bandwidth for the loops in this order:

- D-axis current loop
- Q-axis current loop
- Speed loop
- Flux loop

The vector signal must be specified as a N-by-1 or 1-by-N signal or if specified as a bus must have N elements, where N is the number of loops to be tuned. For instance, if you are tuning the q-axis current loop and the speed loop, and you specify a vector [5000, 200] at this port, the block tunes the q-axis current controller with the target bandwidth 5000 rad/sec and the speed loop controller with the target bandwidth 200 rad/sec.

If you are tuning multiple loops and specify a scalar value at this port, then the block uses the same target bandwidth to tune all the controllers. For effective cascade control, the inner control loops (d-axis and q-axis) must respond much faster than the outer control loops (flux and speed). Therefore, you must supply the target bandwidth as a vector or bus signal when tuning multiple loops.

Alternatively, you can specify target bandwidth for individual loops in block parameters. For more information on how to choose a bandwidth, see that parameter description.

Dependencies

To enable this port, on the Block tab under **Parameters Source**, select **Use external source for bandwidth**.

Data Types: `single` | `double`

target PM — Target phase margin for tuning

scalar | vector | bus

Supply a value for the **Target phase margin (degrees)** parameter for each loop to be tuned. If you are tuning multiple loops, you can specify **target PM** as a vector or bus, entries of which correspond to the target phase margin for the loops in this order:

- D-axis current loop
- Q-axis current loop
- Speed loop
- Flux loop

The vector signal must be specified as a N-by-1 or 1-by-N signal or if specified as a bus must have N elements, where N is the number of loops to be tuned. For instance, if you are tuning q-axis current loop and speed loop, and you specify a vector [60, 45] at this port, the block tunes q-axis current controller with target phase margin 60 degrees and speed loop controller with target phase margin 45 degrees.

If you are tuning multiple loops and specify a scalar value at this port, then the block uses the same target phase margin to tune all the controllers.

Alternatively, you can specify target phase margin for individual loops in block parameters. For more information on how to choose a target phase margin, see that parameter description.

Dependencies

To enable this port, on the Block tab under **Parameters Source**, select **Use external source for target phase margin**.

Data Types: single | double

sine Amp — Amplitudes of injected sinusoidal perturbation signals

vector | matrix

Supply a value for the **Sine Amplitudes** parameter for each loop to be tuned. Specify one of the following:

- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning.
- N-by-5 matrix, where N is the number of loops to be tuned. Each row entry must of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$.

If you are tuning multiple loops and specify a vector of length 5 at this port, then the block uses the specified amplitude for all the loops at each of $[1/10, 1/3, 1, 3, 10]\omega_c$ corresponding to that loop.

Alternatively, you can specify the sinusoidal perturbation amplitude for individual loops in block parameters. For more information, see the parameter description.

Dependencies

To enable this port, on the Block tab under **Parameters Source**, select **Use external source for sine amplitudes**.

Data Types: single | double

Output

perturbation_daxis — Direct-axis current input perturbation

scalar

Perturbation signal input used for estimating the frequency-response data model associated with the d-axis current control loop. Inject the perturbation signal from this port by using a sum block to the output of the PID controller that regulates the d-axis current.

- When the experiment is running, the block generates perturbation signals at this port.
- When the experiment is not running, the signal at this port is zero. In this state, the block has no effect on the plant.

Dependencies

To enable this port, select **Tune D-axis current loop**.

Data Types: `single` | `double`

perturbation_qaxis — Quadrature-axis current input perturbation

scalar

Perturbation signal input used for estimating the frequency-response data model associated with the q-axis current control loop. Inject this perturbation signal from this port by using a sum block to the output of the PID controller that regulates the q-axis current.

- When the experiment is running, the block generates perturbation signals at this port.
- When the experiment is not running, the signal at this port is zero. In this state, the block has no effect on the plant.

Dependencies

To enable this port, select **Tune Q-axis current loop**.

Data Types: `single` | `double`

perturbation_spd — Speed input perturbation

scalar

Perturbation signal input used for estimating the frequency-response data model associated with the motor speed control loop. Inject this perturbation signal from this port by using a sum block with the output of the PID controller that regulates the speed of the motor.

- When the experiment is running, the block generates perturbation signals at this port.
- When the experiment is not running, the signal at this port is zero. In this state, the block has no effect on the plant.

Dependencies

To enable this port, select **Tune speed loop**.

Data Types: `single` | `double`

perturbation_flux — Flux input perturbation

scalar

Perturbation signal input used for estimating the frequency-response data model associated with the motor flux control loop. Inject this perturbation signal from this port by using a sum block to the output of the PID controller that regulates the flux linkage of the motor.

- When the experiment is running, the block generates perturbation signals at this port.
- When the experiment is not running, the signal at this port is zero. In this state, the block has no effect on the plant.

Dependencies

To enable this port, select **Tune flux loop**.

