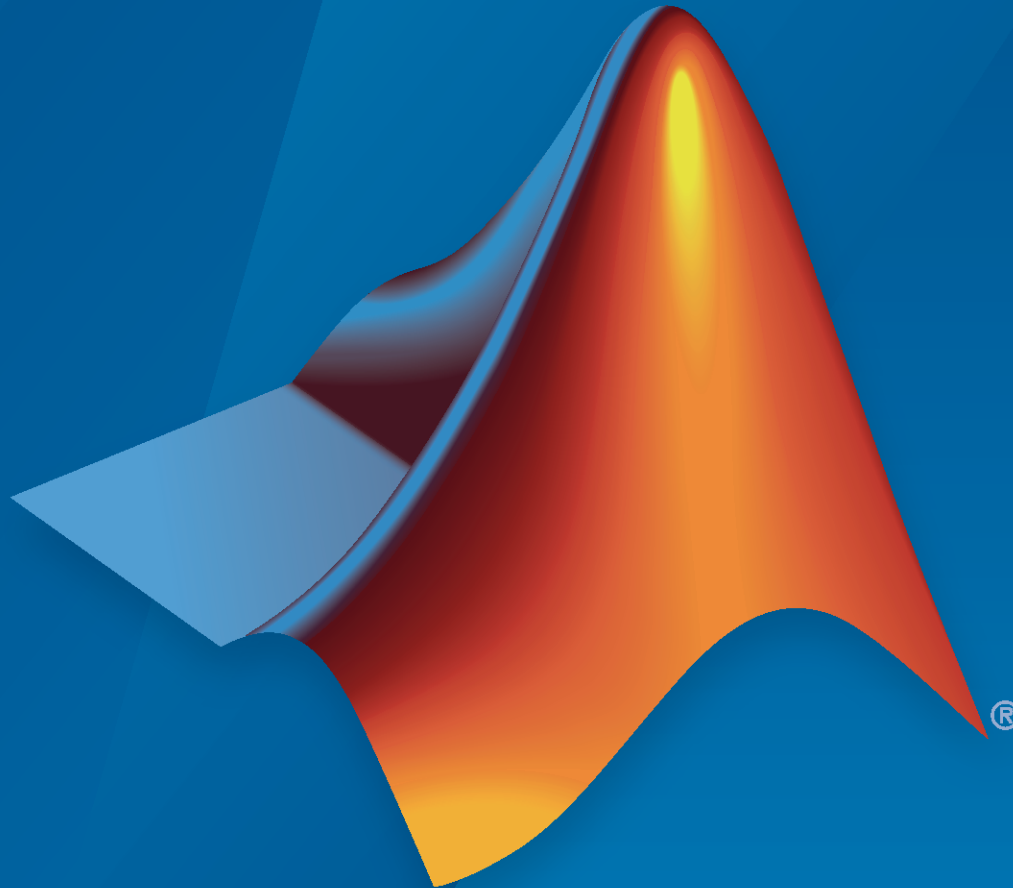


Motor Control Blockset™

Getting Started Guide



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Motor Control Blockset™ Getting Started Guide

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Product Overview

Motor Control Blockset Product Description

Design and implement motor control algorithms

Motor Control Blockset provides Simulink® blocks for creating and tuning field-oriented control and other algorithms for brushless motors. Blocks include Park and Clarke transforms, sensorless observers, field weakening, a space-vector generator, and an FOC autotuner. You can verify control algorithms in closed-loop simulation using the motor and inverter models included in the blockset.

The blockset parameter estimation tool runs predefined tests on your motor hardware for accurate estimation of stator resistance, d -axis and q -axis inductance, back EMF, inertia, and friction. You can incorporate these motor parameter values into a closed-loop simulation to analyze your controller design.

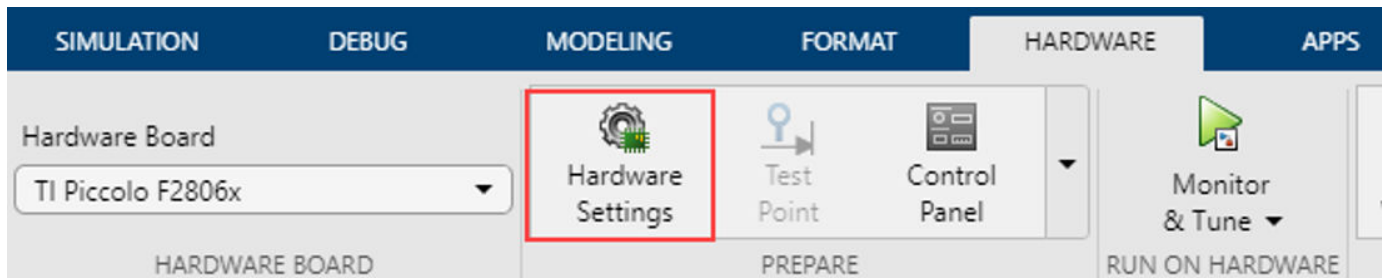
Reference examples show how to verify control algorithms in desktop simulation and generate compact C code that supports execution rates required for production implementation. The reference examples can also be used to implement algorithms for motor control hardware kits supported by the blockset.

Model Configuration Parameters

Model Configuration Parameters

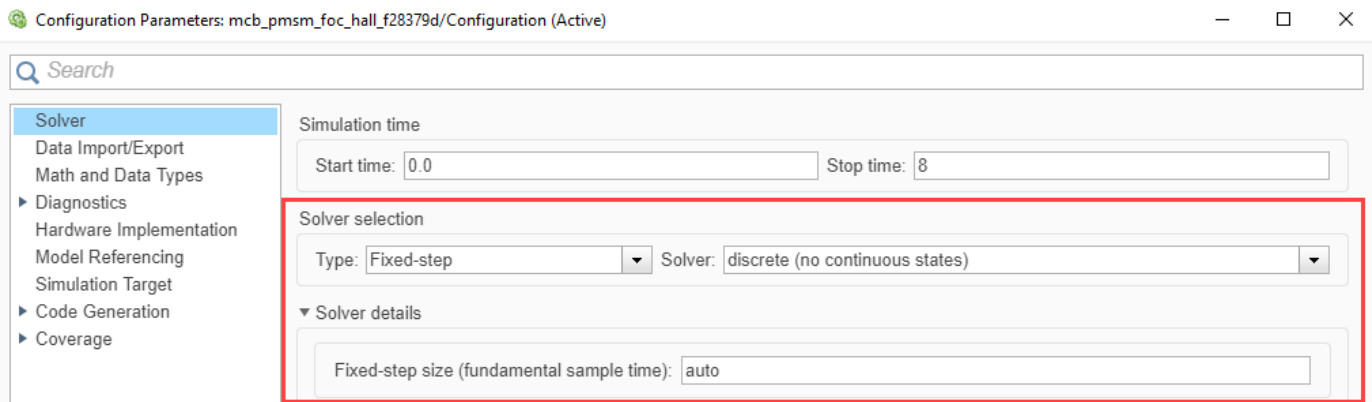
Update the configuration parameters for a Simulink model that you create, before simulating or deploying the model to the controller.

In the Simulink window, click **Hardware Settings** in the **HARDWARE** tab to open the Configuration Parameters dialog box and select the target hardware in the **Hardware board** field.



Solver Configuration

In the **Solver** tab of the Configuration Parameters dialog box, for a fixed-step discrete solver, type **auto** in the **Fixed-step size (fundamental sample time)** field.

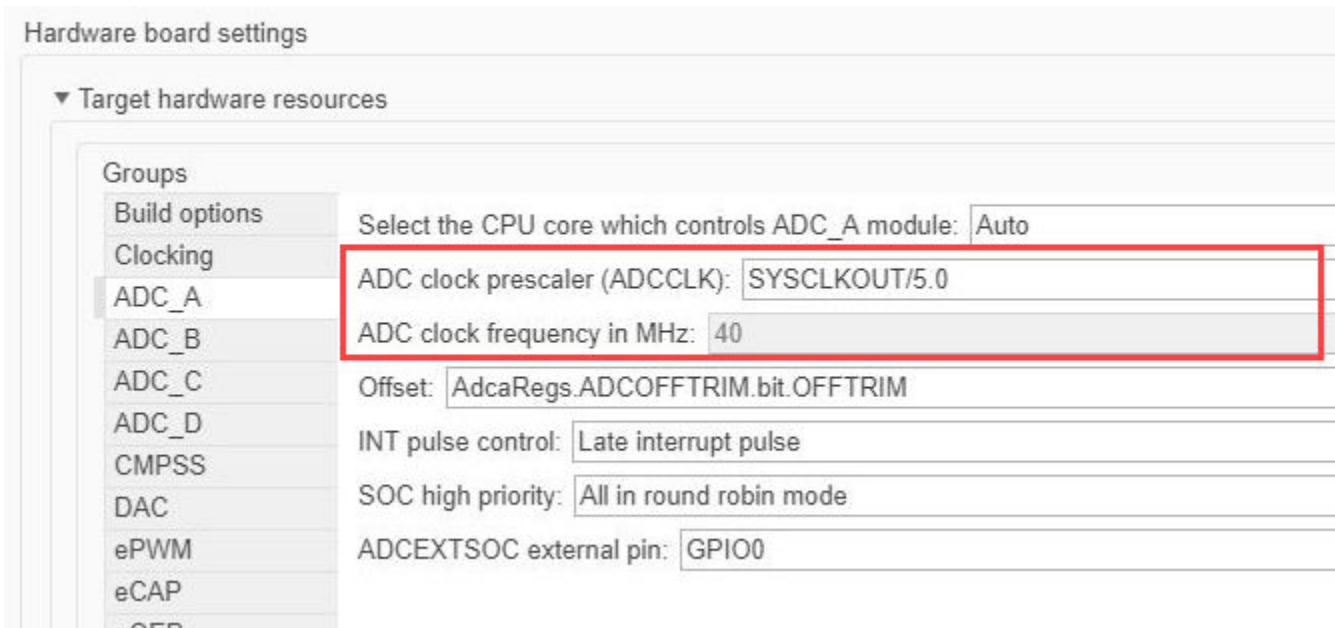


ADC Interface Configuration

If you connect analog inputs (current or voltage sensors) to the hardware board, configure the related ADC parameters in the Configuration Parameters dialog box by using these steps:

- 1 Open the **Hardware Implementation** tab.
- 2 Set the ADC clock prescaler and check the ADC clock frequency. Ensure that the displayed ADC clock frequency is less than the maximum value specified in the device datasheet.

This example shows the ADC configuration for LAUNCHXL-F28379D board. The maximum operating frequency of ADCCLK for TMS320F28379D targets is 50 MHz.

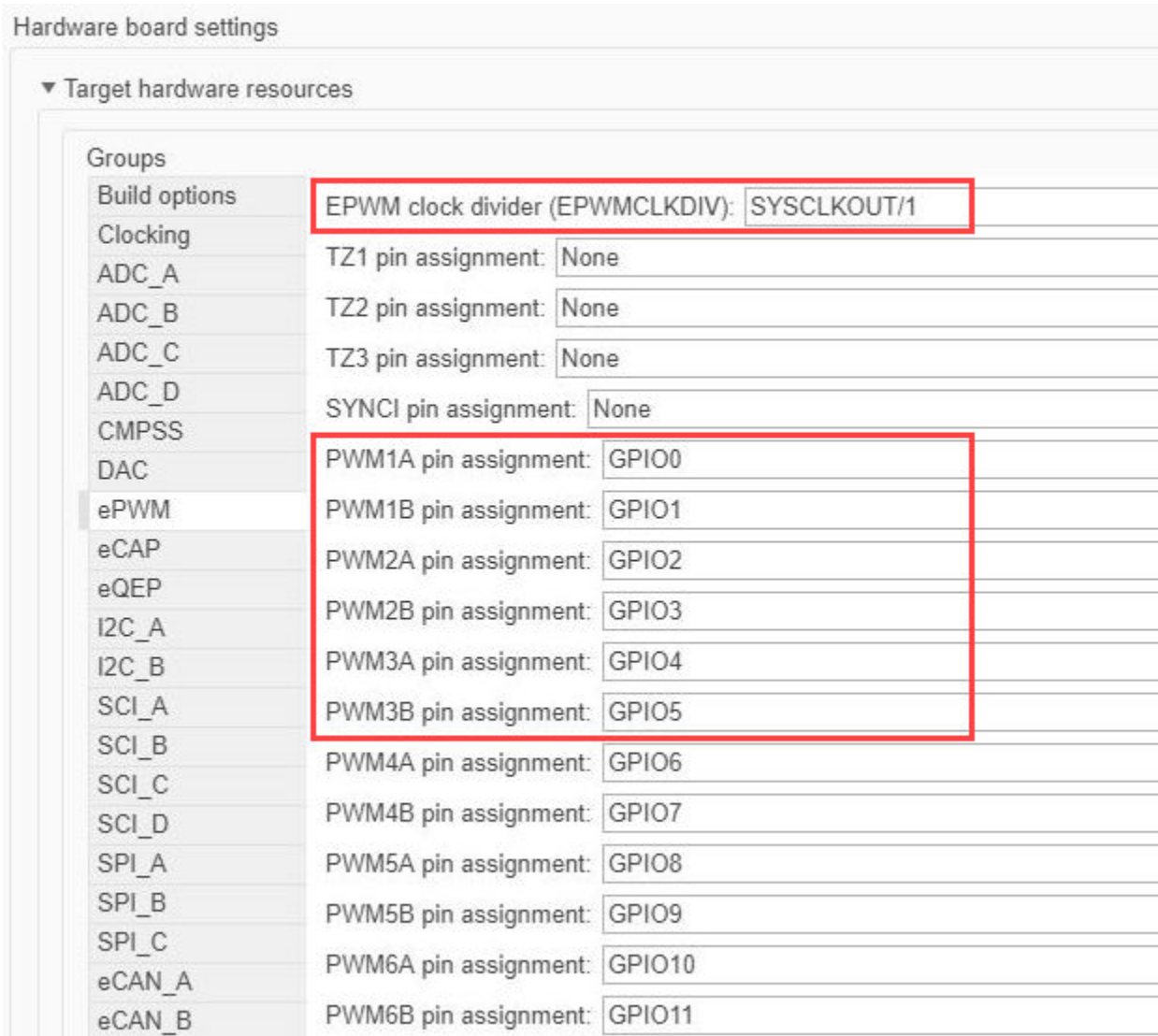


PWM Interface Configuration

If you connect PWM outputs from target device to the inverter, configure the related PWM parameters in the Configuration Parameters dialog box by using the following steps:

- 1 Open the **Hardware Implementation** tab.
- 2 Set the ePWM clock divider to SYSCLKOUT/1.
- 3 Update the following PWM pin assignment fields.

ePWM pin settings	Property
PWM1A pin assignment	Gate pulse for Phase-A high-side transistor
PWM1B pin assignment	Gate pulse for Phase-A low-side transistor
PWM2A pin assignment	Gate pulse for Phase-B high-side transistor
PWM2B pin assignment	Gate pulse for Phase-B low-side transistor
PWM3A pin assignment	Gate pulse for Phase-C high-side transistor
PWM3B pin assignment	Gate pulse for Phase-C low-side transistor



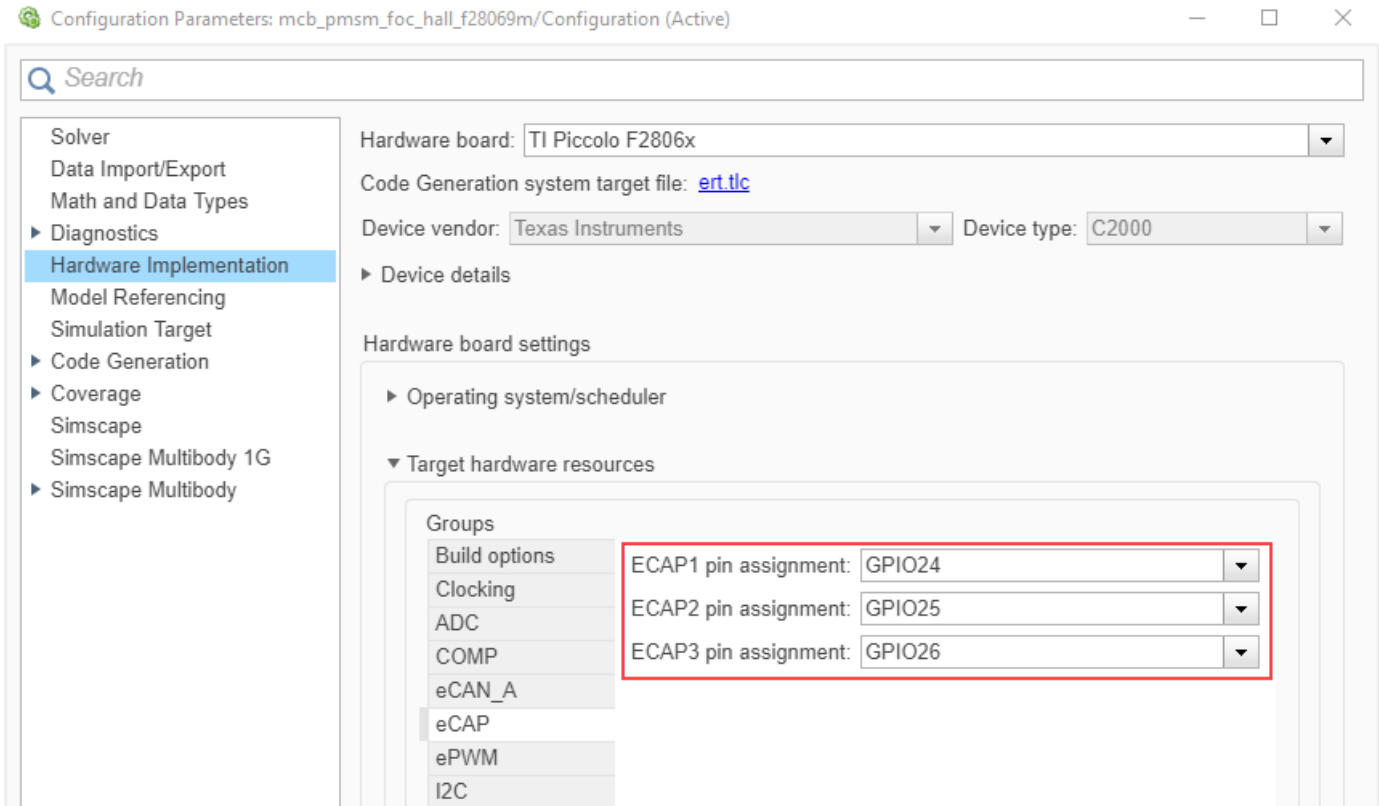
Hall Sensor Interface Configuration

If you connect a Hall sensor to the hardware board, configure the related parameters in the Configuration Parameters dialog box by using the following steps:

- 1 Open the **Hardware Implementation** tab.
- 2 Select the **eCAP** group under **Hardware board settings > Target hardware resources**.
- 3 Update the following ECAP pin assignment fields:

ECAP pin assignment field	Field value
ECAP1 pin assignment	Hall A
ECAP2 pin assignment	Hall B
ECAP3 pin assignment	Hall C

The following example shows the eCAP configuration for a Hall sensor connected to DRV8312 board with a F28069 Piccolo MCU control card:



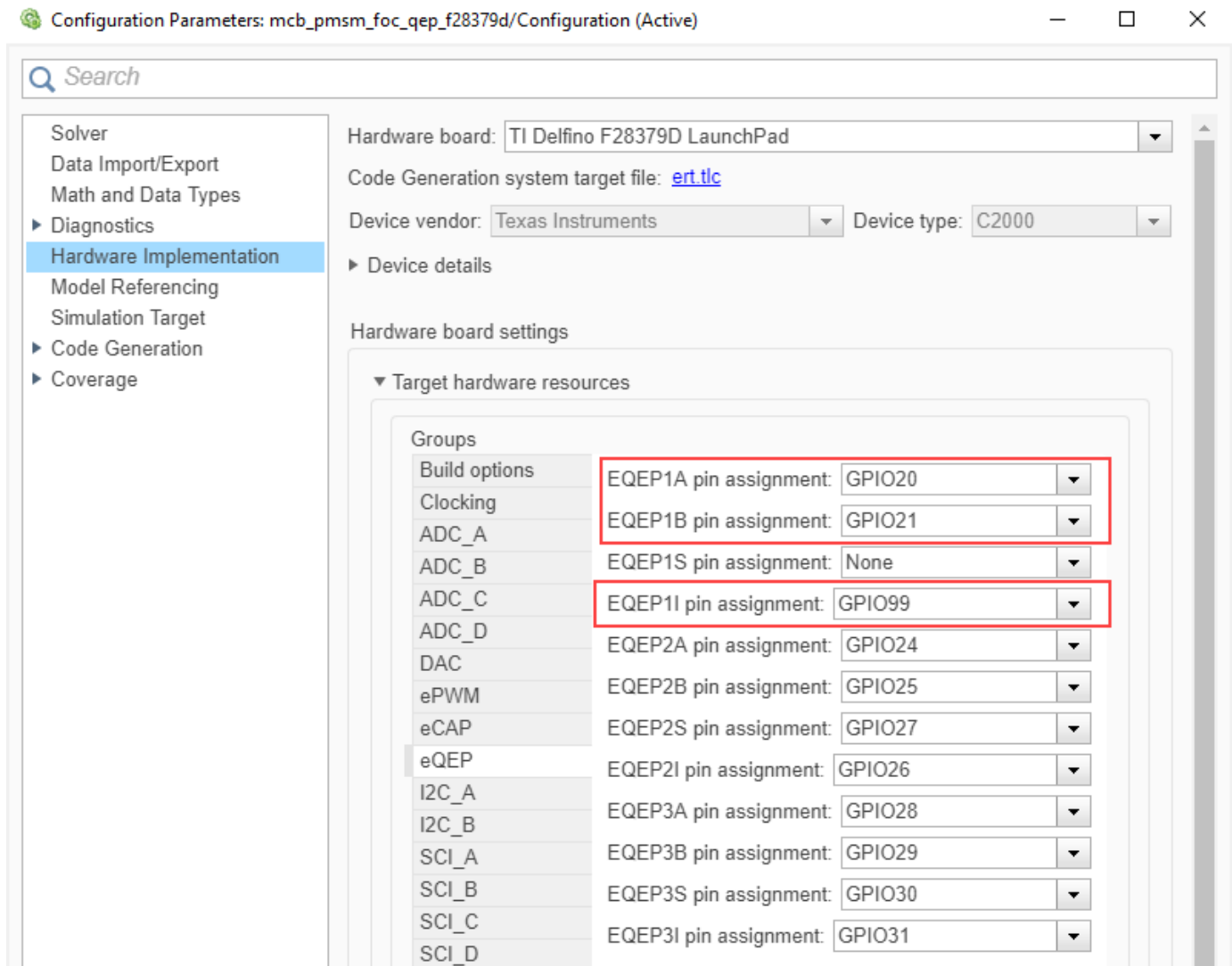
Quadrature Encoder Interface Configuration

If you connect a Quadrature Encoder sensor to the hardware board, configure the related parameters in the Configuration Parameters dialog box by using the following steps:

- 1 Open the **Hardware Implementation** tab.
- 2 Select the **eQEP** group under **Hardware board settings > Target hardware resources**.
- 3 Update the following EQEP pin assignment fields:

EQEP pin assignment field	Property
EQEP1A pin assignment	Quadrature Encoder Channel A
EQEP1B pin assignment	Quadrature Encoder Channel B
EQEP1I pin assignment	Quadrature Encoder Index

The following example shows the eQEP configuration for a quadrature encoder sensor connected to a LAUNCHXL-F28379D board:



Serial Communication Interface Configuration

If you are generating code and using serial communication between host and target Simulink models, configure the related parameters in the Configuration Parameters dialog box by using the following steps:

- 1 Open the **Hardware Implementation** tab.
- 2 Select the **SCI_A** group under **Hardware board settings > Target hardware resources**.
- 3 Update the following SCI_A settings:

SCI_A settings	Property
Suspension mode	Serial suspension mode
Number of stop bits	Stop bits
Parity mode	Parity

SCI_A settings	Property
Character length bits	Data bits
Desired baud rate in bits/sec	Serial communication baud rate
Pin assignment(Tx)	Output pin for Serial Transmit
Pin assignment(Rx)	Input pin for Serial Receive

For example, use the following SCI_A configuration for a Hall sensor connected to a F28379D LaunchPad board:

The screenshot shows the Configuration Parameters tool for the TI Delfino F28379D LaunchPad. The left sidebar lists various hardware resources, with SCI_A selected. The main panel shows the configuration for SCI_A, with several fields highlighted by red boxes:

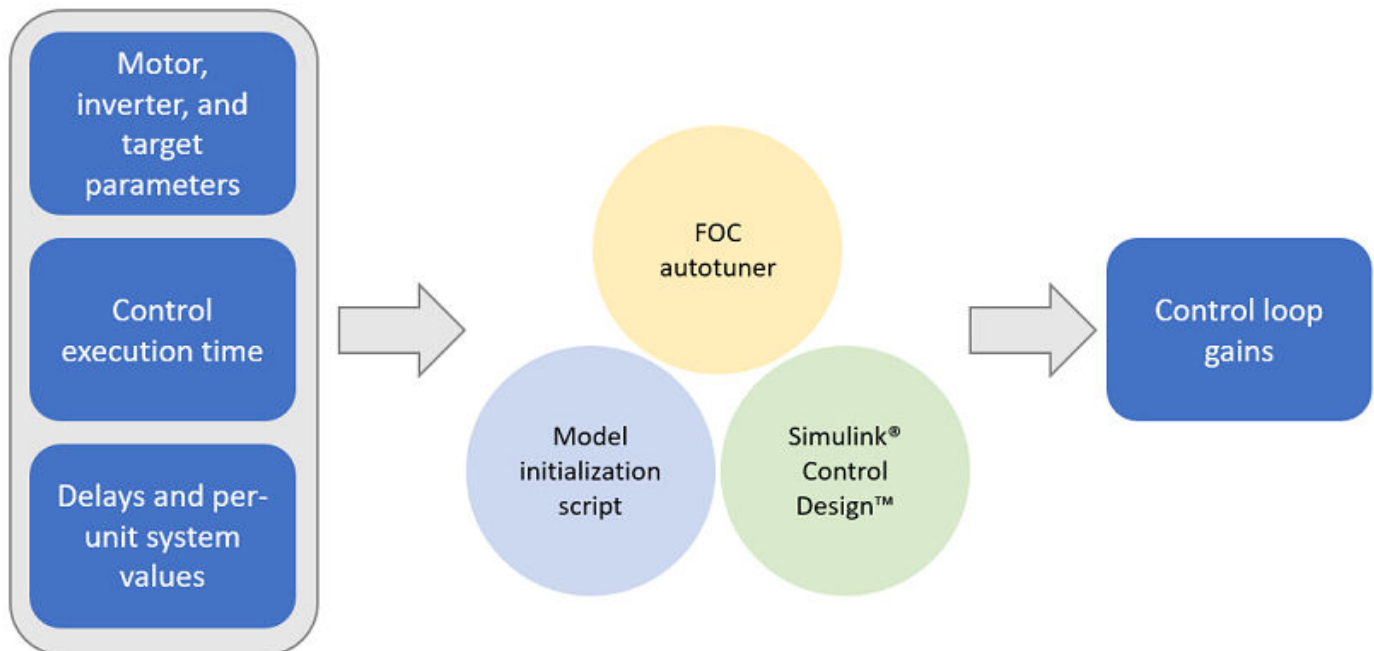
- Suspension mode:** Free_run
- Number of stop bits:** 1
- Parity mode:** None
- Character length bits:** 8
- Desired baud rate in bits/sec:** 5e6
- Baud rate prescaler (BRR = (SCIHBAUD << 8) | SCILBAUD):** 4
- Closest achievable baud rate (LSPCLK/(BRR+1)/8) in bits/sec:** 5000000
- Communication mode:** Raw_data
- Blocking mode:** (unchecked)
- Data byte order:** Little_Endian
- Pin assignment(Tx):** GPIO42
- Pin assignment(Rx):** GPIO43

Estimate Control Gains from Motor Parameters

Estimate Control Gains from Motor Parameters

Perform control parameter tuning for the speed and the torque control loops that are part of the Field-Oriented Control (FOC) algorithm. Motor Control Blockset provides you with multiple methods to compute the control loop gains from the system or block transfer functions that are available for the motors, inverter, and controller:

- Use the Field Oriented Control Autotuner block.
- Use Simulink Control Design™.
- Use the model initialization script.



Field-Oriented Control Autotuner

The Field-Oriented Control Autotuner block of Motor Control Blockset enables you to automatically tune the PID control loops in your Field-Oriented Control (FOC) application in real time. You can automatically tune the PID controllers associated with the following loops (for more details, see “How to Use Field Oriented Control Autotuner Block”):

- Direct-axis (d -axis) current loop
- Quadrature-axis (q -axis) current loop
- Speed loop

For each loop that the block tunes, the Field-Oriented Control Autotuner block performs the autotuning experiment in a closed-loop manner without using a parametric model associated with that loop. The block enables you to specify the order in which the block tunes the control loops. When the tuning experiment runs for one loop, the block has no effect on the other loops. For more details about FOC autotuner, see Field Oriented Control Autotuner and “Tune PI Controllers Using Field Oriented Control Autotuner” on page 4-24.

Simulink Control Design

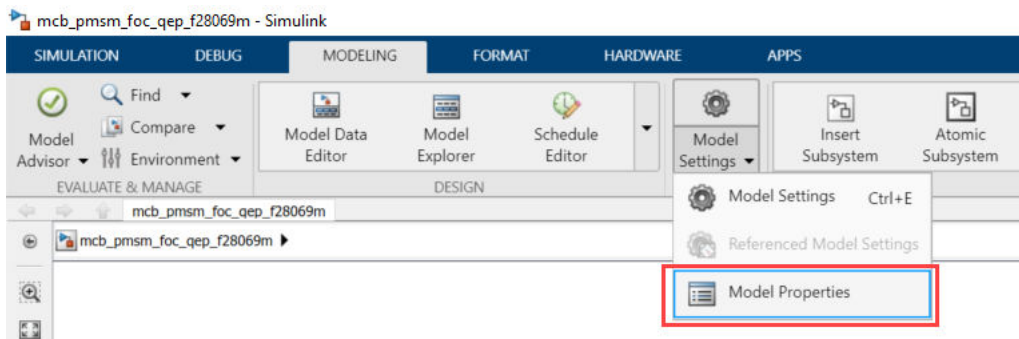
Simulink Control Design enables you to design and analyze the control systems modeled in Simulink. You can automatically tune the arbitrary SISO and MIMO control architectures, including the PID controllers. You can deploy PID autotuning to the embedded software to automatically compute the PID gains in real time.

You can find the operating points and compute the exact linearizations of the Simulink models at different operating conditions. Simulink Control Design provides tools that let you compute the simulation-based frequency responses without modifying your model. For details, see <https://www.mathworks.com/help/slcontrol/index.html>.

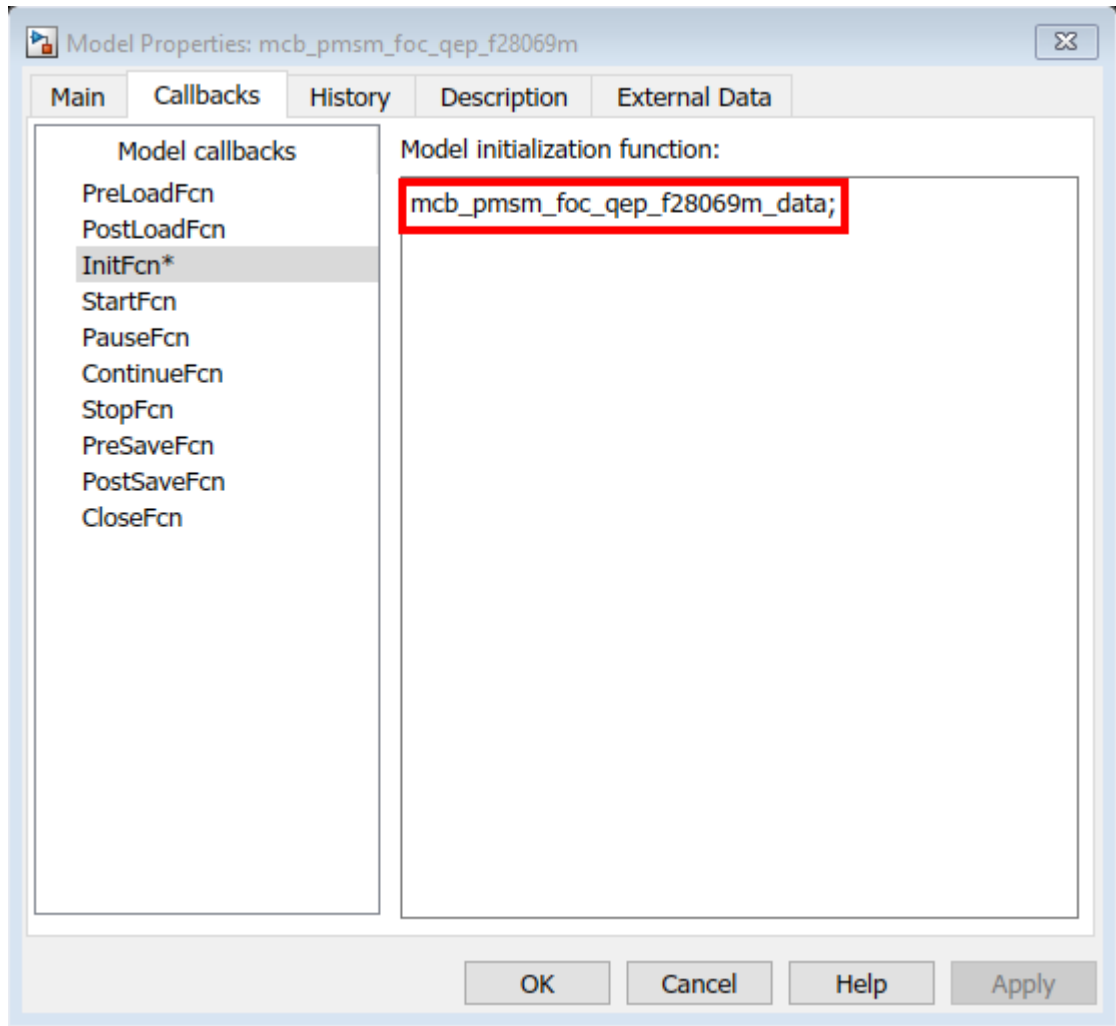
Model Initialization Script

This section explains how the Motor Control Blockset examples estimate the control gains needed to implement field-oriented control. For example, for a PMSM that is connected to a quadrature encoder, these steps describe the procedure to compute the control loop gain values from the system details by using the initialization script:

- 1 Open the initialization script (.m) file of the example in MATLAB®. To find the associated script file name:
 - a Select **Modeling > Model Settings > Model Properties** to open the model properties dialog box.



- b In the Model Properties dialog box, navigate to the **Callbacks** tab > **InitFcn** to find the name of the script file that Simulink opens before running the example.



- 2 This figure shows an example of the initialization script (.m) file.

```

1  %% *****
2  % Model      : PMSM Field Oriented Control
3  % Description : Set Parameters for PMSM Field Oriented Control
4  % File name  : mcb_pmsm_foc_qep_f28069m_data.m
5  % Copyright 2020 The MathWorks, Inc.
6
7  %% Parameters needed for Offset computation are
8  % target.PWM_Counter_Period - PWM counter value for epwm blocks
9  % target.CPU_frequency     - CPU frequency of the microcontroller
10 % Ts                       - Control sample time
11 % PU_System.N_base         - Base speed for per unit conversion
12 % pmsm.p                   - Number pole pairs in the motor
13
14 % Other parameters are not mandatory for offset computation
15
16 %% Set PWM Switching frequency
17 PWM_frequency = 20e3; %Hz // converter s/w freq
18 T_pwm        = 1/PWM_frequency; %s // PWM switching time period
19
20 %% Set Sample Times
21 Ts           = T_pwm; %sec // simulation time step for controller
22 Ts_simulink  = T_pwm/2; %sec // simulation time step for model simulation
23 Ts_motor     = T_pwm/2; %Sec // Simulation sample time
24 Ts_inverter  = T_pwm/2; %sec // simulation time step for average value inverter
25 Ts_speed     = 10*Ts; %Sec // Sample time for speed controller
26
27 %% Set data type for controller & code-gen
28 % dataType = fixdt(1,32,17); % Fixed point code-generation
29 dataType = 'single'; % Floating point code-generation
30
31 %% System Parameters // Hardware parameters
32
33 pmsm = mcb_SetPMSMMotorParameters('BLY171D');
34 pmsm.PositionOffset = 0.17;
35
36 %% Parameters below are not mandatory for offset computation
37
38 inverter = mcb_SetInverterParameters('DRV8312-C2-KIT');
39
40 inverter.ADCOffsetCalibEnable = 1; % Enable: 1, Disable:0
41
42 target = mcb_SetProcessorDetails('F28069M',PWM_frequency);
43
44 %% Derive Characteristics
45 pmsm.N_base = mcb_getBaseSpeed(pmsm,inverter); %rpm // Base speed of motor at given Vdc
46 % mcb_getCharacteristics(pmsm,inverter);
47
48 %% PU System details // Set base values for pu conversion
49
50 PU_System = mcb_SetPUSystem(pmsm,inverter);
51
52 %% Controller design // Get ballpark values!
53
54 PI_params = mcb.internal.SetControllerParameters(pmsm,inverter,PU_System,T_pwm,Ts,Ts_speed);
55
56 %%Updating delays for simulation
57 PI_params.delay_Currents = int32(Ts/Ts_simulink);
58 PI_params.delay_Speed    = int32(Ts_speed/Ts_simulink);
59
60 % mcb_getControlAnalysis(pmsm,inverter,PU_System,PI_params,Ts,Ts_speed);

```

- 3 Use the **Workspace** to edit the control variables values. For example, to update Stator resistance (R_s), use the variable `pmsm` to add the parameter value to the R_s field.

The image shows two windows from a MATLAB environment. On the left is the 'Workspace' window, and on the right is the 'pmsm' struct editor window. A red box highlights the 'pmsm' variable in the workspace, and another red box highlights the 'Rs' field in the struct editor. Red lines connect the workspace box to the struct editor box.

Field	Value
model	'Teknic-2310P'
sn	'003'
p	4
Rs	0.3600
Ld	2.0000e-04
Lq	2.0000e-04
J	7.0616e-06
B	2.6369e-06
Ke	4.6400
Kt	0.2740
I_rated	7.1000
N_max	6000
PositionOffset	0.1700
QEPlits	1000
FluxPM	0.0064
T_rated	0.2724
N_base	3902

- 4 The model initialization script associated with a target model calls these functions and sets up the workspace with the necessary variables.