Data Types: `single` | `double`

pid gains — Tuned PID coefficients

bus

This 4-element bus signal contains the tuned PID gains P , I , D , and the filter coefficient N for each control loop the block tunes. These values correspond to the P, I, D, and N parameters in the expressions given in the Form parameter. Initially, the values are 0, 0, 0, and 100, respectively. The block updates the values when the experiment ends. The bus signal corresponding to each loop the block tunes always has four elements, even if you are not tuning a PIDF controller.

Data Types: `single` | `double`

convergence — Convergence of FRD estimation during experiment

scalar

The block uses perturbation signals to estimate the frequency response of the plant associated with each loop at several frequencies around the target bandwidth for tuning. `convergence` indicates how close to completion the estimation of the plant frequency response is. Typically, this value quickly rises to about 90% after the experiment begins, and then gradually converges to a higher value. Stop the experiment when it levels off near 100%.

Data Types: `single` | `double`

estimated PM — Estimated phase margin for most recently tuned loop

scalar

This port outputs the estimated phase margin achieved by the tuned controller for the most recently tuned loop, in degrees. The block updates this value when the tuning experiment ends for each loop. The estimated phase margin is calculated from the angle of $G(j\omega_c)C(j\omega_c)$, where G is the estimated plant for that loop, C is the tuned controller, and ω_c is the crossover frequency (bandwidth). The estimated phase margin might differ from the target phase margin specified by the Target phase margin (degrees) parameter. It is an indicator of the robustness and stability achieved by the tuned system.

- Typically, the estimated phase margin is near the target phase margin. In general, the larger the value, the more robust is the tuned system, and the less overshoot there is.
- A negative phase margin indicates that the closed-loop system might be unstable.

Dependencies

To enable this port, on the Block tab, select **Estimated phase margin achieved by tuned controllers**.

Data Types: `single` | `double`

frd — Estimated frequency response for most recently tuned loop

vector

This port outputs the frequency-response data estimated by the experiment for most recently tuned loop. Initially, the value at `frd` is `[0, 0, 0, 0, 0]`. During the experiment, the block injects signals at frequencies `[1/10, 1/3, 1, 3, 10] ω_c` , where ω_c is the target bandwidth. At each sample time during the experiment, the block updates `frd` with a vector containing the complex frequency response at each of these frequencies. You can use the progress of the response as an alternative to `convergence` to examine the convergence of the estimation. When the experiment stops, the block updates `frd` with the final estimated frequency response used for computing the PID gains.

Dependencies

To enable this port, on the Block tab, select **Plant frequency responses near bandwidth**.

Data Types: `single` | `double`

nominal — Plant input and output at nominal operating point for most recently tuned loop

vector

This port outputs a vector containing the plant input and plant output for the most recently tuned loop or the loop currently being tuned. These values are the plant input and output at the nominal operating point at which the block performs the experiment.

Dependencies

To enable this port, on the Block tab, select **Plant nominal input and output**.

Data Types: `single` | `double`

loop_startstops — Active loop

bus

This 4-element bus signal indicates whether the tuning experiment for each loop tuned by the block is active or not. For each signal in the bus, the port outputs the logical value `1` (`true`) for the loop when the tuning experiment is running. The value is logical `0` (`false`) when the experiment is over or has not yet started. You can use this port to trigger updates of PID gains for individual loops.

Dependencies

To enable this port, on the Block tab, disable **Use external source for start/stop of experiment** and select **Start/stop of autotuning process**.

Data Types: `single` | `double`

Parameters

Tune D-axis current loop — Enable d-axis current loop tuning

`on` (default) | `off`

Use this parameter to enable or disable d-axis current loop autotuning.

Programmatic Use

Block Parameter: `TuneDaxisLoop`

Type: character vector

Values: 'on' | 'off'

Default: 'on'

Tune Q-axis current loop — Enable q-axis current loop tuning

on (default) | off

Use this parameter to enable or disable q-axis current loop autotuning.

Programmatic Use

Block Parameter: TuneQaxisLoop

Type: character vector

Values: 'on' | 'off'

Default: 'on'

Tune speed loop — Enable speed loop tuning

on (default) | off

Use this parameter to enable or disable speed loop autotuning.

Programmatic Use

Block Parameter: TuneSpeedLoop

Type: character vector

Values: 'on' | 'off'

Default: 'on'

Tune flux loop — Enable flux loop tuning

on (default) | off

Use this parameter to enable or disable flux loop autotuning.

Programmatic Use

Block Parameter: TuneSpeedLoop

Type: character vector

Values: 'on' | 'off'

Default: 'on'

Use same settings for current loop controllers (D-axis + Q-axis) — Enable same tuning and experiment settings for direct-axis and quadrature-axis current loops

off (default) | on

Select this parameter to enable the same tuning and experiment settings for d-axis and q-axis current loops. When enabled, the block uses the same controller settings, target bandwidth, phase margin, and other experiment settings to tune d-axis and q-axis current loops.

Programmatic Use

Block Parameter: UseSameSettingsInner

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Use same settings for outer loop controllers (Speed + Flux) — Enable same tuning and experiment settings for speed and flux loops

off (default) | on

Select this parameter to enable the same tuning and experiment settings for speed and flux loops. When enabled, the block uses the same controller settings, target bandwidth, phase margin, and other experiment settings to tune speed and flux loops.

Programmatic Use

Block Parameter: UseSameSettingsOuter

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Tuning Tab

D-axis Current Loop

Type — D-axis current loop PID controller actions

PI (default) | PID | PIDF | ...

Specify the type of PID controller associated with the d-axis current control loop.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use

Block Parameter: PIDTypeDaxis

Type: character vector

Values: 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'

Default: 'PI'

Form — D-axis current loop PID controller form

Parallel (default) | Ideal

Specify the PID controller form associated with your d-axis current control loop.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- `Parallel` — In `Parallel` form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)}$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see `Integrator` method and `Filter` method).

Other controller actions amount to setting P , I , or D to zero.

- **Ideal** — In **Ideal** form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to Inf . (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes

Programmatic Use

Block Parameter: PIDFormDaxis

Type: character vector

Values: 'Parallel' | 'Ideal'

Default: 'Parallel'

Controller sample time (sec) — D-axis current loop PID controller sample time

0.001 (default) | positive scalar | -1

Specify the sample time of your PID controller associated with the d-axis current control loop in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s ω_c is the controller sample time that you specify with the **Controller sample time (sec)** parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use

Block Parameter: TsDaxis

Type: scalar

Value positive scalar | -1

Default: 0.001

Integrator method — D-axis current loop controller discrete integration formula for integrator term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Integrator** method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z-1}$
Backward Euler	$\frac{T_s z}{z-1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes integral action.

Programmatic Use

Block Parameter: IntegratorMethodDaxis

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Filter method — D-axis current loop controller discrete integration formula for derivative filter term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Filter** method parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z-1}$

Filter method	F_d
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodDaxis

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) — D-axis current loop target crossover frequency of tuned response

100 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use

Block Parameter: BandwidthDaxis

Type: positive scalar

Default: 100

Target phase margin (degrees) — D-axis current loop target minimum phase margin

60 (default) | scalar in range 0–90

Specify a target minimum phase margin for the tuned open-loop response associated with the d-axis current control loop at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°–60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5–10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes

Programmatic Use

Block Parameter: TargetPMDaxis

Type: scalar

Values: 0–90

Default: 60

Q-axis Current Loop

Type — Q-axis current loop PID controller actions

PI (default) | PID | PIDF | ...

Specify the type of PID controller associated with the q-axis current control loop.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use

Block Parameter: PIDTypeQaxis

Type: character vector

Values: 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'

Default: 'PI'

Form — Q-axis current loop PID controller form

Parallel (default) | Ideal

Specify the PID controller form associated with your q-axis current control loop.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- **Parallel** — In **Parallel** form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see `Integrator` method and `Filter` method).

Other controller actions amount to setting P , I , or D to zero.

- `Ideal` — In `Ideal` form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to `Inf`. (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes

Programmatic Use

Block Parameter: `PIDFormQaxis`

Type: character vector

Values: 'Parallel' | 'Ideal'

Default: 'Parallel'

Controller sample time (sec) — Q-axis current loop PID controller sample time

0.001 (default) | positive scalar | -1

Specify the sample time of your PID controller associated with the q-axis current control loop in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s ω_c is the controller sample time that you specify with the `Controller sample time (sec)` parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use

Block Parameter: `TsQaxis`

Type: scalar

Value positive scalar | -1

Default: 0.001

Integrator method — Q-axis current loop controller discrete integration formula for integrator term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the Integrator method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes integral action.

Programmatic Use

Block Parameter: IntegratorMethodQaxis

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Filter method — Q-axis current loop controller discrete integration formula for derivative filter term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Filter method** parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z-1}$
Backward Euler	$\frac{T_s z}{z-1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodQaxis

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) — Q-axis current loop target crossover frequency of tuned response

100 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use

Block Parameter: BandwidthQaxis

Type: positive scalar

Default: 100

Target phase margin (degrees) — Q-axis current loop target minimum phase margin

60 (default) | scalar in range 0-90

Specify a target minimum phase margin for the tuned open-loop response associated with the q-axis current control loop at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°-60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5-10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes

Programmatic Use

Block Parameter: TargetPMQaxis

Type: scalar

Values: 0-90

Default: 60

Speed Loop

Type — Speed loop PID controller actions

PI (default) | PID | PIDF | ...

Specify the type of PID controller associated with the speed control loop.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use

Block Parameter: PIDTypeSpeed

Type: character vector

Values: 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'

Default: 'PI'

Form — Speed loop PID controller form

Parallel (default) | Ideal

Specify the PID controller form associated with your speed control loop.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- **Parallel** — In **Parallel** form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see **Integrator method** and **Filter method**).