Model Initialization Script	Function Called By Model Initialization Script	Description
Script associated with a target model	mcb_SetPMSMMotorParameters	<p>Input to the function is motor type (for example, BLY171D).</p> <p>The function populates a structure named <code>pmsm</code> in the MATLAB workspace, which is used by the model.</p> <p>It also computes the permanent magnet flux and rated torque for the selected motor.</p> <p>You can extend the function by adding an additional switch-case for a new motor.</p> <p>This function also loads the structure <code>motorParam</code>, obtained by running parameter estimation, to the structure <code>pmsm</code>. If the structure <code>motorParam</code> is not available in the MATLAB workspace, the function loads the default parameters.</p>
	mcb_SetInverterParameters	<p>Input to the function is inverter type (for example, BoostXL-DRV8305).</p> <p>The function populates a structure named <code>inverter</code> in the MATLAB workspace, which is used by the model.</p> <p>The function also computes the inverter resistance for the selected inverter.</p> <p>You can extend the function by adding an additional switch-case for a new inverter.</p>

Model Initialization Script	Function Called By Model Initialization Script	Description
	mcb_SetProcessorDetails	<p>Inputs to the function are processor type (for example, F28379D) and the Pulse-Width Modulation (PWM) switching frequency.</p> <p>The function populates a structure named <code>target</code> in the MATLAB workspace, which is used by the model.</p> <p>The function also computes the PWM counter period that is a parameter for the ePWM block in the target model.</p> <p>You can extend the function by adding an additional switch-case for a new processor.</p>
	mcb_getBaseSpeed	<p>Inputs to the function are motor and inverter parameters.</p> <p>The function computes the base speed for PMSM.</p> <p>Type <code>help mcb_getBaseSpeed</code> at the MATLAB command window or see section “Obtain Base Speed” on page 3-14 for more details.</p>
	mcb_SetPUSystem	<p>Inputs to the function are motor and inverter parameters.</p> <p>The function sets the base values of the per-unit system for voltage, current, speed, torque, and power.</p> <p>The function populates a structure named <code>PU_System</code> in the MATLAB workspace, which is used by the model.</p>

Model Initialization Script	Function Called By Model Initialization Script	Description
	<code>mcb.internal.SetControllerParameters</code>	<p>Inputs to the function are motor and inverter parameters, per-unit system base values, PWM switching time period, sample time for the control system, and sample time for the speed controller.</p> <p>The function computes the Proportional Integral (PI) parameters (K_p, K_i) for the field-oriented control implementation.</p> <p>The function populates a structure named <code>PI_params</code> in the MATLAB workspace, which is used by the model.</p> <p>See section “Obtain Controller Gains” on page 3-16 for more details.</p>
	<code>mcb_updateInverterParameters</code>	<p>Inputs to the function are motor and inverter parameters.</p> <p>The function updates the inverter parameters based on the selected hardware and motor.</p>

This table explains the useful variables for each control parameter that you can update.

Note You can try starting MATLAB in the administrator mode on Windows® system, if you are unable to update the model initialization scripts associated with the example models.

Control Parameter Category	Control Parameter Name	MATLAB Workspace Variable
Motor parameters	Manufacturer’s model number	<code>pmsm.model</code>
	Manufacturer’s serial number	<code>pmsm.sn</code>
	Pole pairs	<code>pmsm.p</code>
	Stator resistance (Ohm)	<code>pmsm.Rs</code>
	d-axis stator winding inductance (Henry)	<code>pmsm.Ld</code>

Control Parameter Category	Control Parameter Name	MATLAB Workspace Variable
	q-axis stator winding inductance (Henry)	pmsm.Lq
	Back emf constant (V_line(peak)/krpm)	pmsm.Ke
	Motor Inertia (kg.m ²)	pmsm.J
	Friction constant (N.m.s)	pmsm.F
	Permanent Magnet Flux (WB)	pmsm.FluxPM
	Trated	pmsm.T_rated
	Nbase	pmsm.N_base
	Maximum motor speed used in the mcb_getCharacteristics(pmsm,inverter) function pmsm.N_max = 2 * pmsm.N_base	pmsm.N_max
	Irated	pmsm.I_rated
Position decoders	QEP index and Hall position offset correction	pmsm.PositionOffset
	Quadrature encoder slits per revolution	pmsm.QEPSlits
Inverter parameters	Manufacturer's model number	inverter.model
	Manufacturer's serial number	inverter.sn
	DC link voltage of the inverter (V)	inverter.V_dc
	Maximum permissible currents by inverter (A)	inverter.I_trip
	On-state resistance of MOSFETs (Ohm)	inverter.Rds_on
	Shunt resistance for current sensing (Ohm)	inverter.Rshunt
	Per-phase board resistance seen by motor (Ohm)	inverter.R_board
	ADC Offsets for current sensor (I _a and I _b)	inverter.CtSensAoffset inverter.CtSensBoffset
	Maximum limit of automatically calibrated ADC offsets for current sensor (I _a and I _b)	inverter.CtSensOffsetMax
	Minimum limit of automatically calibrated ADC offsets for current sensor (I _a and I _b)	inverter.CtSensOffsetMin

Control Parameter Category	Control Parameter Name	MATLAB Workspace Variable
	Enable Auto-calibration for current sense ADCs	<code>inverter.ADCOffsetCalibEnable</code>
	ADC gain factor configured by SPI	<code>inverter.ADCGain</code>
	Type of inverter: 1 – Active high-enabled inverter 0 – Active low-enabled inverter	<code>inverter.EnableLogic</code>
	Type of current sense amplifier: 1 – Non-inverting amplifier -1 – Inverting amplifier	<code>inverter.invertingAmp</code>
	Reference voltage for the inverter current sensing circuit (V)	<code>inverter.ISenseVref</code>
	Output voltage of the inverter current sensing circuit corresponding to 1 Ampere current (V/A) You can compute this parameter using the datasheet values of current shunt resistance (<code>inverter.Rshunt</code>) and current sense amplifier gain of the inverter. $\text{inverter.ISenseVoltPerAmp} = \text{inverter.Rshunt} \times \text{current sense amplifier gain}$	<code>inverter.ISenseVoltPerAmp</code>
	Maximum measurable peak-neutral current by the inverter current sensing circuit (A)	<code>inverter.ISenseMax</code>
Processor	Manufacturer's model number	<code>target.model</code>
	Manufacturer's serial number	<code>target.sn</code>
	CPU Frequency	<code>target.CPU_frequency</code>
	PWM frequency	<code>target.PWM_frequency</code>
	PWM counter period	<code>target.PWM_Counter_Period</code>
	Reference voltage for ADC (V)	<code>Target.ADC_Vref</code>
	Maximum count output for 12-bit ADC	<code>Target.ADC_MaxCount</code>

Control Parameter Category	Control Parameter Name	MATLAB Workspace Variable
	Baud rate for serial communication	Target.SCI_baud_rate
Per-Unit System	Base voltage (V)	PU_System.V_base
	Base current (A)	PU_System.I_base
	Base speed (rpm)	PU_System.N_base
	Base torque (Nm)	PU_System.T_base
	Base power (Watts)	PU_System.P_base
Data-type for target device	Data-type (Fixed-point Or Floating-point) selection	dataType
Sample time values	Switching frequency for converter	PWM_frequency
	PWM switching time period	T_pwm
	Sample time for current controllers	Ts
	Sample time for speed controller	Ts_speed
	Simulation sample time	Ts_simulink
	Simulation sample time for motor	Ts_motor
	Simulation sample time for inverter	Ts_inverter
Controller parameters	Proportional gain for Iq controller	PI_params.Kp_i
	Integral gain for Iq controller	PI_params.Ki_i
	Proportional gain for Id controller	PI_params.Kp_id
	Integral gain for Id controller	PI_params.Ki_id
	Proportional gain for Speed controller	PI_params.Kp_speed
	Integral gain for Speed controller	PI_params.Ki_speed
	Proportional gain for Field weakening controller	PI_params.Kp_fwc
	Integral gain for Field weakening controller	PI_params.Ki_fwc
Sensor delay parameters	Current sensor delay	Delays.Current_Sensor
	Speed sensor delay	Delays.Speed_Sensor
	Delay for low-pass speed filter	Delays.Speed_Filter
Controller delay parameters	Damping factor (ζ) of the current control loop	Delays.OM_damping_factor

Control Parameter Category	Control Parameter Name	MATLAB Workspace Variable
	Symmetrical optimum factor of the speed control loop	Delays.S0_factor_speed

Note For the predefined processors and drivers, the model initialization script uses the default values.

The model initialization script uses these functions for performing the computations:

Control Parameter Category	Function	Functionality
Base speed of the motor	mcb_getBaseSpeed	<p>Calculates the base speed of PMSM at the rated voltage and rated load.</p> <p>For details, type <code>help mcb_getBaseSpeed</code> at the MATLAB command prompt or see section “Obtain Base Speed” on page 3-14.</p>
Motor characteristics for the given motor and inverter	mcb_getCharacteristics	<p>Obtain these characteristics of the motor.</p> <ul style="list-style-type: none"> • Torque as opposed to speed characteristics • Power as opposed to speed characteristics • I_{dq} as opposed to speed characteristics • Maximum phase current ($I_{peak} = \sqrt{I_d^2 + I_q^2}$) of the motor as opposed to speed characteristics <p>For details, type <code>help mcb_getCharacteristics</code> at the MATLAB command prompt.</p> <p>For details, see section “Obtain Motor Characteristics” on page 3-15.</p>

Control Parameter Category	Function	Functionality
Control algorithm parameters	<code>mcb.internal.SetControllerParameters</code>	<p>Compute the gains for these PI controllers:</p> <ul style="list-style-type: none"> • Current (torque) control loop gains (K_p, K_i) for currents I_d and I_q • Speed control loop gains (K_p, K_i) • Field weakening control gains (K_p, K_i) <p>For details, see section “Obtain Controller Gains” on page 3-16.</p>
Control analysis for the motor and inverter you are using	<code>mcb_getControlAnalysis</code>	<p>Performs frequency domain analysis for the computed gains of PI controllers used in the field-oriented motor control system.</p> <hr/> <p>Note This feature requires Control System Toolbox™.</p> <hr/> <p>For details, type <code>help mcb_getControlAnalysis</code> at the MATLAB command prompt.</p>

Obtain Base Speed

The function `mcb_getBaseSpeed` computes the base speed of the PMSM at the given supply voltage. Base speed is the maximum motor speed at the rated voltage and rated load, outside the field-weakening region.

When you call this function (for example, `base_speed = mcb_getBaseSpeed(pmsm,inverter)`), it returns the base speed (in rpm) for the given combination of PMSM and inverter. The function accepts the following inputs:

- PMSM parameter structure.
- Inverter parameter structure.

These equations describe the computations that the function performs:

The inverter voltage constraint is defined by computing the d -axis and q -axis voltages:

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

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

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

The current limit circle defines the current constraint which can be considered as:

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

In the preceding equation, i_d is zero for surface PMSMs. For interior PMSMs, values of i_d and i_q corresponding to MTPA are considered.

Using the preceding relationships, we can compute the base speed as:

$$\omega_{base} = \frac{1}{p} \cdot \frac{v_{max}}{\sqrt{(L_q i_q)^2 + (L_d i_d + \lambda_{pm})^2}}$$

where:

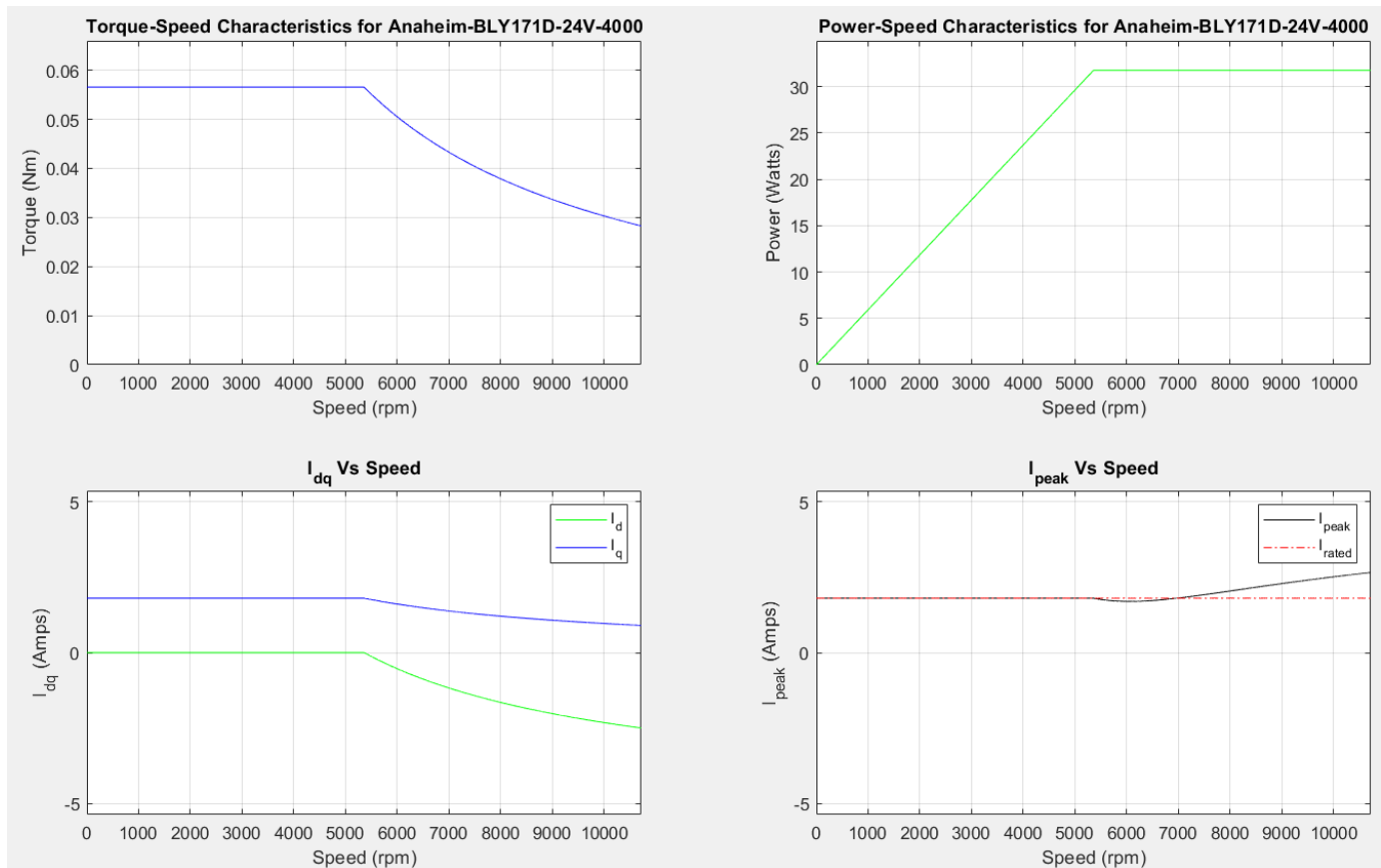
- ω_e is the electrical speed corresponding to frequency of stator voltages (Radians/ sec).
- ω_{base} is the mechanical base speed of the motor (Radians/ sec).
- i_d is the d -axis current (Amperes).
- i_q is the q -axis current (Amperes).
- v_{d0} is the d -axis voltage when i_d is zero (Volts).
- v_{q0} is the q -axis voltage when i_q is zero (Volts).
- L_d is the d -axis winding inductance (Henry).
- L_q is the q -axis winding inductance (Henry).
- R_s is the stator phase winding resistance (Ohms).
- λ_{pm} is the permanent magnet flux linkage (Weber).
- v_d is the d -axis voltage (Volts).
- v_q is the q -axis voltage (Volts).
- v_{max} is the maximum fundamental line to neutral voltage (peak) supplied to the motor (Volts).
- v_{dc} is the dc voltage supplied to the inverter (Volts).
- i_{max} is the maximum phase current (peak) of the motor (Amperes).
- p is the number of motor pole pairs.

Obtain Motor Characteristics

The function `mcb_getCharacteristics` calculates the torque and speed characteristics of the motor, which helps you to develop the control algorithm for the motor.

The function returns these characteristics for the given PMSM:

- Torque as opposed to Speed
- Power as opposed to Speed
- I_{dq} as opposed to Speed
- I_{peak} as opposed to Speed



Obtain Controller Gains

The function `mcb.internal.SetControllerParameters` computes the gains for the PI controllers used in the field-oriented motor control systems.

You can use this command to call the function `mcb.internal.SetControllerParameters`:

```
PI_params = mcb.internal.SetControllerParameters(pmsm, inverter, PU_System, T_pwm, Ts, Ts_speed);
```

The function returns the gains of these PI controllers used in the FOC algorithm:

- Direct-axis (d -axis) current loop
- Quadrature-axis (q -axis) current loop
- Speed loop
- Field-weakening control loop

The function accepts these inputs:

- `pmsm` object
- `inverter` object
- PU system params
- `T_pwm`
- `Ts_control`

- `Ts_speed`

The function does not plot any characteristic.

The design of compensators depends on the classical frequency response analysis applied to the motor control systems. We used the Modulus Optimum (MO) based design for the current controllers and the Symmetrical Optimum (SO) based design for the speed controller.

The function automatically computes the other required parameters (for example, delays, damping factor) based on the input arguments.

You can modify the default system responses by an optional input to the function that specifies the system delays, damping factor, and symmetrical optimum factor:

```
PI_params = mcb.internal.SetControllerParameters(pmsm,inverter,PU_System,T_pwm,Ts,Ts_speed,Delays)
```

Damping factor (ζ) defines the dynamic behavior of the standard form of a second-order system, where $0 < \zeta < 1$ [1]. An underdamped system gets close to the final value more quickly than a critically damped or an overdamped system. Among the systems that respond without oscillations, a critically damped system shows the quickest response. An overdamped system is always slow in responding to any inputs. This parameter has a default value of $\frac{1}{\sqrt{2}}$.

Symmetrical optimum factor (a) defines the placement of the cross-over frequency at the geometric mean of the two corner frequencies, to obtain maximum phase margin that results in optimum damping of the speed loop, where $a > 1$ [2]. This parameter has a default value of 1.2.

This example explains how to customize the parameters:

```
% Sensor Delays
Delays.Current_Sensor = 2*Ts;           %Current Sensor Delay
Delays.Speed_Sensor = Ts;              %Speed Sensor Delay
Delays.Speed_Filter = 20e-3;           %Delay for Speed filter (LPF)

% Controller Delays
Delays.OM_damping_factor = 1/sqrt(2); %Damping factor for current control loop
Delays.SO_factor_speed = 1.5;         %Symmetrical optimum factor 1 < x < 20

% Controller design
PI_params = mcb.internal.SetControllerParameters(pmsm,inverter,PU_System,T_pwm,Ts,Ts_speed,Delays)
```

Perform Control Analysis

The function `mcb_getControlAnalysis` performs the basic control analysis of the PMSM FOC current control system. The function performs frequency domain analysis for the computed PI controller gains used in the field-oriented motor control systems.