Other controller actions amount to setting P , I , or D to zero.

- **Ideal** — In **Ideal** form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to **Inf**. (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes

Programmatic Use

Block Parameter: PIDFormSpeed

Type: character vector

Values: 'Parallel' | 'Ideal'

Default: 'Parallel'

Controller sample time (sec) — Speed loop PID controller sample time

0.1 (default) | positive scalar | -1

Specify the sample time of your PID controller associated with the speed control loop in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s ω_c is the controller sample time that you specify with the **Controller sample time (sec)** parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use

Block Parameter: TsSpeed

Type: scalar

Value positive scalar | -1

Default: 0.1

Integrator method — Speed loop controller discrete integration formula for integrator term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{N + F_d(z)} \right).$$

For a controller sample time T_s , the Integrator method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes integral action.

Programmatic Use

Block Parameter: IntegratorMethodSpeed

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Filter method — Speed loop controller discrete integration formula for derivative filter term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Filter method** parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z-1}$
Backward Euler	$\frac{T_s z}{z-1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodSpeed

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) — Speed loop target crossover frequency of tuned response
1 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use**Block Parameter:** BandwidthSpeed**Type:** positive scalar**Default:** 1**Target phase margin (degrees) — Speed loop target minimum phase margin**

60 (default) | scalar in range 0-90

Specify a target minimum phase margin for the tuned open-loop response associated with the speed control loop at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°–60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5–10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes**Programmatic Use****Block Parameter:** TargetPMSpeed**Type:** scalar**Values:** 0–90**Default:** 60**Flux Loop****Type — Flux loop PID controller actions**

PI (default) | PID | PIDF | ...

Specify the type of PID controller associated with the flux control loop.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use**Block Parameter:** PIDTypeFlux**Type:** character vector**Values:** 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'**Default:** 'PI'

Form — Flux loop PID controller form

Parallel (default) | Ideal

Specify the PID controller form associated with your flux control loop.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- **Parallel** — In **Parallel** form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see **Integrator** method and **Filter** method).

Other controller actions amount to setting P , I , or D to zero.

- **Ideal** — In **Ideal** form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to Inf. (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes

Programmatic Use

Block Parameter: PIDFormFlux

Type: character vector

Values: 'Parallel' | 'Ideal'

Default: 'Parallel'

Controller sample time (sec) — Flux loop PID controller sample time

0.1 (default) | positive scalar | -1

Specify the sample time of your PID controller associated with the flux control loop in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s ω_c is the controller sample time that you specify with the **Controller sample time (sec)** parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use

Block Parameter: TsFlux

Type: scalar

Value: positive scalar | -1

Default: 0.1

Integrator method — Flux loop controller discrete integration formula for integrator term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the Integrator method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes integral action.

Programmatic Use

Block Parameter: IntegratorMethodFlux

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Filter method — Flux loop controller discrete integration formula for derivative filter term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the Filter method parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodFlux

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) – Flux loop target crossover frequency of tuned response

1 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use

Block Parameter: BandwidthFlux

Type: positive scalar

Default: 1

Target phase margin (degrees) — Flux loop target minimum phase margin

60 (default) | scalar in range 0-90

Specify a target minimum phase margin for the tuned open-loop response associated with the flux control loop at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°-60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5-10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes

Programmatic Use

Block Parameter: TargetPMFlux

Type: scalar

Values: 0-90

Default: 60

Current Loops (Q-axis + D-axis)

Type — Current loop PID controller actions

PI (default) | PID | PIDF | ...

Specify the type of PID controller associated with the current control loops.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use

Block Parameter: PIDTypeAllInner

Type: character vector

Values: 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'

Default: 'PI'

Form — Current loop PID controller form

Parallel (default) | Ideal

Specify the PID controller form associated with your current control loops.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- **Parallel** — In **Parallel** form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see **Integrator method** and **Filter method**).

Other controller actions amount to setting P , I , or D to zero.

- **Ideal** — In **Ideal** form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to Inf. (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes

Programmatic Use

Block Parameter: PIDFormAllInner

Type: character vector

Values: 'Parallel' | 'Ideal'

Default: 'Parallel'

Controller sample time (sec) — Current loop PID controller sample time

0.001 (default) | positive scalar | -1

Specify the sample time of your PID controllers associated with the current control loops in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s ω_c is the controller sample time that you specify with the **Controller sample time (sec)** parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use**Block Parameter:** TsAllInner**Type:** scalar**Value** positive scalar | -1**Default:** 0.001**Integrator method — Current loop controller discrete integration formula for integrator term**

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the Integrator method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes**Dependencies**

This parameter is enabled when the controller includes integral action.