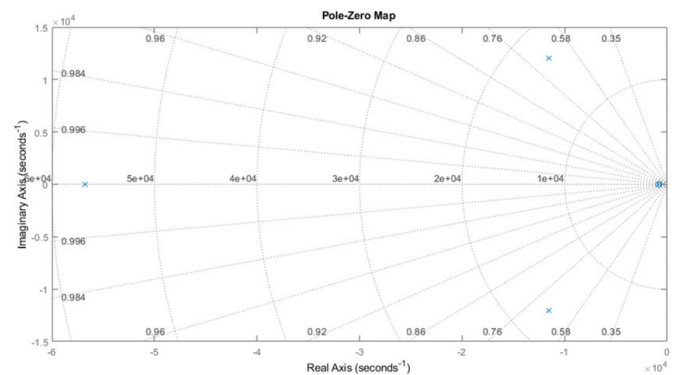
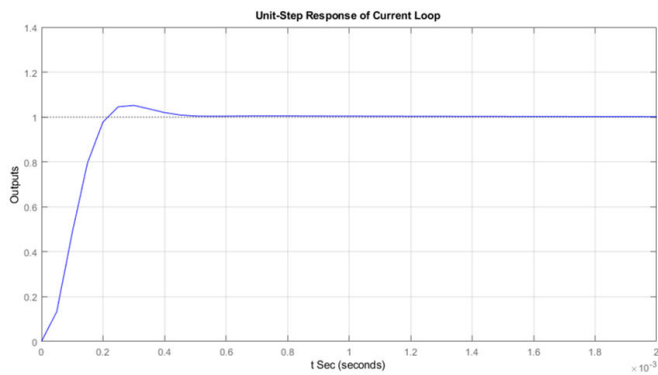
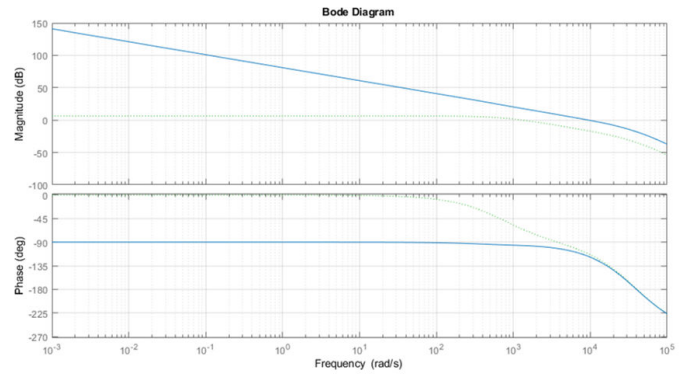
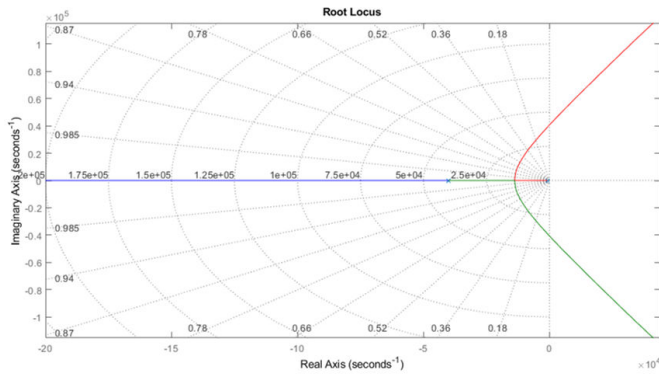
Note This function requires the Control System Toolbox.

When you call this function (for example, `mcb_getControlAnalysis(pmsm,inverter,PU_System,PI_params,Ts,Ts_speed)`), it performs the following functions for the current control loop or subsystem:

- Transfer function for the closed-loop current control system

- Root locus
- Bode diagram
- Stability margins (PM & GM)
- Step response
- PZ map

The function plots the corresponding plots:



References

- [1] Ogata, K. (2010). *Modern control engineering*. Prentice hall.
- [2] Leonhard, W. (2001). *Control of electrical drives*. Springer Science & Business Media. pp. 86.

Implement Motor Speed Control by Using Field-Oriented Control (FOC)

- “Field-Oriented Control (FOC)” on page 4-2
- “Six-Step Commutation” on page 4-4
- “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6
- “Tune Control Parameter Gains in Hardware and Validate Plant” on page 4-14
- “Tune PI Controllers Using Field Oriented Control Autotuner” on page 4-24
- “Field-Oriented Control of PMSM Using Hall Sensor” on page 4-34
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- “Field-Weakening Control (with MTPA) of PMSM” on page 4-44
- “Sensorless Field-Oriented Control of PMSM” on page 4-57
- “Field-Oriented Control of PMSM Using SI Units” on page 4-63
- “Hall Offset Calibration for PMSM Motor” on page 4-67
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- “Estimate Initial Rotor Position Using Pulsating High-Frequency and Dual-Pulse Methods” on page 4-169
- “Algorithm-Export Workflows for Custom Hardware” on page 4-186
- “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188
- “Field-Oriented Control of PMSM Using Reinforcement Learning” on page 4-195
- “Estimate Induction Motor Parameters Using Recommended Hardware” on page 4-202
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Field-Oriented Control (FOC)

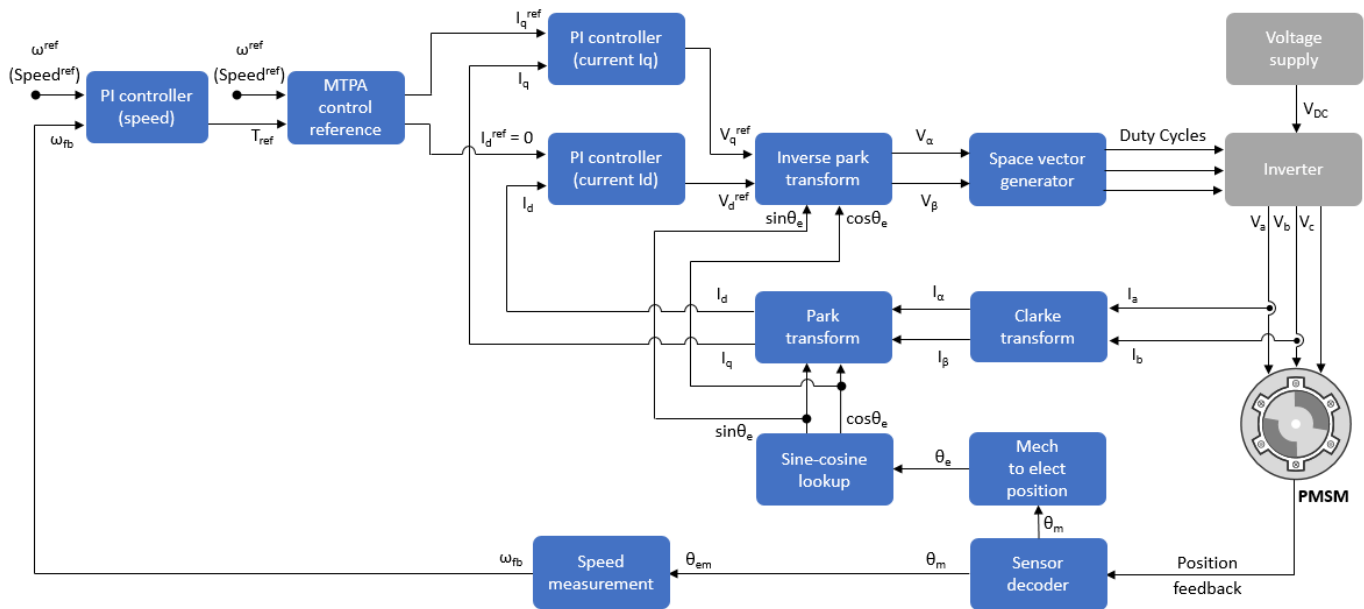
Field-Oriented Control (FOC), also known as vector control, is a technique used to control Permanent Magnet Synchronous Motor (PMSM) and AC induction motors (ACIM). FOC provides good control capability over the full torque and speed ranges. The FOC implementation requires transformation of stator currents from the stationary reference frame to the rotor flux reference frame (also known as d - q reference frame).

Speed control and torque control are the most commonly used control modes of FOC. The position control mode is less common. Most of the traction applications use the torque control mode in which the motor control system follows a reference torque value. In the speed control mode, the motor controller follows a reference speed value and generates a torque reference for the torque control that forms an inner subsystem. In the position control mode, the speed controller forms the inner subsystem.

FOC algorithm implementation requires real time feedback of the currents and rotor position. Measure the current and position by using sensors. You can also use sensorless techniques that use the estimated feedback values instead of the actual sensor-based measurements.

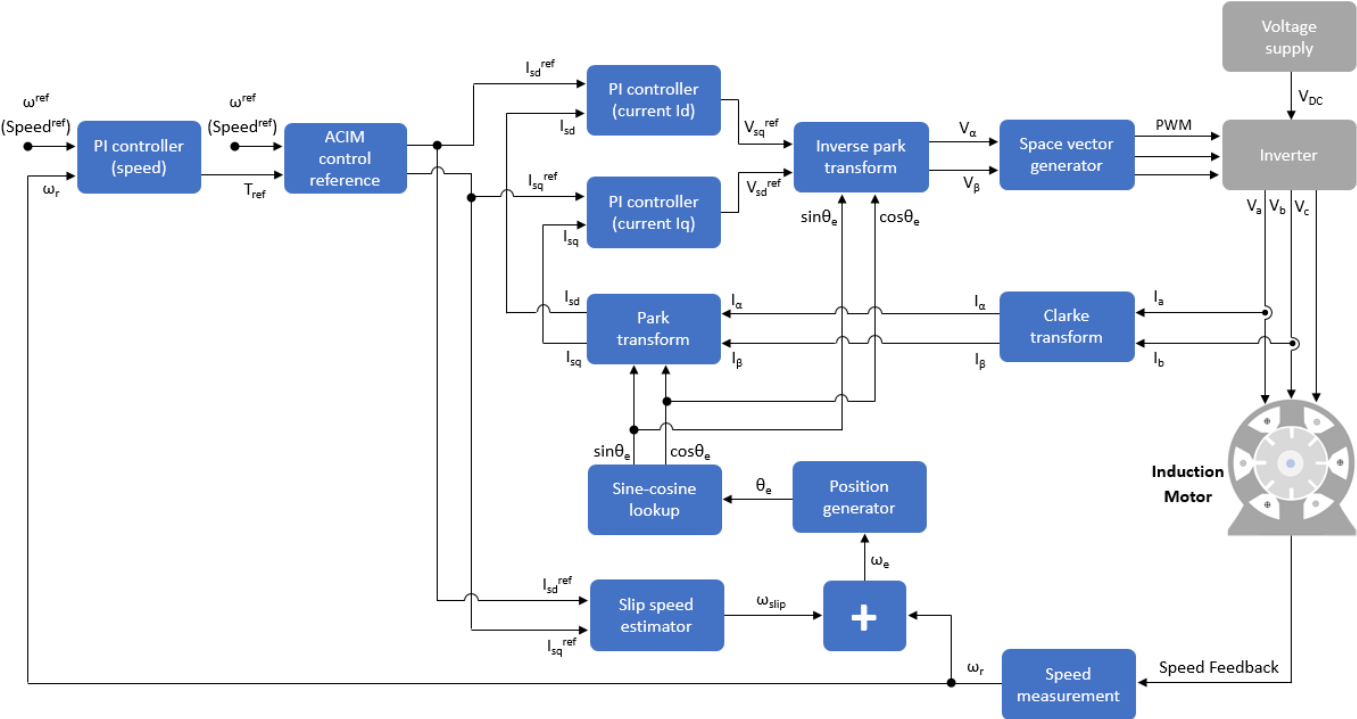
Permanent Magnet Synchronous Motor (PMSM)

This figure shows the FOC architecture for a PMSM. For detailed set of equations and assumptions that Motor Control Blockset uses to implement FOC of a PMSM, see “Mathematical Model of PMSM”.



AC Induction Motor (ACIM)

This figure shows the FOC architecture for an AC induction motor (ACIM). For detailed set of equations and assumptions that Motor Control Blockset uses to implement FOC of an induction motor, see “Mathematical Model of Induction Motor”.



Six-Step Commutation

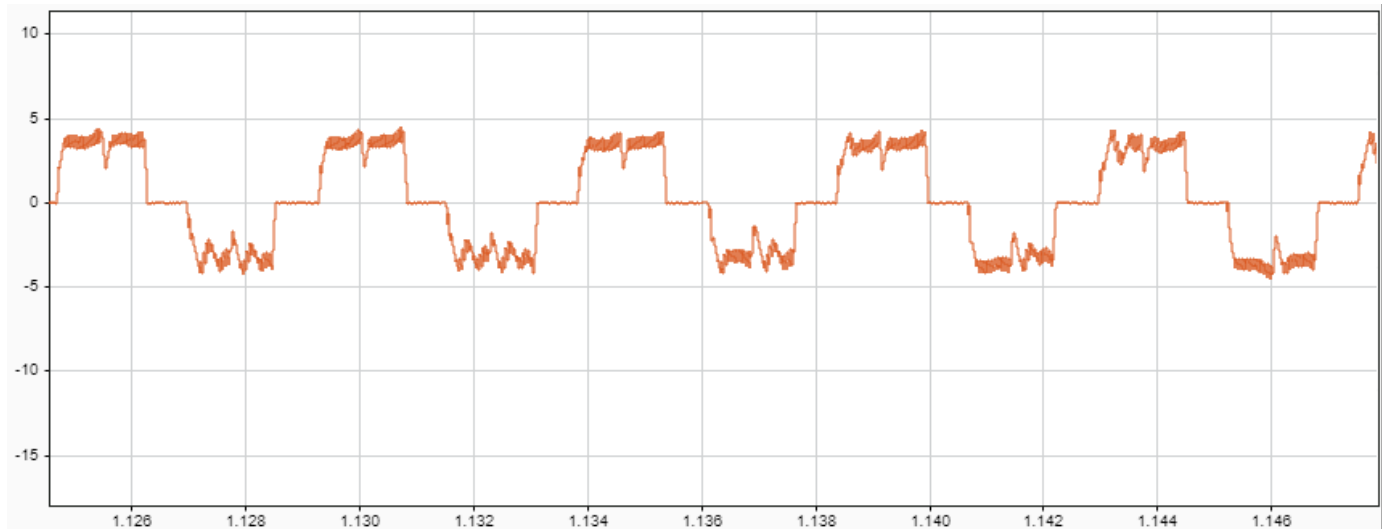
Six-step commutation, also known as trapezoidal commutation, is a commutation technique used to control three-phase brushless DC (BLDC) permanent magnet motor. It controls the stator currents to achieve a motor speed and direction of rotation.

Six-step commutation uses these conduction modes:

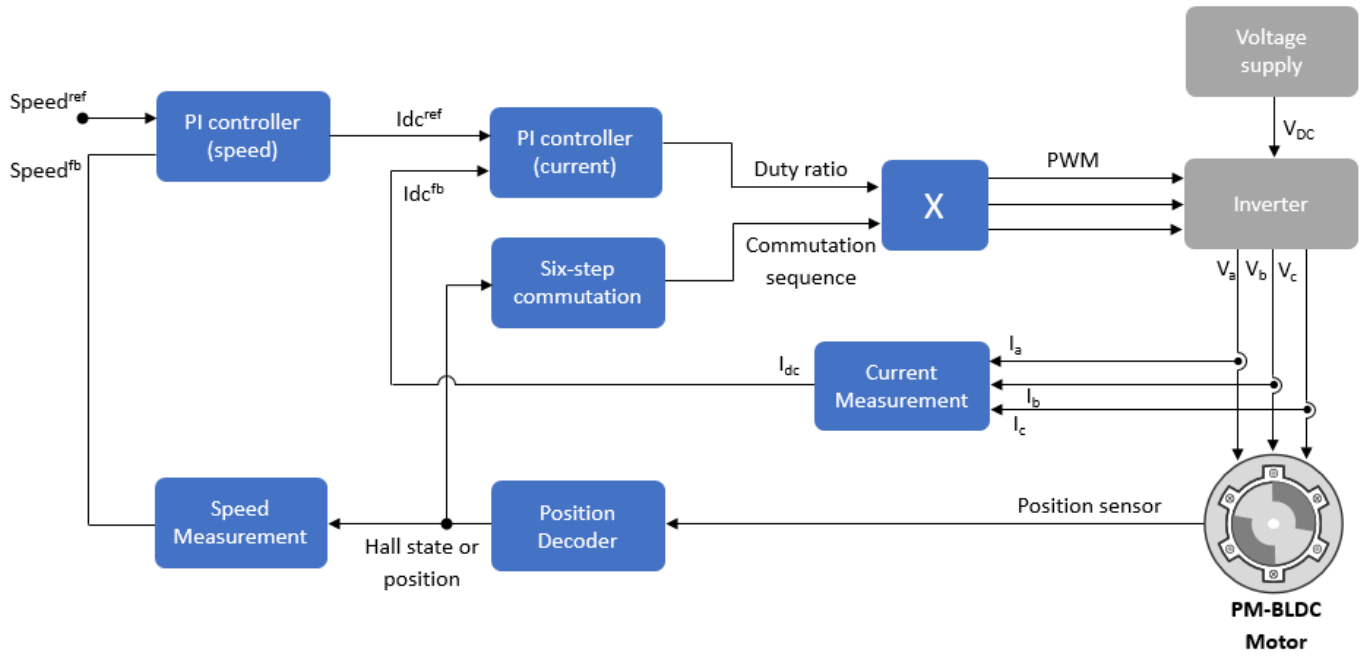
- 120 degree mode conducts current in only two stator phases.
- 180 degree mode conducts current in all three stator phases.

Motor Control Blockset supports 120 degree conduction mode. At a given time, this mode energizes only two stator phases and electrically isolates the third phase from the power supply. You can use either Hall or quadrature encoder position sensors to detect the rotor position. Motor Control Blockset provides Six Step Commutation block that uses the Hall sequence or rotor position inputs to determine the 60 degree sector where the rotor is present. It generates a switching sequence that energizes the corresponding phases. As the motor rotates, the sequence switches the stator currents every 60 degree such that the torque angle (angle between rotor d-axis and stator magnetic field) remains 90 degrees (with a deviation of 30 degrees). Therefore, the switching signals operate switches to control the stator currents, and therefore, control the motor speed and direction of rotation. For more details, see Six Step Commutation.

The stator current waveform takes a trapezoidal shape.



The 120 degree conduction mode is a less complex technique that provides good speed control for the BLDC motors. This figure shows the six-step commutation architecture for a BLDC motor.



Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset

This example uses open-loop control (also known as scalar control or Volts/Hz control) to run a motor. This technique varies the stator voltage and frequency to control the rotor speed without using any feedback from the motor. You can use this technique to check the integrity of the hardware connections. A constant speed application of open-loop control uses a fixed-frequency motor power supply. An adjustable speed application of open-loop control needs a variable-frequency power supply to control the rotor speed. To ensure a constant stator magnetic flux, keep the supply voltage amplitude proportional to its frequency.

Open-loop motor control does not have the ability to consider the external conditions that can affect the motor speed. Therefore, the control system cannot automatically correct the deviation between the desired and the actual motor speed.

This model runs the motor by using an open-loop motor control algorithm. The model helps you get started with Motor Control Blockset™ and verify the hardware setup by running the motor. The target model algorithm also reads the ADC values from the current sensors and sends these values to the host model by using serial communication.

You can use this model to:

- Check connectivity with the target.
- Check serial communication with the target.
- Verify the hardware and software environment.
- Check ADC offsets for current sensors.
- Run a new motor with an inverter and target setup for the first time.

Models

The example includes these models:

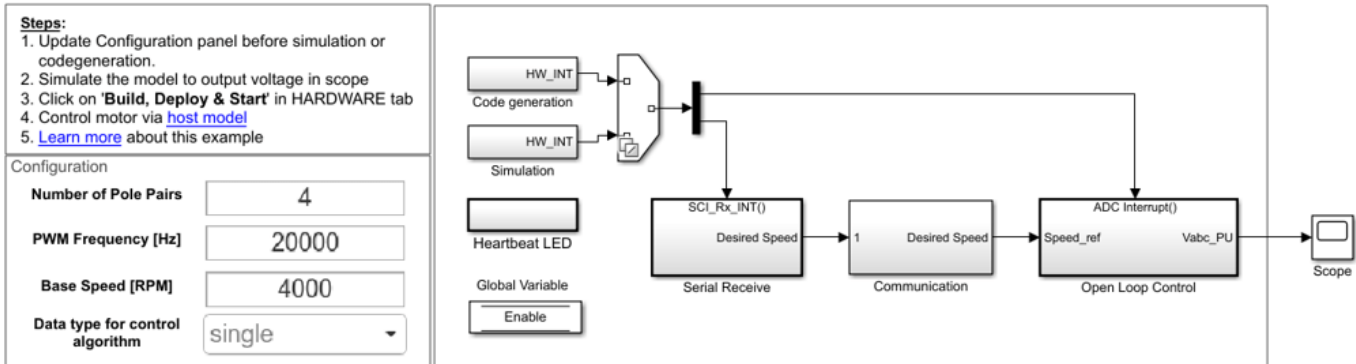
- `mcb_open_loop_control_f28069M_DRV8312`
- `mcb_open_loop_control_f28069MLaunchPad`
- `mcb_open_loop_control_f28379d`

You can use these models for both simulation and code generation. You can also use the `open_system` command to open the Simulink® models. For example, use this command for a F28069M based controller:

```
open_system('mcb_open_loop_control_f28069M_DRV8312.slx');
```


Open Loop Control of 3-phase motors

Note: This example requires a TI F28069M Control Card with DRV8312 EVM



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For the model names that you can use for different hardware configurations, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

1. For the models: **mcb_open_loop_control_f28069M_DRV8312** and **mcb_open_loop_control_f28069MLaunchPad**

- Motor Control Blockset™
- Fixed-Point Designer™

2. For the model: **mcb_open_loop_control_f28379d**

- Motor Control Blockset™

To generate code and deploy model:

1. For the models: **mcb_open_loop_control_f28069M_DRV8312** and **mcb_open_loop_control_f28069MLaunchPad**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the model: **mcb_open_loop_control_f28379d**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors

- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. For BOOSTXL-DRV8323, use these steps to update the model:

- Navigate to this path in the model: /Open Loop Control/Codegen/Hardware Initialization.
- For LAUNCHXL-F28379D: Update **DRV830x Enable block** from GPIO124 to GPIO67.
- For LAUNCHXL-F28069M: Update **DRV830x Enable block** from GPIO50 to GPIO12.

2. For BOOSTXL-3PHGANINV, use these steps to update the model:

- For LAUNCHXL-F28379D: In the **Configuration** panel of **mcb_open_loop_control_f28379d**, set **Inverter Enable Logic** to **Active Low**.

NOTE: When using BOOSTXL-3PHGANINV inverter, ensure that proper insulation is available between bottom layer of BOOSTXL-3PHGANINV and the LAUNCHXL board.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open a model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the motor by using open-loop control.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- F28069M controller card + DRV8312-69M-KIT inverter:
mcb_open_loop_control_f28069M_DRV8312

For connections related to the preceding hardware configuration, see “F28069 control card configuration” on page 7-2.

- LAUNCHXL-F28069M controller + (BOOSTXL-DRV8301 or BOOSTXL-DRV8305 or BOOSTXL-DRV8323 or BOOSTXL-3PHGANINV) inverter: mcb_open_loop_control_f28069MLaunchPad
- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8301 or BOOSTXL-DRV8305 or BOOSTXL-DRV8323 or BOOSTXL-3PHGANINV) inverter: mcb_open_loop_control_f28379d

To configure the model **mcb_open_loop_control_f28379d**, set the **Inverter Enable Logic** field (in the **Configuration** panel of target model) to:

- **Active High:** To use the model with BOOSTXL-DRV8301 or BOOSTXL-DRV8305 or BOOSTXL-DRV8323 inverter.
- **Active Low:** To use the model with BOOSTXL-3PHGANINV inverter.

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

NOTE:

- This example supports any type of three-phase AC motor (PMSM or induction) and any type of inverter attached to the supported hardware.
- Some PMSMs do not run at higher speeds, especially when the shaft is loaded. To resolve this issue, you should apply more voltages corresponding to a given frequency. You can use these steps to increase the applied voltages in the model:

1. Navigate to this path in the model: /Open Loop Control/Control_System/VabcCalc/.
2. Update the gain Correction_Factor_sinePWM as 20%.
3. For safety reasons, regularly monitor the motor shaft, motor current, and motor temperature.

Generate Code and Run Model to Implement Open-Loop Control

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.
4. Update these motor parameters in the **Configuration** panel of the target model.
 - **Number of Pole Pairs**
 - **PWM Frequency [Hz]**
 - **Base Speed [RPM]**
 - **Data type for control algorithm**
 - **Inverter Enable Logic** (only available in **mcb_open_loop_control_f28379d** target model)
5. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, a program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

NOTE: Ignore the warning message "Multitask data store option in the Diagnostics page of the Configuration Parameter Dialog is none" displayed by the model advisor, by clicking the Always Ignore button. This is part of the intended workflow.

7. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_open_loop_control_host_model.slx');
```

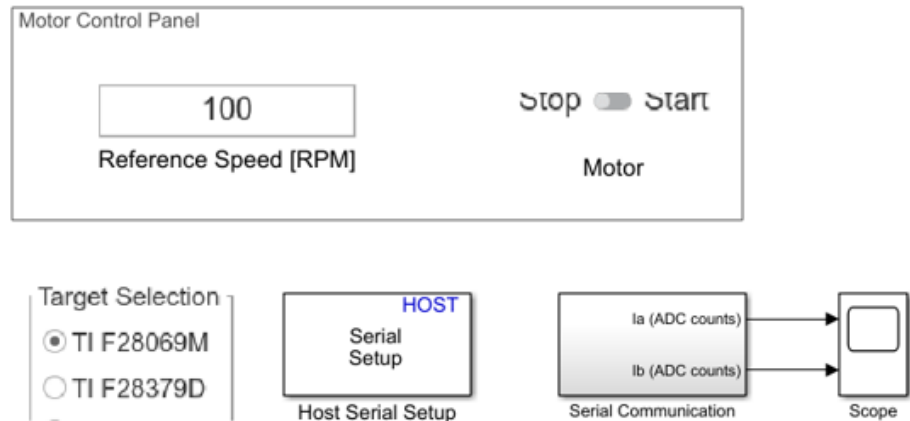
Open Loop Control Host Model

Prerequisites:

1. Deploy the target model to the hardware [F28069m + DRV8312 F28069m Launchpad](#) [F28379d Launchpad](#)
2. You should see and verify the variables from the target model in the base workspace.

Steps:

1. Select hardware in **Target Selection**. Select 'Other' option if you want to manually set the baud rate in 'Host Serial Setup' block.
2. Select the serial port in 'Serial 1' tab of 'Host Serial Setup' block.
3. Use 'Motor Start / Stop' switch to control the motor.
4. Enter speed request in RPM using 'Reference Speed' edit box. Limit the reference speed to half of the rated speed.
5. Observe the ADC counts for phase current measurement in Scope.



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. Select a target (either TI F28069M, TI F28379D, or Other) in the **Target Selection** area of the host model.

NOTE: If you select Other, you can enter the **Baud rate** for the target hardware that you are using, in the Host Serial Setup block parameter dialog box.

8. In the Host Serial Setup block parameter dialog box of the host model, select a **Port name**.

10. Enter the Reference Speed value in the host model.

11. Click **Run** on the **Simulation** tab to run the host model.

12. Change the position of the Start / Stop Motor switch to On, to start running the motor.

13. After the motor is running, observe the ADC counts for the I_a and I_b currents in the Time Scope.

NOTE: This example may not allow the motor to run at full capacity. Begin running the motor at a small speed. In addition, it is recommended to change the Reference Speed in small steps (for example, for a motor having a base speed of 3000 rpm, start running the motor at 500 rpm and then increase or decrease the speed in steps of 200 rpm).

If the motor does not run, change the position of the Start / Stop Motor switch to Off, to stop the motor and change the Reference Speed in the host model. Then, change the position of the Start / Stop Motor switch to On, to run the motor again.

Generate Code and Run Model to Calibrate ADC Offset

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. Disconnect the motor wires for three phases from the hardware board terminals.
4. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.
5. Load a sample program to CPU2 of LAUNCHXL-F28379D (for example, program that operates the CPU2 blue LED using GPIO31) to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

NOTE: Ignore the warning message "Multitask data store option in the Diagnostics page of the Configuration Parameter Dialog is none" displayed by the model advisor, by clicking the Always Ignore button. This is part of the intended workflow.

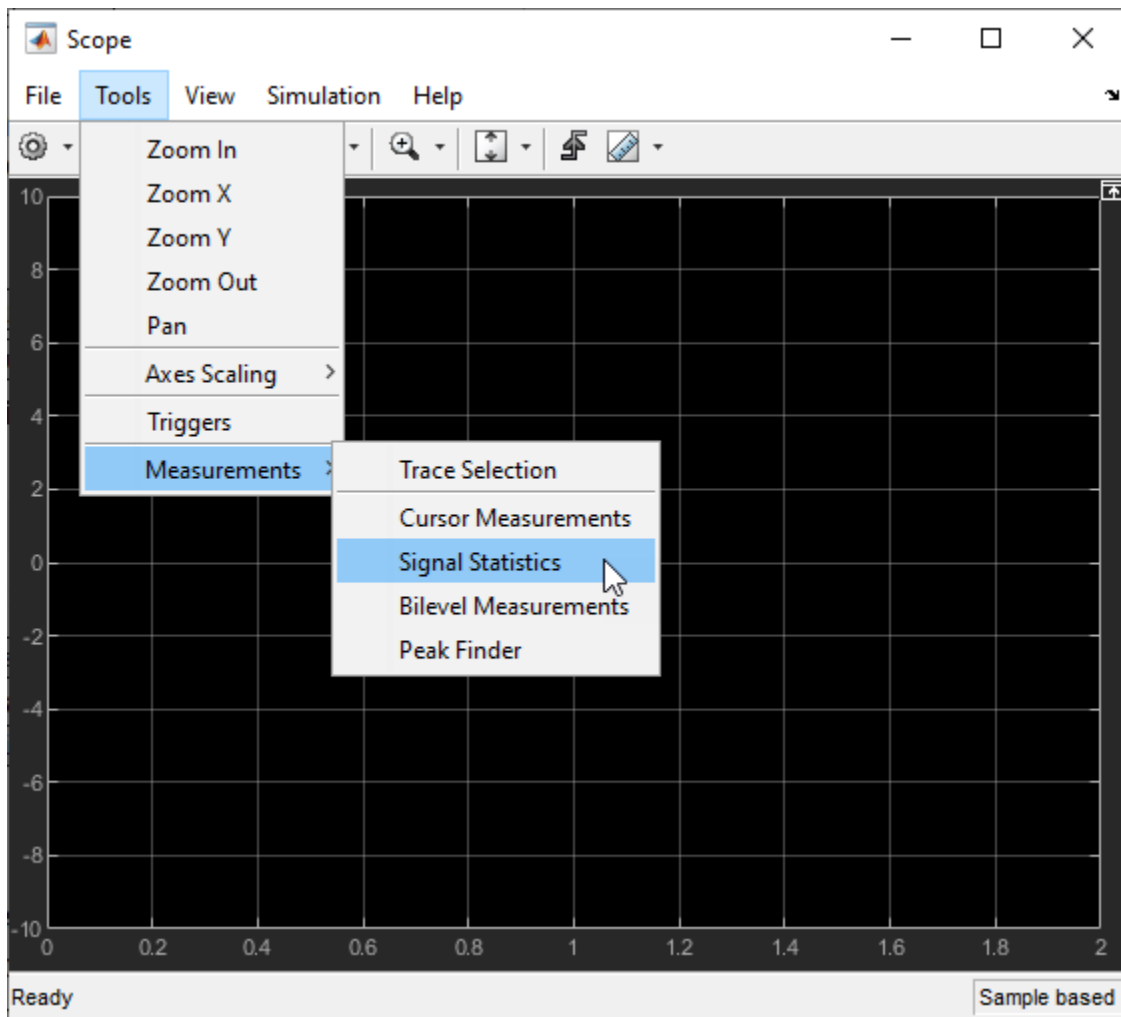
7. Click the **host model** hyperlink in the target model to open the associated host model.

8. In the Host Serial Setup block parameter dialog box of the host model, select a **Port name**.

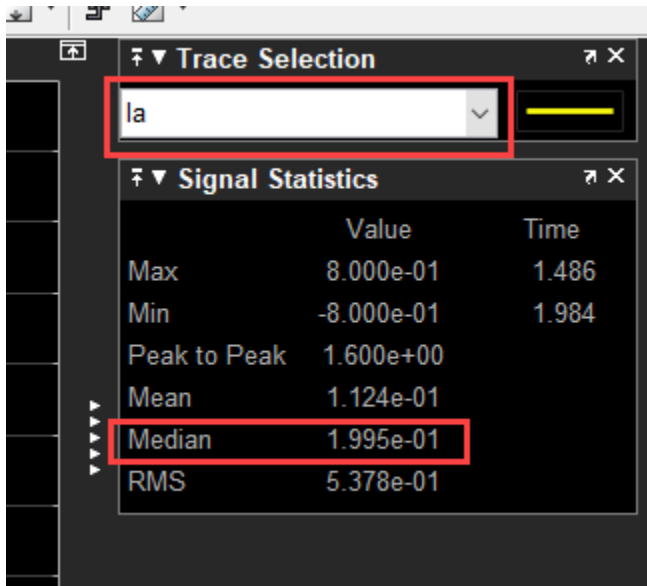
9. Click **Run** on the **Simulation** tab to run the host model.

10. Observe the ADC counts for the I_a and I_b currents in the Time Scope. The average values of the ADC counts are the ADC offset corrections for the currents I_a and I_b . To obtain the average (median) values of ADC counts:

- In the **Scope** window, navigate to **Tools > Measurements** and select **Signal Statistics** to display the **Trace Selection** and **Signal Statistics** areas.



- Under **Trace Selection**, select a signal (I_a or I_b). The characteristics of the selected signal are displayed in the **Signal Statistics** pane. You can see the median value of the selected signal in the Median field.



For the Motor Control Blockset examples, update the computed ADC (or current) offset value in the `inverter.CtSensAOffset` and `inverter.CtSensBOffset` variables in the model initialization script linked to the example. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

NOTE: The computed ADC offset depends on the ADC gain value `inverter.SPI_Gain_Setting` that you configure in the model initialization script. Changing ADC gain also changes the ADC offset.

Tune Control Parameter Gains in Hardware and Validate Plant

This example uses field-oriented control (FOC) to run a three-phase permanent magnet synchronous motor (PMSM) in different modes of operation for plant validation. FOC algorithm implementation needs the real-time feedback of the rotor position. This example uses a quadrature encoder sensor to measure the rotor position. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

The example runs the motor in these modes:

- **Stop** - In this mode, the motor stops running because the inverter outputs zero volts.
- **Open loop** - In this mode, the controller uses open-loop control to run the motor. You can use the **Operating Mode Variables > Open-loop mode** area of the host model to change the output voltage of the inverter (in per-unit) and the rotor speed (in per-unit). Use the **Monitor** area to select the speed and rotor position values to display them on the scope for monitoring.
- **Torque control** - In this mode, the controller uses a torque control algorithm to run the motor. You can use the **Operating Mode Variables > Motor torque control mode** area of the host model to change the I_d reference and I_q reference current values (in per-unit). You can also set the maximum speed limit of the motor (in per-unit).

You can lock the rotor by turning the slider switch to the Pos lock position that sets the rotor position to zero. Therefore, in this mode, the controller receives the position feedback as zero because the motor stops running. If you turn the switch to the Unlock position, the motor runs and the controller receives position feedback from the quadrature encoder (you can monitor this value by using the Position_meas signal in the **Monitor** area of host model). You can use the scope to monitor the two debug signals (Monitor Signal #1 and Monitor Signal #2) that you select in the **Monitor** area. Therefore, you can use the slider switch to tune the torque control gain parameters.

- **Speed control** - In this mode, the controller uses a speed control algorithm to run the motor. You can use the **Operating Mode Variables > Motor speed control mode** area of the host model to change the Speed Reference value (in per-unit) of the rotor. You can use the scope to monitor the two debug signals (Monitor Signal #1 and Monitor Signal #2) that you select in the **Monitor** area.

For information related to the per-unit system, see “Per-Unit System” on page 6-16.

To further control the motor, you can also use the **Control loop gains** area of the host model to change the control parameters of the d-axis and q-axis current controllers and the speed controller.

You can use this example to run the motor in open-loop control, torque control, and speed control modes. You can also use this example for tuning the hardware gains and validating the plant model.

Caution: Stop the motor first before transitioning from one operating mode to another.

You can select one of these operating modes in the Control area of the host model:

- Stop
- Open loop run
- Torque control
- Speed control

Model

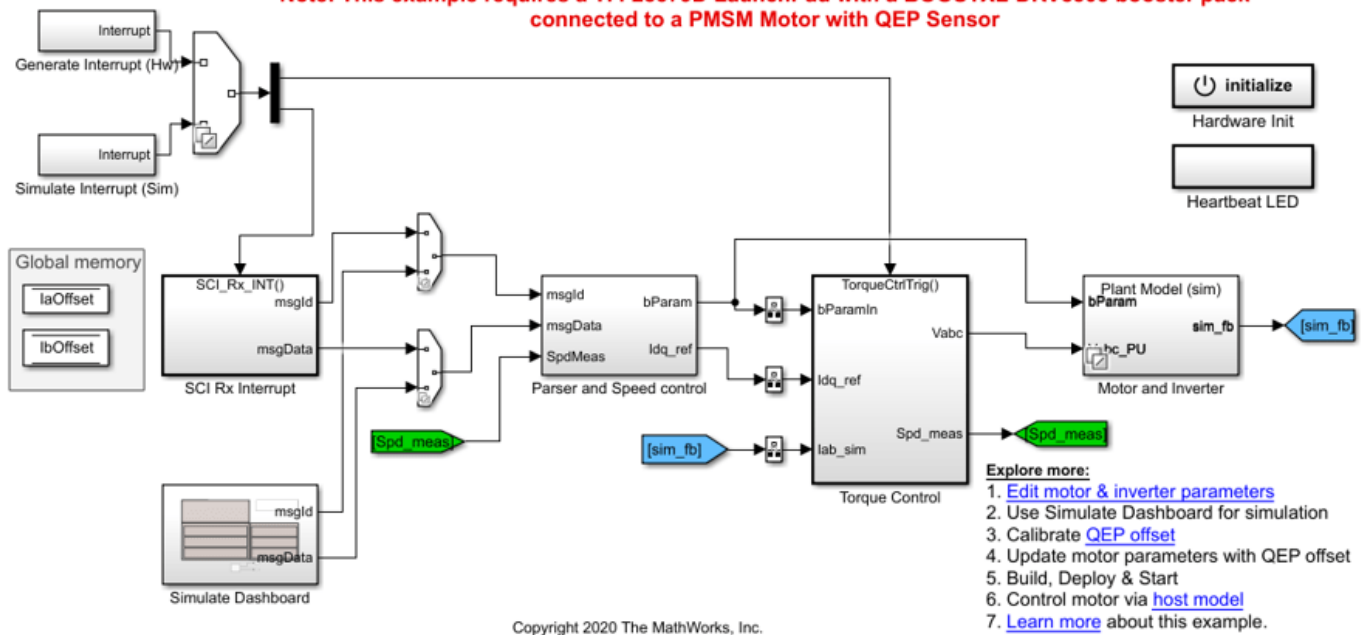
The example includes the model `mcb_pmsm_operating_mode_f28379d`.

You can use the model for both simulation and code generation. You can also use the `open_system` command to open the Simulink® model:

```
open_system('mcb_pmsm_operating_mode_f28379d.slx');
```

Control Parameter Gain Tuning (Manual) in Hardware and Plant Validation

Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack connected to a PMSM Motor with QEP Sensor



Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

1. Motor Control Blockset™
2. Embedded Coder®
3. Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
4. Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate Model

Follow these steps to simulate the model.

1. Open the target model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the target model.
3. Open the **mcb_pmsm_operating_mode_f28379d > Simulate Dashboard** subsystem.

Control Panel for Simulation

Control

Select Motor operating mode

Stop

Open loop run

Torque control

Speed control

Every run default values are updated from init script.
To update the default values in dashboard, update the values in init script.

Operating Mode Variables

Open-loop mode

Voltage ref (PU) Speed ref (PU)

Motor torque control mode

Unlock Pos lock

Id Reference Iq Reference Speed limit

Motor speed control mode

Speed Reference

Control loop gains

d-axis current controller

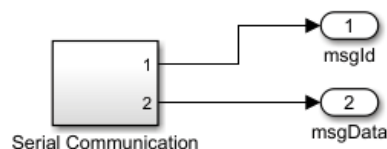
Kp Gain Ki Gain

q-axis current controller

Kp Gain Ki Gain

Speed controller

Kp Gain Ki Gain



Instructions for Open-Loop Run Mode:

1. If the current operating mode is other than open-loop run, select **Stop** in the **Control** area to stop the motor. Select **Open loop run** to start the motor.
2. Set the reference voltage and reference speed values (in per-unit) in the **Voltage ref (PU)** and **Speed ref (PU)** fields available in the **Operating Mode Variables > Open-loop mode** area.

Instructions for Torque Control Mode:

1. If the current operating mode is other than torque control, select **Stop** in the **Control** area to stop the motor. Select **Torque control** in the **Control** area.
2. Enter the value θ (per-unit) in the **Iq Reference** field in the **Operating Mode Variables > Motor torque control mode** area. In addition, set the speed limit of the motor using the **Speed limit** field.
3. Move the slider switch to **Unlock** position in the **Operating Mode Variables > Motor torque control mode** area.
4. Enter the value $\theta . 1$ (per-unit) in the in the **Iq Reference** field (in the **Operating Mode Variables** area) to start running the motor.
5. Open Simulation Data Inspector and select the **Iq_ref_PU** and **Iq_fb_PU** signals for monitoring.
6. Follow steps 2 to 5 for **Id Reference** and monitor the **Id_ref_PU** and **Id_fb_PU** signals.

NOTE: The motor can reach high speeds if you run it under no load condition in this operating mode. In addition, the motor will not meet the Iq reference current under no load condition in this operating mode.

Instructions for Speed Control Mode:

1. If the current operating mode is other than speed control, select **Stop** in the **Control** area to stop the motor. Select **Speed control** in the **Control** area.
2. Enter the value $\theta . 5$ (per-unit) in the **Speed Reference** field in the **Operating Mode Variables > Motor speed control mode** area.
3. Open Simulation Data Inspector and select the **Speed_ref_PU** and **Speed_fb_PU** signals for monitoring.

Instructions for Tuning Gain of Torque Controller:

1. If the current operating mode is other than torque control, select **Stop** in the **Control** area to stop the motor. Select **Torque control** in the **Control** area.
2. Turn the slider switch to **Pos lock** position in the **Operating Mode Variables > Motor torque control mode** area.
3. Enter the value $\theta . 2$ (per-unit) in the **Id Reference** field in the **Operating Mode Variables** area.
4. Open Simulation Data Inspector, select the **Id_ref_PU** and **Id_fb_PU** signals, and observe the step response of these signals.
5. Tune the control gains Kp and Ki for the d-axis current controller. Perform step change to validate the controller gains.

Instructions for Tuning Gain of Speed Controller:

1. If the current operating mode is other than speed control, select **Stop** in the **Control** area to stop the motor. Select **Speed control** in the **Control** area.
2. Enter the value 0.5 (per-unit) in the **Speed Reference** field in the **Operating Mode Variables > Motor speed control mode** area.
3. Enter the value 0.8 (per-unit) in the **Speed Reference** field.
4. Open Simulation Data Inspector, select the **Speed_ref_PU** and **Speed_fb_PU** signals, and observe the speed step response.
5. Tune the control gains K_p and K_i for the speed controller. Perform step change to validate the controller gains.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the model, run (and control) the motor in a selected operating mode, and monitor the debug signals of the model.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter:
`mcb_pmsm_operating_mode_f28379d`

For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

5. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

6. To ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1, load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx).

NOTE:

- Do not directly switch between the open-loop run, torque control, and speed control operating modes. Always stop the motor before changing the operating mode.
- Before you run the motor in speed control mode for the first time, run the motor in open-loop to determine the quadrature encoder index. This helps to start the motor smoothly in the closed-loop speed control mode.

Instructions for Open-Loop Run Mode:

1. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
2. Click the **host model** hyperlink in the target model to open the associated host model.
3. In the Host Serial Setup block mask of the host model, select a **Port name**.
4. Click **Run** on the **Simulation** tab to run the host model.
5. Select **Stop** in the **Control** area to stop the motor.
6. Select **Open loop run** to start the motor.
7. Set the reference voltage and reference speed values (in per-unit) in the **Voltage ref (PU)** and **Speed ref (PU)** fields available in the **Operating Mode Variables > Open-loop mode** area.

Instructions for Torque Control Mode:

1. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
2. Click the **host model** hyperlink in the target model to open the associated host model.
3. In the Host Serial Setup block mask of the host model, select a **Port name**.
4. Click **Run** on the **Simulation** tab to run the host model.
5. Select **Stop** in the **Control** area to stop the motor.
6. Enter the value 0 (per-unit) in the **Id Ref (PU)** and **Iq Ref (PU)** fields in the **Operating Mode Variables > Motor torque control mode** area. In addition, set the speed limit of the motor using the **Speed limit (PU)** field.
7. Select **Torque control** in the **Control** area.
8. Move the slider switch to **Unlock** position in the **Operating Mode Variables > Motor torque control mode** area.
9. Select **Iq_ref** for **Monitor Signal #1** and **Iq_meas** for **Monitor Signal #2** in the **Monitor** area.

10. Enter the value 0.1 (per-unit) in the **Iq Ref (PU)** field (in the **Operating Mode Variables** area) to start running the motor.

11. Open the scope in the host model and monitor the Iq_ref and Iq_meas current signals.

Note: The motor can reach high speeds if you run it under no load condition in this operating mode. In addition, the motor will not meet the Iq reference current under no load condition in this operating mode.

Instructions for Speed Control Mode:

1. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
2. Click the **host model** hyperlink in the target model to open the associated host model.
3. In the Host Serial Setup block mask of the host model, select a **Port name**.
4. Click **Run** on the **Simulation** tab to run the host model.
5. Select **Stop** in the **Control** area to stop the motor.
6. Enter the value 0.5 (per-unit) in the **Speed Ref (PU)** field in the **Operating Mode Variables > Motor speed control mode** area.
7. Select **Speed control** in the **Control** area.
8. Select **Speed_ref** for **Monitor Signal #1** and **Speed_meas** for **Monitor Signal #2** in the **Monitor** area.
9. Open the scope in the host model and monitor the Speed_ref and Speed_meas output signals.

Instructions for Tuning Gain of Torque Controller:

1. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
2. Click the **host model** hyperlink in the target model to open the associated host model.
3. In the Host Serial Setup block mask of the host model, select a **Port name**.
4. Click **Run** on the **Simulation** tab to run the host model.
5. Select **Stop** in the **Control** area to stop the motor.
6. Select **Torque control** in the **Control** area.
7. Turn the slider switch to **Pos lock** position in the **Operating Mode Variables > Motor torque control mode** area.
8. Select **Id_ref** for **Monitor Signal #1** and **Id_meas** for **Monitor Signal #2** in the **Monitor** area.
9. Enter the value 0.2 (per-unit) in the **Id Ref (PU)** field in the **Operating Mode Variables** area.
10. Open the scope and monitor the step response signal.
11. Tune the control gains Kp and Ki for the d-axis current controller.

Instructions for Tuning Gain of Speed Controller:

1. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
2. Click the **host model** hyperlink in the target model to open the associated host model.
3. In the Host Serial Setup block mask of the host model, select a **Port name**.
4. Click **Run** on the **Simulation** tab to run the host model.
5. Select **Stop** in the **Control** area to stop the motor.
6. Select **Speed control** in the **Control** area.
7. Select **Speed_ref** for **Monitor Signal #1** and **Speed_meas** for **Monitor Signal #2** in the **Monitor** area.
8. Enter the value 0.5 (per-unit) in the **Speed Ref (PU)** field in the **Operating Mode Variables > Motor speed control mode** area.
9. Open the scope and observe the reference and the measured speed values.
10. Enter the value 0.8 (per-unit) in the **Speed Ref (PU)** field.
11. Observe the speed step response in the scope.
12. Tune the control gains K_p and K_i for the speed controller.

Instructions for Validating Plant Model:

1. Open the target model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the target model.
3. Open the **mcb_pmsm_operating_mode_f28379d > Simulate Dashboard** subsystem.
4. If the current operating mode is other than speed control, select **Stop** in the **Control** area to stop the motor. Select **Speed control** in the **Control** area.
5. Enter the value 0.2 (per-unit) in the **Speed Reference** field in the **Operating Mode Variables > Motor speed control mode** area.
6. Enter the value 0.5 (per-unit) in the **Speed Reference** field.
7. Open Simulation Data Inspector, select the **Speed_ref_PU** and **Speed_fb_PU** signals, and observe the speed step response.
8. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
9. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model:

```
open_system('mcb_host_mode_control.slx');
```

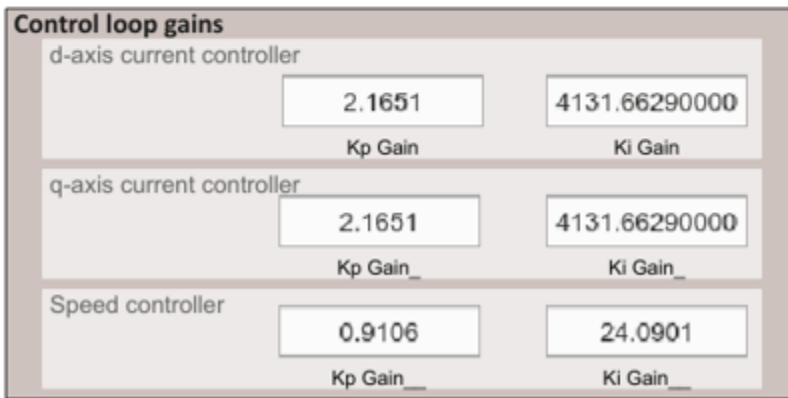
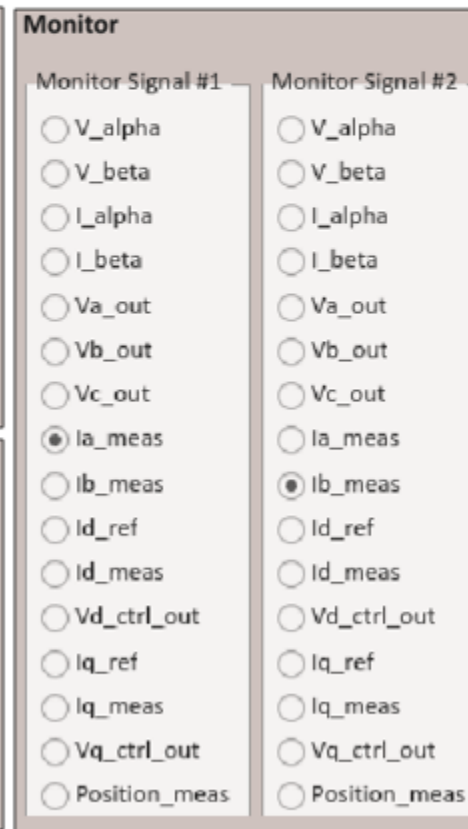
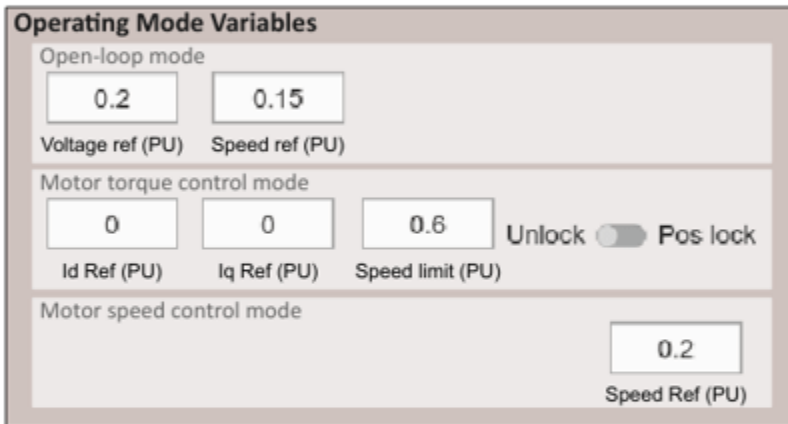
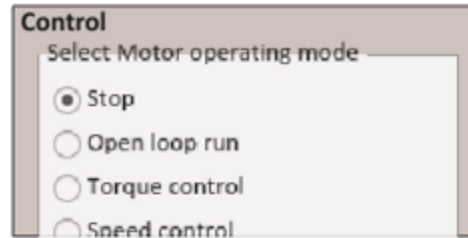
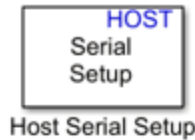
Host model for Control Parameter Gain Tuning (Manual) in Hardware and Plant Validation

Prerequisites:

1. Deploy the target model to the hardware [mcb_pmsm_operating_mode_f28379d](#)
2. You should see and verify the variables from the target model in the base workspace.

Steps:

1. Select the port name in Serial 1 tab of Host Serial Setup block.
2. Caution: Stop the motor when switching between the modes



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10. In the Host Serial Setup block mask of the host model, select a **Port name**.
11. Click **Run** on the **Simulation** tab to run the host model.
12. Select **Stop** in the **Control** area of the host model to ensure that the motor is not running.
13. Select **Speed control** in the **Control** area.
14. Select **Speed_ref** for **Monitor Signal #1** and **Speed_meas** for **Monitor Signal #2** in the **Monitor** area.

15. Enter the value 0.2 (per-unit) in the **Speed Ref (PU)** field in the **Operating Mode Variables > Motor speed control mode** area.

16. Open the scope and observe the reference and the measured speed values.

17. Enter the value 0.5 (per-unit) in the **Speed Ref (PU)** field.

18. Observe the speed step response in the scope.

19. Compare the speed step responses obtained in steps 7 (with simulation) and 18 (with code generation).

NOTE: In the **Control loop gains** area, you must enter the gain values that can be represented by the datatype defined in the model initialization script.

For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

Tune PI Controllers Using Field Oriented Control Autotuner

This example computes the gain values of PI controllers available in the speed and current control loops by using the Field Oriented Control Autotuner block. For details about this block, see Field Oriented Control Autotuner. For details about field-oriented control, see “Field-Oriented Control (FOC)” on page 4-2.

Use the code-generation capability of the example to deploy the gain tuning algorithm to the target hardware. This enables you to run the algorithm by using hardware connected to a motor and to compute accurate PI controller gains by processing motor feedback in real-time on the target hardware. The example uses a quadrature encoder sensor to measure the rotor position.

Model

The example includes the target model `mcb_pmsm_foc_autotuner_f28379d`.

You can use this model for both simulation and code generation. Use the `open_system` command to open the model.

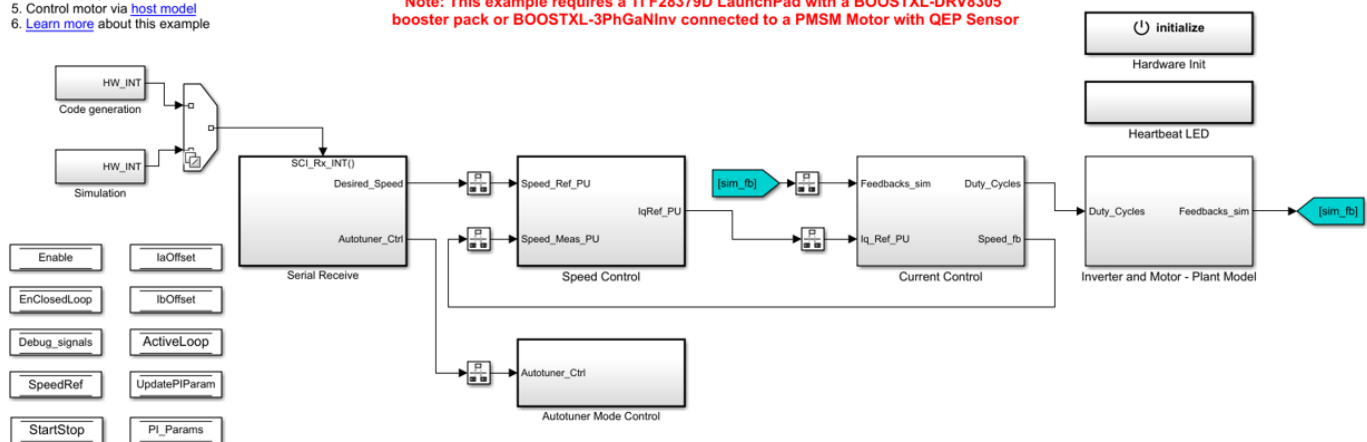
```
open_system('mcb_pmsm_foc_autotuner_f28379d.slx');
```

Explore more:

1. [Edit motor & inverter parameters](#)
2. Use [Offset computation model](#) to find out position offset.
3. Update offset in init script to variable `'pmsm.PositionOffset'`
4. Build, Deploy & Start
5. Control motor via [host model](#)
6. [Learn more](#) about this example

Tuning PI controllers for current and speed using FOC Autotuner

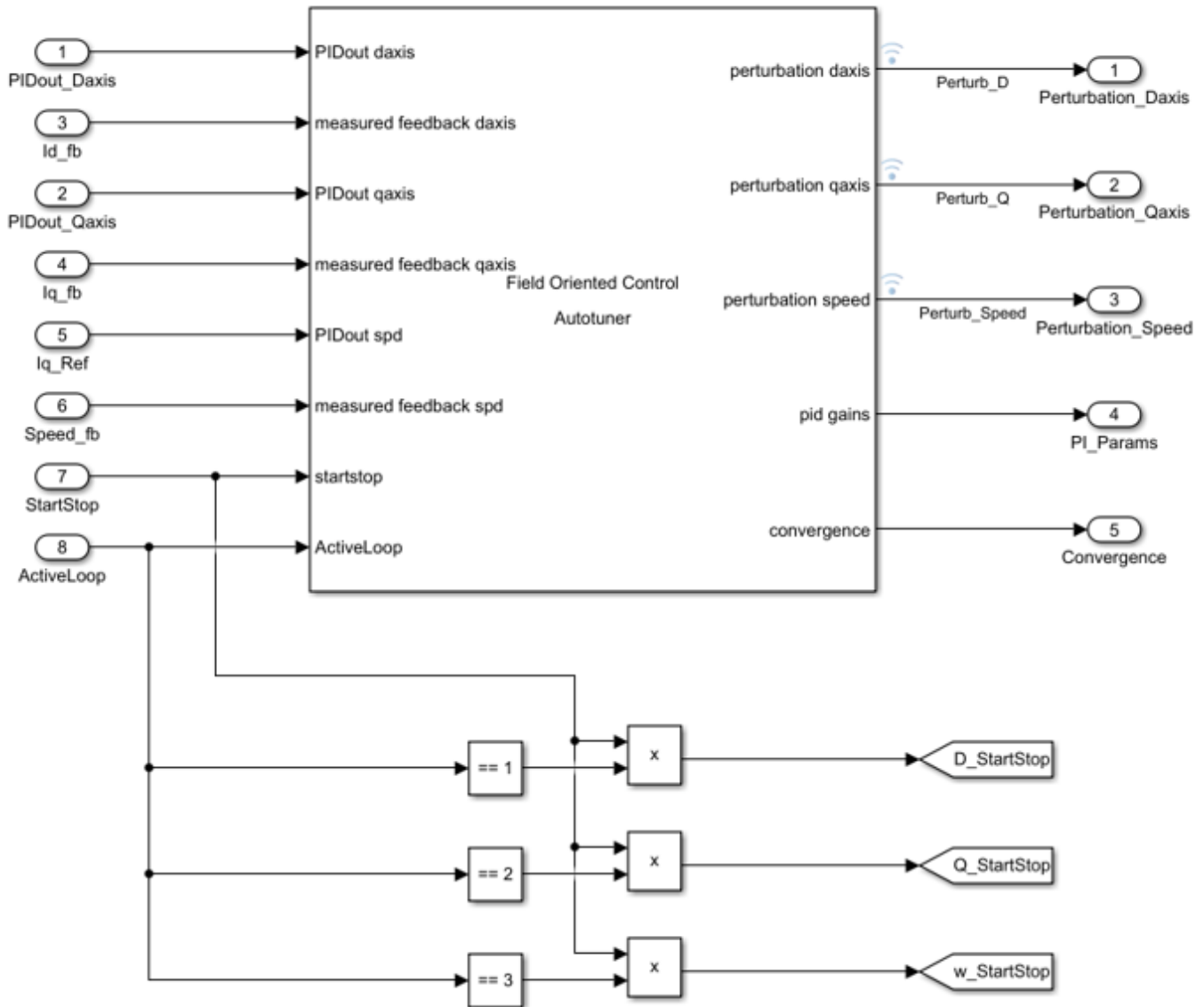
Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack or BOOSTXL-3PhGaNInv connected to a PMSM Motor with QEP Sensor



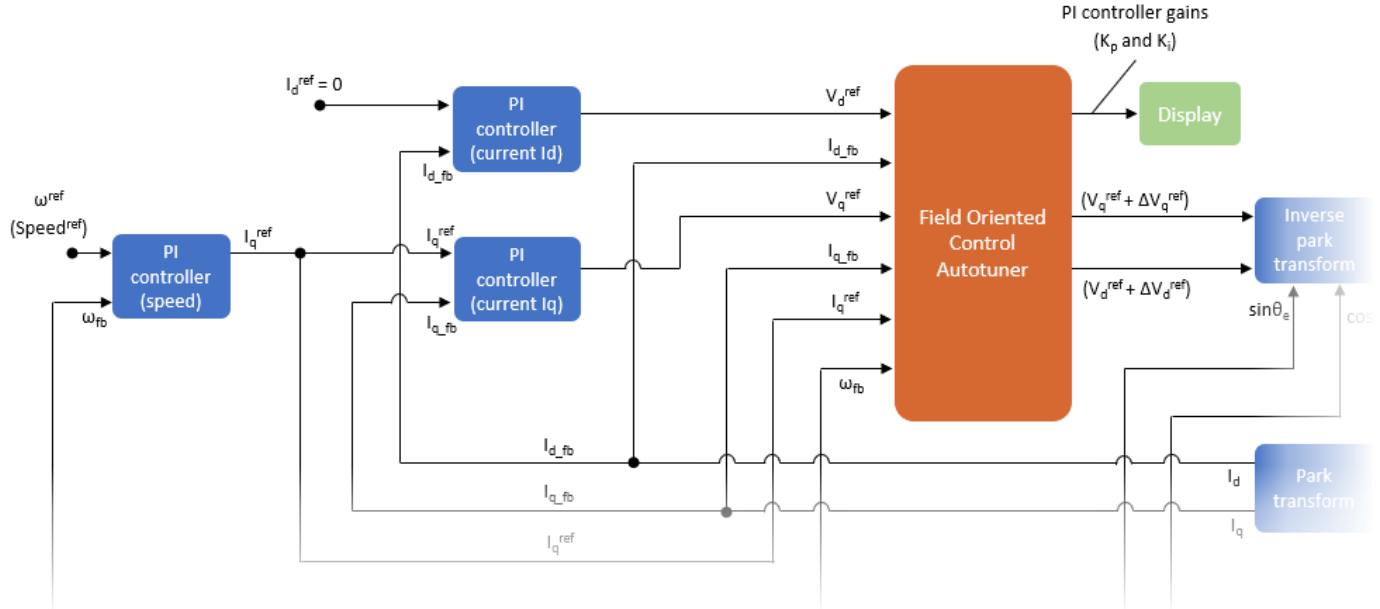
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The Field Oriented Control Autotuner block iteratively tunes the d- and q-axis current control and speed control loops and computes the gains of the current and speed PI controllers. Use this command to locate the Field Oriented Control Autotuner block available inside the model:

```
open_system('mcb_pmsm_foc_autotuner_f28379d/Current Control/Control_System/Closed Loop Control/F
```



The block processes the current and speed feedback from the plant. It also processes the voltage output of the d- and q-axis current PI controllers to compute the PI controller gains (K_p and K_i).



For more details on the FOC architecture, see “Field-Oriented Control (FOC)” on page 4-2.

Required MathWorks® Products

To simulate model:

- Motor Control Blockset™
- Simulink Control Design™

To generate code and deploy model:

- Motor Control Blockset™
- Simulink Control Design™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors

Prerequisites for Simulation and Hardware Deployment

1. Open the model initialization script for the target model. Check and update the motor, inverter, and other control system and hardware parameters available in the script. For instructions on locating and editing the model initialization script associated with a target model, see “Estimate Control Gains from Motor Parameters” on page 3-2.

2. In the **Inverter & Target Parameters** section of the model initialization script, verify that the `mcb_SetInverterParameters` function uses the argument `BoostXL-DRV8305`. This enables the script to use the preprogrammed parameters for the BOOSTXL-DRV8305 inverter.

3. Configure these parameters correctly in the model initialization script. These variables are essential for the gain-tuning algorithm to compute the PI controller gains. If the values of these variables are incorrect, the model may fail to bring the motor to the steady speed state.

- `pmsm.p`

- `pmsm.I_rated`
- `pmsm.PositionOffset`
- `pmsm.QEPslits`

4. If you are using a motor that is not listed in the `mcb_SetPMSMMotorParameters` function (used in the **System Parameters // Hardware parameters** section of the model initialization script), tune the default values of the following initial gains available in the **Initial PI parameters** section of the model initialization script. This ensures that the motor reaches the steady state of speed-control operation:

- `PI_params.Kp_Id`
- `PI_params.Ki_Id`
- `PI_params.Kp_Iq`
- `PI_params.Ki_Iq`
- `PI_params.Kp_Speed`
- `PI_params.Ki_Speed`

When you either simulate or run the example on a target hardware, the example uses crude values of the PI controller gains to achieve the steady state of speed-control operation.

Note: When using this example, if the motor (whether it is listed or not in the `mcb_SetPMSMMotorParameters` function) does not run, try tuning the default values of these parameters.

5. In the **FOC Autotuner parameters** section of the model initialization script, check and update the parameters of the Field Oriented Control Autotuner block. This sets the reference bandwidth and phase margin values for both the speed and the current PI controllers.

Simulate the Target Model

Simulating the example is optional. Follow these steps to simulate the target model:

1. Open the target model.
2. Click **Run** on the **Simulation** tab to simulate the target model.
3. Observe the computed PI controller gain values in the Display blocks available in the `mcb_pmsm_foc_autotuner_f28379d/Current Control/PI_Params_Display_and_Logging` subsystem.

The computed gains might not be accurate because step 4 in the Prerequisites for Simulation and Hardware Deployment section checks the accuracy of only four motor parameters.

If you want to compute and test the PI controller gains using simulation, follow these steps before clicking **Run** on the **Simulation** tab of the target model.

- In the **System Parameters // Hardware parameters** section of the model initialization script, verify that the `mcb_SetPMSMMotorParameters` function uses an argument that represents your motor (for example, `Teknic2310P`). Open the `mcb_SetPMSMMotorParameters` function to see the preprogrammed cases that store the motor parameters of commonly used PMSMs.

If the `mcb_SetPMSMMotorParameters` function does not list your PMSM, determine the parameters for your motor.

- If you have motor control hardware, you can estimate the parameters for your motor, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the `motorParam` variable (in the MATLAB® workspace) with the estimated motor parameters.

- If you obtain the motor parameters from the datasheet or other sources, add and configure the motor parameters in the model initialization script. These parameter values override the selected pre-programmed case in the function `mcb_SetPMSMMotorParameters`.

If you use the parameter estimation tool, do not update the motor parameters directly in the model initialization script. The script automatically extracts the motor parameters from the updated `motorParam` variable in the workspace.

After you simulate the target model and determine the gains, update any target model (either a Motor Control Blockset example model or your own model) with the computed gain values to quickly bring the motor to a steady speed state.

Deploy the example to the target hardware to tune the PI controller gains more accurately by using an actual hardware connected to a motor. For more details, see the Generate Code and Deploy Model to Target Hardware section.

Generate Code and Deploy Model to Target Hardware

This section shows how to generate code and run the algorithm for tuning the PI controller gains on the target hardware. Running the example on the hardware enables you to compute the PI controller gains more accurately by processing the feedback from an actual plant in real-time.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you run the host model on the host computer, deploy the target model to the controller hardware board. The host model uses serial communication to command the target model and run the motor in closed-loop control.

Required Hardware

The example supports the following hardware configuration. You can also use the target model name to open the model from the MATLAB® command prompt.

LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: `mcb_pmsm_foc_autotuner_f28379d`

For more information on connections related to this hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Complete the hardware connections.
2. The model automatically computes the analog to digital converter (ADC) offset (also known as current offset). To disable this functionality (enabled by default), update the value of the `inverter.ADCOffsetCalibEnable` variable in the model initialization script to 0.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization script. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

3. Compute the quadrature encoder index offset value and update it in the `pmsm.PositionOffset` variable in the model initialization script of the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

4. Open the target model. If you want to change the default hardware configurations of the model, see “Model Configuration Parameters” on page 2-2.

5. Load a sample program to the CPU2 of the LAUNCHXL-F28379D board. For example, load the program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`). This ensures that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

7. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_host_autotuner_f28379d.slx');
```

PMSM Field Oriented Control Autotuner Host

Prerequisites:

1. Deploy the target model to the hardware [mcb_pmsm_foc_autotuner_f28379d](#)
2. Verify the variables from the target model in the base workspace.

Steps:

1. Select the serial port in **Host Serial Setup**
2. Use the **Motor** switch to start motor.
3. Input speed reference which is approximately half of the rated speed of the motor.
4. Ensure the motor operation is stable by observing the speed signal in the scope.
5. Start tuning process using the **Autotuner** switch. Keep the **PI Parameters** switch in 'Autotuner' during tuning process.
6. If you wish to repeat the experiment, put the **PI Parameters** switch to 'Default' position to write the default PI parameters to controllers.
7. Revert the **PI Parameters** switch to 'Autotuner'. Use the 'Autotuner' switch to start tuning again.

Stop Start Motor

Speed Ref [RPM]

Stop Start Autotuner

Autotuner Default PI Parameters

Tuning Status

---	---	---
Kp_Daxis	Kp_Qaxis	Kp_Speed
---	---	---
Ki_Daxis	Ki_Qaxis	Ki_Speed

HOST

Serial Setup

Serial Communication

SelectedSignals

Debug1 Debug2

Debug signals

- Speed_Ref & Speed_Feedback
- Id_Ref & Id_Feedback
- Iq_Ref & Iq_Feedback
- Ia & Ib
- Ia & Pos

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For details on serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

8. In the Host Serial Setup block parameters dialog box, select the **Port name** to which you have connected the target hardware.

9. Turn the **Motor** slider switch to the **Start** position to start running the motor.

10. Update the reference speed value in the **Speed Ref [RPM]** field. It is recommended that you use a value that is approximately half the rated speed of the motor.

11. In the **Debug signals** section, select **Speed_Ref & Speed_Feedback** and monitor the speed signals in the **SelectedSignals** time scope. Wait until the motor reaches a steady speed.

The example can begin tuning only in the steady speed state.

12. Check that the **PI Parameters** slider switch is in the **Autotuner** position.

13. Turn the **Autotuner** slider switch to the **Start** position to start autotuning the PI controller gains. The tuning process introduces perturbations depending on the controller goals (bandwidth and phase margin) in the controller output. The example uses the system response to the perturbations to calculate the optimal controller gain values.

The model performs these tests iteratively on the motor and determines an accurate set of Kp and Ki gains for the current and speed PI controllers.

The **Tuning Status** display changes status from **Tuning not started** to **Tuning in progress**.

Note: When tuning is in progress, ensure that the **PI Parameters** slider switch remains in the **Autotuner** position.

14. When the tuning process successfully completes, the **Tuning Status** display changes status from **Tuning in progress** to **Tuning complete**.

The target model updates the speed and current PI controllers running on the target hardware with the computed Kp and Ki gains. In addition, the host model displays these values.

15. If the gain-tuning algorithm encounters an error during the tuning process, the **Tuning Status** display shows **Tuning failed**. Turn the **Autotuner** slider switch to the **Stop** position and see the **Troubleshooting** section for the troubleshooting instructions.

16. If you have successfully completed the tuning process, turn the **Autotuner** slider switch to the **Stop** position. Turn the **PI Parameters** slider switch to the **Default** position to enable the default operating mode of the target model. In this mode, the target model uses the computed gain values to operate the motor using FOC.

17. Validate the computed gain values. For instructions, see the **Validate Computed PI Controller Gains** section.

Validate Computed PI Controller Gains

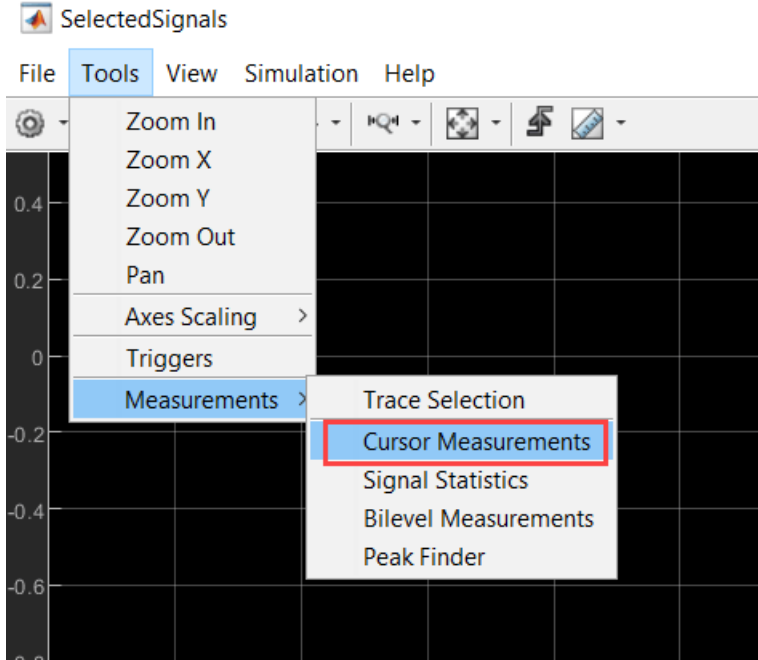
1. Check that the motor is running and that the **PI Parameters** slider switch is in the **Default** position.

2. Select the **Speed_Ref & Speed_Feedback** debug signal in the **Debug signals** section of the host model.

3. Open the **SelectedSignals** time scope to monitor the reference speed and speed feedback signals.

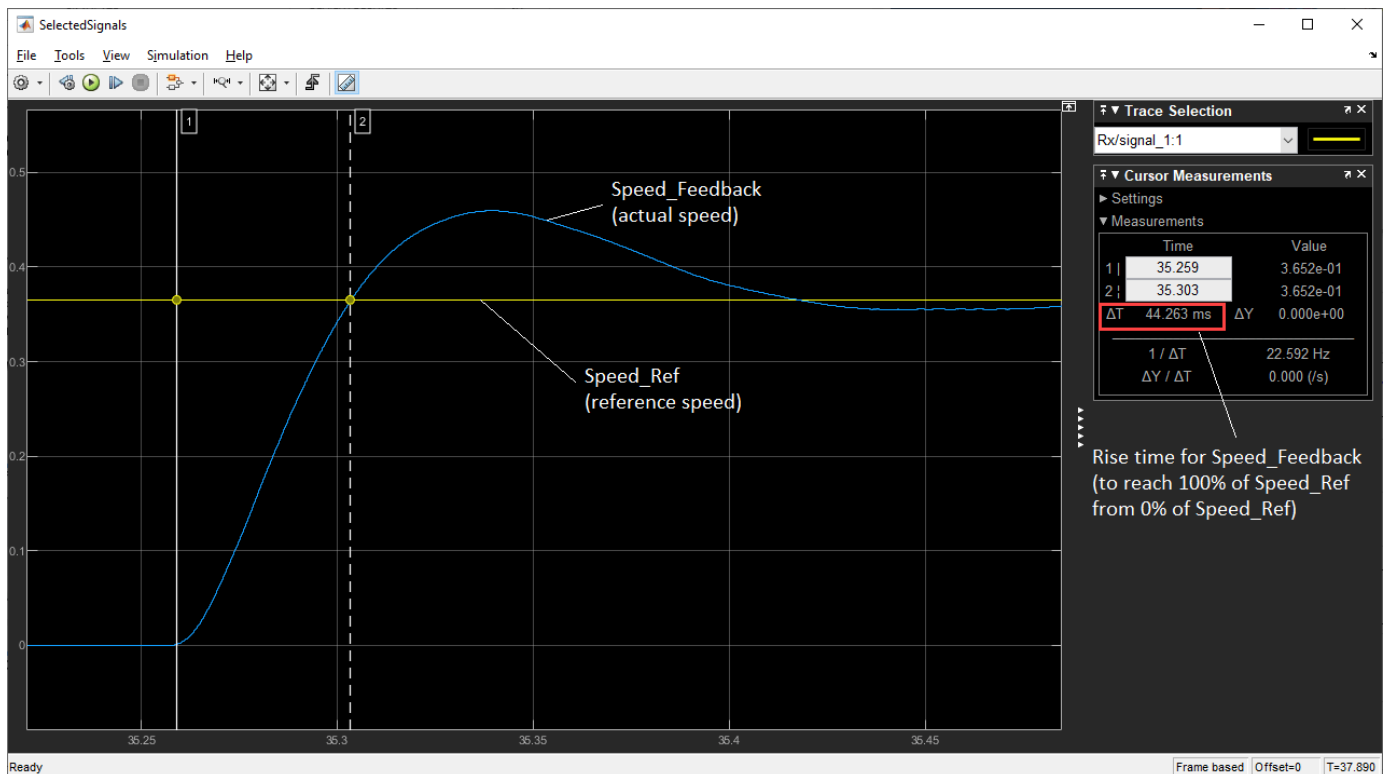
4. Update the reference speed (for your motor control application) in the **Speed Ref [RPM]** field and monitor the signals in the time scope.

5. In the **SelectedSignals** window, navigate to **Tools > Measurements** and select **Cursor Measurements** to display the **Cursor Measurements** area.



6. Drag cursor-1 to a position that indicates zero Speed_Ref (just before Speed_ref rises). Drag cursor-2 to a position where Speed_Feedback meets Speed_Ref for the first time.

ΔT indicates the actual response time of the FOC algorithm (time taken by the motor to reach 100% of the reference speed from zero reference speed).



7. For the speed PI controller, use the `PI_params.SpeedBW` variable available in the model initialization script to determine the bandwidth of the speed PI controller. Compute the theoretical response time using this relation:

$$Response_time = \left(\frac{2}{PI_params.SpeedBW} \right)$$

Compare the theoretical `Response_time` with the actual response time ΔT to validate the speed PI controller gains.

Similarly, you can validate the current PI controller gains by analyzing the step responses of the d and q current PI controllers.

Troubleshooting

Follow these steps to troubleshoot failed gain-tuning instances.

1. Identify the loop (either d current, q current, or speed) for which the tuning process failed.

The target model tunes the PI controllers in this sequence:

d current controller → q current controller → speed controller

Tuning failure of one controller in this sequence results in incorrect gain tuning for the subsequent controllers.