Programmatic Use**Block Parameter:** IntegratorMethodAllInner**Type:** character vector**Values:** 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'**Default:** 'Forward Euler'**Filter method — Current loop controller discrete integration formula for derivative filter term**

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Filter method** parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodAllInner

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) — Current loop target crossover frequency of tuned responses

100 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use

Block Parameter: BandwidthAllInner

Type: positive scalar

Default: 1

Target phase margin (degrees) — Current loop target minimum phase margins

60 (default) | scalar in range 0-90

Specify target minimum phase margin for the tuned open-loop responses associated with the current control loops at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°-60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5-10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes

Programmatic Use

Block Parameter: TargetPMAAllInner

Type: scalar

Values: 0-90

Default: 60

Outer Loops (Speed + Flux)

Type — Outer loop PID controller actions

PI (default) | PID | PIDF | ...

Specify the type of PID controllers associated with the outer control loops.

The controller type indicates what actions are present in the controller that regulates the loop. The following controller types are available for PID autotuning:

- P — Proportional only
- I — Integral only
- PI — Proportional and integral
- PD — Proportional and derivative
- PDF — Proportional and derivative with derivative filter
- PID — Proportional, integral, and derivative
- PIDF — Proportional, integral, and derivative with derivative filter

Make sure the controller type matches the controller that regulates the loop.

Programmatic Use**Block Parameter:** PIDTypeAllOuter**Type:** character vector**Values:** 'P' | 'I' | 'PI' | 'PD' | 'PDF' | 'PID' | 'PIDF'**Default:** 'PI'**Form — Outer loop PID controller form**

Parallel (default) | Ideal

Specify the PID controller form associated with your outer control loops.

The controller form determines the interpretation of the PID coefficients P , I , D , and N .

- **Parallel** — In **Parallel** form, the transfer function of a discrete-time PIDF controller is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

where $F_i(z)$ and $F_d(z)$ are the integrator and filter formulas (see **Integrator method** and **Filter method**).

Other controller actions amount to setting P , I , or D to zero.

- **Ideal** — In **Ideal** form, the transfer function of a discrete-time PIDF controller is

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

Other controller actions amount to setting D to zero or setting I to Inf. (In ideal form, the controller must have proportional action.)

Make sure the controller form matches the controller that regulates the loop.

Tunable: Yes**Programmatic Use****Block Parameter:** PIDFormAllOuter**Type:** character vector**Values:** 'Parallel' | 'Ideal'**Default:** 'Parallel'**Controller sample time (sec) — Outer loop PID controller sample time**

0.1 (default) | positive scalar | -1

Specify the sample time of your PID controllers associated with the outer control loop in seconds. This value also sets the sample time for the experiment performed by the block.

To perform PID tuning, the block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter.

Make sure the controller sample time matches the controller that regulates the loop.

Tips

If you want to run the deployed block with different sample times in your application, set this parameter to -1 and put the block in a Triggered Subsystem. Then, trigger the subsystem at the

desired sample time. If you do not plan to change the sample time after deployment, specify a fixed and finite sample time.

Programmatic Use

Block Parameter: TsAllOuter

Type: scalar

Value: positive scalar | -1

Default: 0.1

Integrator method — Outer loop controller discrete integration formula for integrator term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the integrator term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the Integrator method parameter determines the formula F_i as follows.

Integrator method	F_i
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller integrator method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes integral action.

Programmatic Use

Block Parameter: IntegratorMethodAllOuter

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Filter method – Outer loop controller discrete integration formula for derivative filter term

Forward Euler (default) | Backward Euler | Trapezoidal

Specify the discrete integration formula for the derivative filter term in your controller. In discrete time, the PID controller transfer function assumed by the block is

$$C = P + F_i(z)I + \frac{D}{N + F_d(z)},$$

in parallel form, or in ideal form,

$$C = P \left(1 + \frac{F_i(z)}{I} + \frac{D}{D/N + F_d(z)} \right).$$

For a controller sample time T_s , the **Filter method** parameter determines the formula F_d as follows.

Filter method	F_d
Forward Euler	$\frac{T_s}{z - 1}$
Backward Euler	$\frac{T_s z}{z - 1}$
Trapezoidal	$\frac{T_s z + 1}{2 z - 1}$

For more information about the relative advantages of each method, see the Discrete PID Controller block reference page.

Make sure the controller derivative filter method matches the controller that regulates the loop.

Tunable: Yes

Dependencies

This parameter is enabled when the controller includes derivative action with a derivative filter term.

Programmatic Use

Block Parameter: FilterMethodAllOuter

Type: character vector

Values: 'Forward Euler' | 'Backward Euler' | 'Trapezoidal'

Default: 'Forward Euler'

Target bandwidth (rad/sec) – Outer loop target crossover frequency of tuned responses

1 (default) | positive scalar

The target bandwidth is the target value for the 0 dB gain crossover frequency of the tuned open-loop response CP , where P is the plant response associated with the loop, and C is the controller response. This crossover frequency roughly sets the control bandwidth. For a rise time τ , a good guess for the target bandwidth is $2/\tau$.

To perform PID tuning, the autotuner block measures frequency-response information up to a frequency of 10 times the target bandwidth. To ensure that this frequency is less than the Nyquist

frequency, the target bandwidth ω_c must satisfy $\omega_c T_s \leq 0.3$, where T_s is the controller sample time that you specify with the **Controller sample time (sec)** parameter. Because of this condition, the fastest rise time you can enforce for tuning is about $1.67T_s$. If this rise time does not meet your design goals, consider reducing T_s .

For best results, use a target bandwidth that is within about a factor of 10 of the bandwidth with the initial PID controller. To tune a controller for a larger change in bandwidth, tune incrementally using smaller changes.

To provide the target bandwidth by using an input port, on the Block tab, select **Use external source for bandwidth**.

Programmatic Use

Block Parameter: BandwidthAllOuter

Type: positive scalar

Default: 1

Target phase margin (degrees) — Outer loop target minimum phase margins

60 (default) | scalar in range 0-90

Specify a target minimum phase margin for the tuned open-loop responses associated with the outer control loops at the crossover frequency.

The target phase margin reflects the desired robustness of the tuned system. Typically, choose a value in the range of about 45°-60°. In general, a higher phase margin reduces overshoot, but can limit the response speed. The default value 60° tends to balance performance and robustness, yielding about 5-10% overshoot, depending on the characteristics of your plant.

To provide the target phase margin by using an input port, on the Block tab, select **Use external source for target phase margins**.

Tunable: Yes

Programmatic Use

Block Parameter: TargetPMAAllOuter

Type: scalar

Values: 0-90

Default: 60

Experiment Tab

Experiment Start/Stop

D-axis current loop start time (sec) — Specify direct-axis current loop tuning experiment start time

1 (default)

Specify the simulation time when the d-axis current loop tuning experiment starts.

Programmatic Use

Block Parameter: StartTimeDaxis

Type: positive scalar

Default: 1

D-axis current loop experiment duration (sec) – Specify direct-axis current loop tuning experiment duration

0.05 (default)

Specify the d-axis current loop tuning experiment duration.

Programmatic Use**Block Parameter:** DurationDaxis**Type:** positive scalar**Default:** 0.05**Q-axis current loop start time (sec) – Specify quadrature-axis current loop tuning experiment start time**

1.1 (default)

Specify the simulation time when the q-axis current loop tuning experiment starts.

Programmatic Use**Block Parameter:** StartTimeQaxis**Type:** positive scalar**Default:** 1.1**Q-axis current loop experiment duration (sec) – Specify quadrature-axis current loop tuning experiment duration**

0.05 (default)

Specify the q-axis current loop tuning experiment duration.

Programmatic Use**Block Parameter:** DurationQaxis**Type:** positive scalar**Default:** 0.05**Speed loop start time (sec) – Specify speed loop tuning experiment start time**

2 (default)

Specify the simulation time when the speed loop tuning experiment starts.

Programmatic Use**Block Parameter:** StartTimeSpeed**Type:** positive scalar**Default:** 2**Speed loop experiment duration (sec) – Specify speed loop tuning experiment duration**

3 (default)

Specify the speed loop tuning experiment duration.

Programmatic Use**Block Parameter:** DurationSpeed**Type:** positive scalar**Default:** 3**Flux loop start time (sec) – Specify flux loop tuning experiment start time**

6 (default)

Specify the simulation time when the flux tuning experiment starts.

Programmatic Use

Block Parameter: StartTimeFlux

Type: positive scalar

Default: 6

Flux loop experiment duration (sec) — Specify flux loop tuning experiment duration
3 (default)

Specify the flux loop tuning experiment duration.

Programmatic Use

Block Parameter: DurationFlux

Type: positive scalar

Default: 3

D-axis Current Loop

Plant Type — Stability of direct-axis current plant

Stable (default) | Integrating

Specify whether the plant associated with the d-axis current control loop is stable or integrating. If the plant has one or more integrators, select *Integrating*.

Programmatic Use

Block Parameter: PlantTypeDaxis

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of direct-axis current plant

Positive (default) | Negative

Specify whether the plant associated with the d-axis current control loop is positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify *Positive*. Otherwise, specify *Negative*. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignDaxis

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in direct-axis current loop

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the

same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level
- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineDaxis

Type: scalar, vector of length 5

Default: 1

Q-axis Current Loop

Plant Type — Stability of quadrature-axis current plant

Stable (default) | Integrating

Specify whether the plant associated with the q-axis current control loop is stable or integrating. If the plant has one or more integrators, select **Integrating**.

Programmatic Use

Block Parameter: PlantTypeQaxis

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of quadrature-axis current plant

Positive (default) | Negative

Specify whether the plant associated with the q-axis current control loop is positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify **Positive**. Otherwise, specify **Negative**. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignQaxis

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in quadrature-axis current loop

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level
- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineQaxis

Type: scalar, vector of length 5

Default: 1

Speed Loop

Plant Type — Stability of speed loop plant

Stable (default) | Integrating

Specify whether the plant associated with the speed control loop is stable or integrating. If the plant has one or more integrators, select Integrating.

Programmatic Use

Block Parameter: PlantTypeSpeed

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of speed loop plant

Positive (default) | Negative

Specify whether the plant associated with the speed control loop is positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify **Positive**. Otherwise, specify **negative**. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignSpeed

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in speed loop

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level
- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineSpeed

Type: scalar, vector of length 5

Default: 1

Flux Loop

Plant Type — Stability of flux loop plant

Stable (default) | Integrating

Specify whether the plant associated with the flux control loop is stable or integrating. If the plant has one or more integrators, select **Integrating**.

Programmatic Use

Block Parameter: PlantTypeFlux

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of flux loop plant

Positive (default) | Negative

Specify whether the plant associated with the flux control loop is positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify **Positive**. Otherwise, specify **Negative**. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignFlux

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in flux loop

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level
- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineFlux

Type: scalar, vector of length 5

Default: 1

Current Loops (D-axis + Q-axis)

Plant Type — Stability of current loop plants

Stable (default) | Integrating

Specify whether the plants associated with the current control loops are stable or integrating. If the plant has one or more integrators, select Integrating.

Programmatic Use

Block Parameter: PlantTypeAllInner

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of current loop plants

Positive (default) | Negative

Specify whether the plants associated with the current control loops are positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify Positive. Otherwise, specify negative. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignAllInner

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in current loops

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level

- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineAllInner

Type: scalar, vector of length 5

Default: 1

Outer Loops (Speed + Flux)

Plant Type — Stability of outer loop plants

Stable (default) | Integrating

Specify whether the plants associated with the outer control loops are stable or integrating. If the plant has one or more integrators, select Integrating.

Programmatic Use

Block Parameter: PlantTypeAllOuter

Type: character vector

Values: 'Stable' | 'Integrating'

Default: 'Stable'

Plant Sign — Sign of outer loop plants

Positive (default) | Negative

Specify whether the plants associated with the outer control loops are positive or negative. If a positive change in the plant input at the nominal operating point results in a positive change in the plant output, specify Positive. Otherwise, specify negative. For stable plants, the sign of the plant is the sign of the plant DC gain.

Programmatic Use

Block Parameter: PlantSignAllOuter

Type: character vector

Values: 'Positive' | 'Negative'

Default: 'Positive'

Sine Amplitudes — Amplitude of sinusoidal perturbations in outer loops

1 (default) | scalar | vector of length 5

During the experiment, the block injects a sinusoidal signal into the plant associated with the loop at the frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$, where ω_c is the target bandwidth for tuning. Use **Sine Amplitudes** to specify the amplitude of each of these injected signals. Specify a:

- Scalar value to inject the same amplitude at each frequency
- Vector of length 5 to specify a different amplitude at each of $[1/10, 1/3, 1, 3, 10]\omega_c$

In a typical plant with typical target bandwidth, the magnitudes of the plant responses at the experiment frequencies do not vary widely. In such cases, you can use a scalar value to apply the same magnitude perturbation at all frequencies. However, if you know that the response decays sharply over the frequency range, consider decreasing the amplitude of the lower frequency inputs and increasing the amplitude of the higher frequency inputs. It is numerically better for the estimation experiment when all the plant responses have comparable magnitudes.

The perturbation amplitudes must be:

- Large enough that the perturbation overcomes any deadband in the plant actuator and generates a response above the noise level
- Small enough to keep the plant running within the approximately linear region near the nominal operating point, and to avoid saturating the plant input or output

In the experiment, the sinusoidal signals are superimposed. Thus, the perturbation can be at least as large as the sum of all amplitudes. Make sure that the largest possible perturbation is within the range of your plant actuator. Saturating the actuator can introduce errors into the estimated frequency response.

To provide the sine amplitudes by using an input port, on the Block tab, select **Use external source for sine amplitudes**.

Tunable: Yes

Programmatic Use

Block Parameter: AmpSineAllOuter

Type: scalar, vector of length 5

Default: 1

Block Tab

Use external source for bandwidths — Supply external signal for target bandwidths

off (default) | on

Select this parameter to enable the bandwidth input port of the block. You can specify the target bandwidth for all the loops the block tunes at this port. When this parameter is disabled, specify the target bandwidths at the block parameters. For more details, see the bandwidth port description.

Programmatic Use

Block Parameter: UseExternalWc

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Use external source for target phase margins — Supply external signal for target phase margin

off (default) | on

Select this parameter to enable the target PM input port of the block. You can specify the target phase margin for all the loops the block tunes at this port. When this parameter is disabled, specify the target phase margins at the block parameters. For more details, see the target PM port description.

Programmatic Use

Block Parameter: UseExternalPM

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Use external source for start/stops of experiment — Supply external signal for start and stop of tuning experiment

off (default) | on

Select this parameter to enable the `start/stop` and `ActiveLoop` input ports of the block. You can specify the start and stop of the experiment and which loop the block tunes at these ports. When this parameter is disabled, specify the start time and duration of the tuning experiment at the block parameters. For more details, see the `start/stop` and `ActiveLoop` port descriptions.

Programmatic Use

Block Parameter: `UseExternalSourceStartStop`

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Use external source for sine amplitudes — Supply external signal for sinusoidal perturbation amplitude

off (default) | on

Select this parameter to enable the `sine Amp` input port of the block. You can specify sinusoidal perturbation amplitude for all the loops the block tunes at this port. When this parameter is disabled, supply the sine amplitudes at block parameters. For more details, see the `sine Amp` port description.

Programmatic Use

Block Parameter: `UseExternalAmpSine`

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Data Type — Floating point precision

double (default) | single

Specify the floating-point precision based on the simulation environment or hardware requirements.

Programmatic Use

Block Parameter: `BlockDataType`

Type: character vector

Values: 'double' | 'single'

Default: 'double'

Estimated phase margin achieved by tuned controllers — Phase margin achieved by most recently tuned loop

off (default) | on

Select this parameter to enable the `estimated PM` output port of the block. The block returns the phase margin achieved by the tuned controller of the most recently tuned loop. When this parameter is disabled, you can see the tuning results by using the **Export to MATLAB** parameter. For more details, see the `estimated PM` port description.

Programmatic Use

Block Parameter: `UseExternalAchievedPM`

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Plant frequency responses near bandwidth — Estimated frequency response for most recently tuned loop

off (default) | on

Select this parameter to enable the `frd` output port of the block. The block returns the estimated frequency response of the most recently tuned loop. When this parameter is disabled, you can see the tuning results by using the **Export to MATLAB** parameter. For more details, see the `frd` port description.

Programmatic Use

Block Parameter: UseExternalFRD

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Plant nominal input and output — Plant input and output at nominal operating point

off (default) | on

Select this parameter to enable the `nominal` output port of the block. The block returns the plant input and output at the nominal operating point of the most recently tuned loop. When this parameter is disabled, you can see the tuning results by using the **Export to MATLAB** parameter. For more details, see the port description.

Programmatic Use

Block Parameter: UseExternalU0

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Start/stop of autotuning process — Signal indicating start and end of experiment for each tuned loop

off (default) | on

Select this parameter to enable `loop_start/stops` output port of the block. The block returns a signal indicating the times at which the autotuning experiment started and ended for each loop tuned by the block. When this parameter is disabled, you can see the tuning results by using the **Export to MATLAB** parameter. For more details, see the `loop_start/stops` port description.

Programmatic Use

Block Parameter: UseExternalActiveLoop

Type: character vector

Values: 'off' | 'on'

Default: 'off'

Export to MATLAB — Send experiment and tuning results to MATLAB workspace

button

When you click this button, the block creates a structure in the MATLAB® workspace containing the experiment and tuning results. This structure, `FOCTuningResult`, contains the tuning results for each loop the block tunes.

- **Daxis** — D-axis current loop tuning results
- **Qaxis** — Q-axis current loop tuning results
- **Speed** — Speed loop tuning results
- **Flux** — Flux loop tuning results

For each loop tuned by the block, the result contains the following fields:

- **P, I, D, N** — Tuned PID gains. The structure contains whichever of these fields are necessary for the controller type you are tuning. For instance, if you are tuning a PI controller, the structure contains P and I, but not D and N.
- **TargetBandwidth** — The value you specified in the **Target bandwidth (rad/sec)** parameter of the block.
- **TargetPhaseMargin** — The value you specified in the **Target phase margin (degrees)** parameter of the block.
- **EstimatedPhaseMargin** — Estimated phase margin achieved by the tuned system.
- **Controller** — The tuned PID controller, returned as a **pid** (for parallel form) or **pidstd** (for ideal form) model object.
- **Plant** — The estimated plant, returned as an **frd** model object. This **frd** contains the response data obtained at the experiment frequencies $[1/10, 1/3, 1, 3, 10]\omega_c$.
- **PlantNominal** — The plant input and output at the nominal operating point when the experiment begins, specified as a structure with the fields **u** (input) and **y** (output).

You can export to the MATLAB workspace while the simulation is running, including when running in external mode.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

The generated code for this block can be resource heavy. For real-time applications, deploying the code on rapid prototyping hardware, such as the Speedgoat real-time target machine, is recommended.

PLC Code Generation

Generate Structured Text code using Simulink® PLC Coder™.

See Also

Topics

“Tune PID Controllers by Using Field-Oriented Control Autotuner”

Introduced in R2020a