Check the computed gains for the three controllers using the Display blocks available in the host model. A zero `Kp` or `Ki` controller gain value indicates that the tuning process failed for the respective controller.

Follow the subsequent steps for the first PI controller in the preceding sequence for which the tuning failed.

2. Select the controller reference and feedback signals for the controller identified in step 1, in the **Debug signals** section (for example, **Iq_Ref & Iq_Feedback** for the q current controller) and open the **SelectedSignals** time scope.

3. Check that the **PI Parameters** slider switch is in the **Autotuner** position.

4. Turn the **Autotuner** slider switch to the **Start** position to run the tuning process again.

5. Monitor the feedback signal for the controller identified in step 1 (for example, **Iq_Feedback**) in the **SelectedSignals** time scope.

Case 1: Follow these steps if the peak value of the controller feedback signal satisfies one of these conditions:

- Value is too high (greater than 1)
- Value is too low (less than `PI_params.CurrentSineAmp` for the current controllers or less than `PI_params.SpeedSineAmp` for the speed controller)

Note: The `PI_params.CurrentSineAmp` and `PI_params.SpeedSineAmp` variables are defined in the model initialization script.

- a. If the controller identified in step 1 is the d or the q current controller, modify the `PI_params.CurrentSineAmp` variable such that it is less than the peak value of the controller feedback signal.
- b. If the controller identified in step 1 is the speed controller, modify the `PI_params.SpeedSineAmp` variable such that it is less than the peak value of the controller feedback signal.
- c. Turn the **Autotuner** slider switch to the **Stop** position and then to the **Start** position to run the tuning process again.

Case 2: Follow these steps if the peak value of the controller feedback signal lies in the range:

- $[PI_params.CurrentSineAmp, 1]$ (for the current controllers)
- $[PI_params.SpeedSineAmp, 1]$ (for the speed controller)

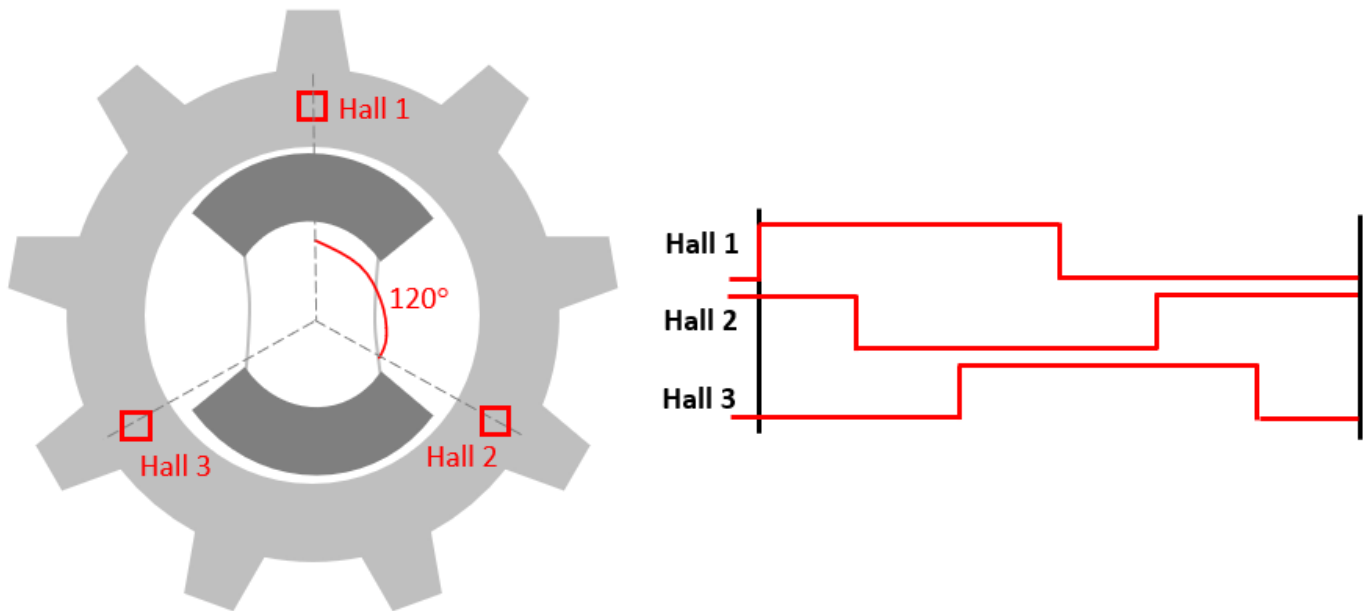
Note: The `PI_params.CurrentSineAmp` and `PI_params.SpeedSineAmp` variables are defined in the model initialization script.

- a. Update the parameters of the Field Oriented Control Autotuner block (that set the reference bandwidth and phase margin values) available in the **FOC Autotuner parameters** section of the model initialization script.
- b. Turn the **Autotuner** slider switch to the **Stop** position and then to the **Start** position to run the tuning process again.

Field-Oriented Control of PMSM Using Hall Sensor

This example implements the field-oriented control (FOC) technique to control the speed of a three-phase permanent magnet synchronous motor (PMSM). The FOC algorithm requires rotor position feedback, which is obtained by a Hall sensor. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

This example uses the Hall sensor to measure the rotor position. A Hall effect sensor varies its output voltage based on the strength of the applied magnetic field. A PMSM consists of three Hall sensors located electrically 120 degrees apart. A PMSM with this setup can provide six valid combinations of binary states (for example, 001,010,011,100,101, and 110). The sensor provides the angular position of the rotor in the multiples of 60 degrees, which the controller uses to compute the angular velocity. The controller can then use the angular velocity to compute an accurate angular position of the rotor.



Models

The example includes these models:

- `mcb_pmsm_foc_hall_f28069m`
- `mcb_pmsm_foc_hall_f28379d`

You can use these models for both simulation and code generation. You can also use the `open_system` command to open the Simulink® model. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_foc_hall_f28069m.slx');
```


However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open a model included with this example.
2. To simulate the model, click **Run** on the **Simulation** tab.
3. To view and analyze the simulation results, click **Data Inspector** on the **Simulation** tab.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- F28069M controller card + DRV8312-69M-KIT inverter: `mcb_pmsm_foc_hall_f28069m`

For connections related to the preceding hardware configuration, see “F28069 control card configuration” on page 7-2.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter: `mcb_pmsm_foc_hall_f28069m`
- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter: `mcb_pmsm_foc_hall_f28379d`

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.

3. The model automatically computes the Analog-to-Digital Converter (ADC) or current offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the Hall sensor offset value and update it in the model initialization script associated with the target model. For instructions, see “Hall Offset Calibration for PMSM Motor” on page 4-67.

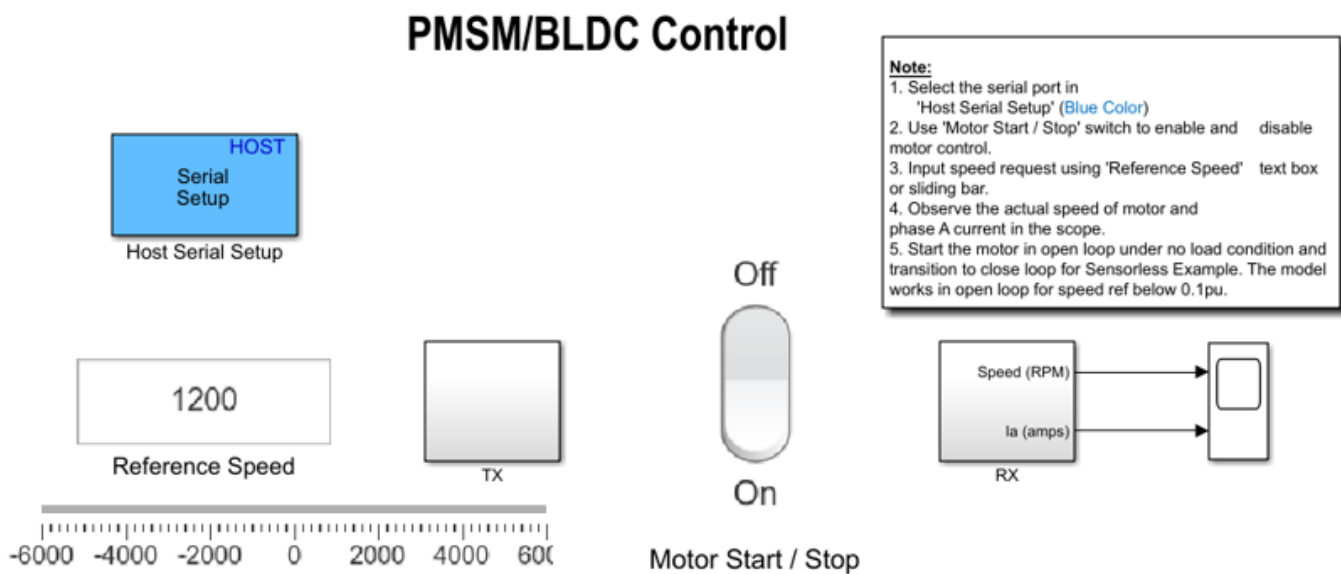
5. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

6. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the model to the hardware.

8. In the target model, click the **host model** hyperlink to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_host_model_f28069m.slx');
```



For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. In the Host Serial Setup block mask of the host model, select a **Port name**.

10. Update the Reference Speed value in the host model.

11. Click **Run** on the **Simulation** tab to run the host model.

12. Change the position of the Start / Stop Motor switch to On, to start running the motor.

NOTE: When you run this example on the hardware at a low Reference Speed, due to a known issue, the PMSM may not follow the low Reference Speed.

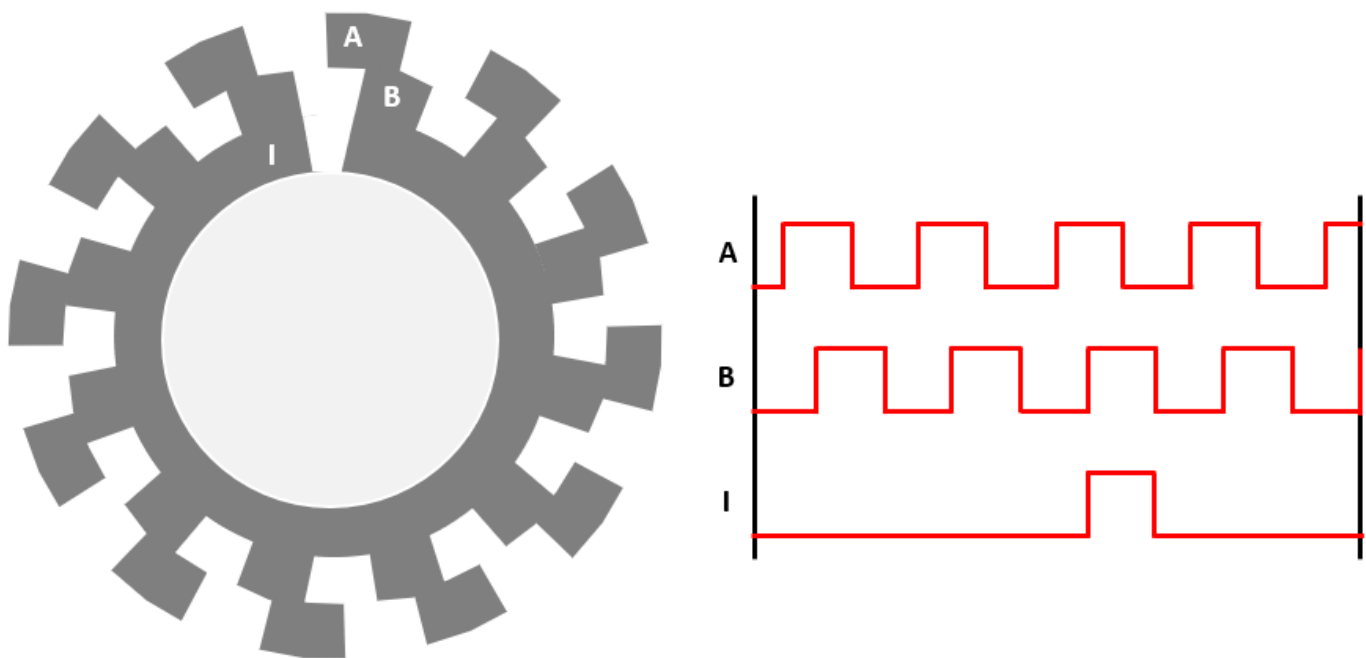
13. Observe the debug signals from the RX subsystem, in the Time Scope of host model.

NOTE: If you are using a F28379D based controller, you can also select the debug signals that you want to monitor.

Field-Oriented Control of PMSM Using Quadrature Encoder

This example implements the field-oriented control (FOC) technique to control the speed of a three-phase permanent magnet synchronous motor (PMSM). The FOC algorithm requires rotor position feedback, which is obtained by a quadrature encoder sensor. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

This example uses the quadrature encoder sensor to measure the rotor position. The quadrature encoder sensor consists of a disk with two tracks or channels that are coded 90 electrical degrees out of phase. This creates two pulses (A and B) that have a phase difference of 90 degrees and an index pulse (I). Therefore, the controller uses the phase relationship between A and B channels and the transition of channel states to determine the direction of rotation of the motor.



Models

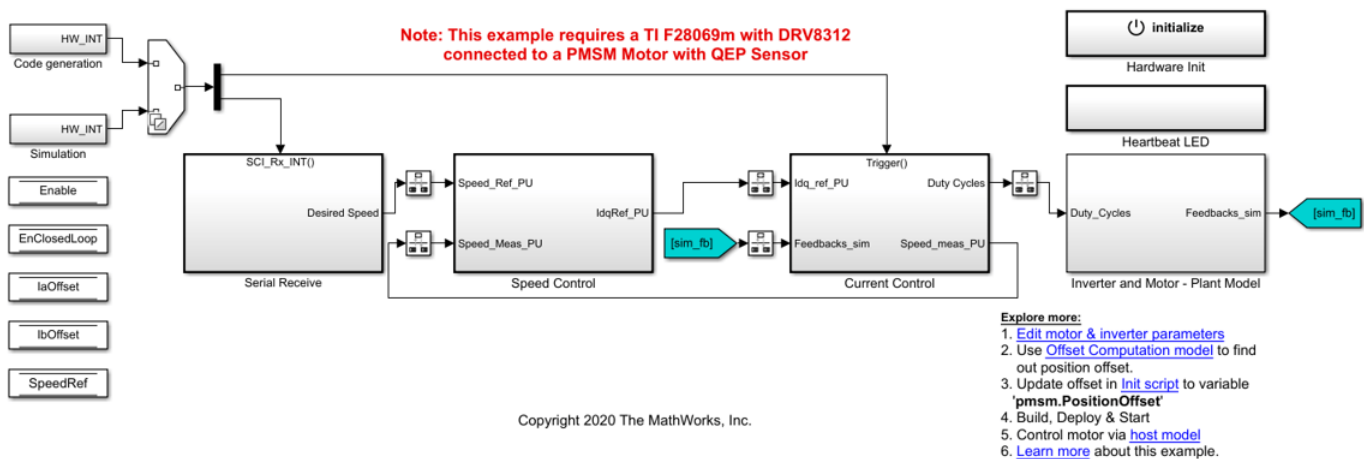
The example includes these models:

- `mcb_pmsm_foc_qep_f28069m`
- `mcb_pmsm_foc_qep_f28069LaunchPad`
- `mcb_pmsm_foc_qep_f28379d`

You can use these models for both simulation and code generation. You can also use the `open_system` command to open the Simulink® models. For example, use this command for a F28069M based controller.

```
open_system('mcb_pmsm_foc_qep_f28069m.slx');
```

Field-Oriented Control for PMSM with QEP sensor



For the model names that you can use for different hardware configurations, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

1. For the models: `mcb_pmsm_foc_qep_f28069m` and `mcb_pmsm_foc_qep_f28069LaunchPad`

- Motor Control Blockset™
- Fixed-Point Designer™

2. For the model `mcb_pmsm_foc_qep_f28379d`

- Motor Control Blockset™

To generate code and deploy model:

1. For the models: `mcb_pmsm_foc_qep_f28069m` and `mcb_pmsm_foc_qep_f28069LaunchPad`

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the model `mcb_pmsm_foc_qep_f28379d`

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open a model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- F28069M control card + DRV8312-69M-KIT inverter: `mcb_pmsm_foc_qep_f28069m`

For connections related to the preceding hardware configuration, see “F28069 control card configuration” on page 7-2.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
`mcb_pmsm_foc_qep_f28069LaunchPad`
- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter:
`mcb_pmsm_foc_qep_f28379d`

NOTE: When using BOOSTXL-3PHGANINV inverter, ensure that proper insulation is available between bottom layer of BOOSTXL-3PHGANINV and the LAUNCHXL board.

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

NOTE: Verify the number of slits available in the quadrature encoder sensor attached to your motor. Check and update the variable `pmsm.QEPSlits` in the model initialization script.

5. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

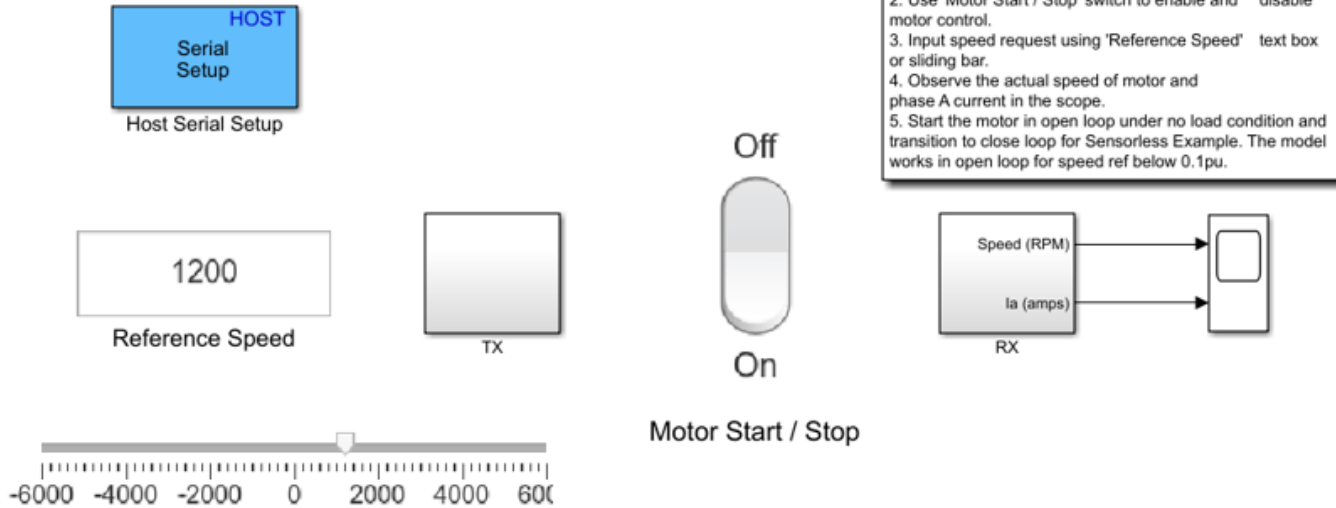
6. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller.

```
open_system('mcb_host_model_f28069m.slx');
```

PMSM/BLDC Control



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For details about the serial communication between the host and target models, see "Host-Target Communication" on page 6-2.

9. In the Host Serial Setup block mask of the host model, select a **Port name**.
10. Update the Reference Speed value in the host model.
11. Click **Run** on the **Simulation** tab to run the host model.
12. Change the position of the Start / Stop Motor switch to On, to start running the motor.
13. Observe the debug signals from the RX subsystem, in the Time Scope of host model.

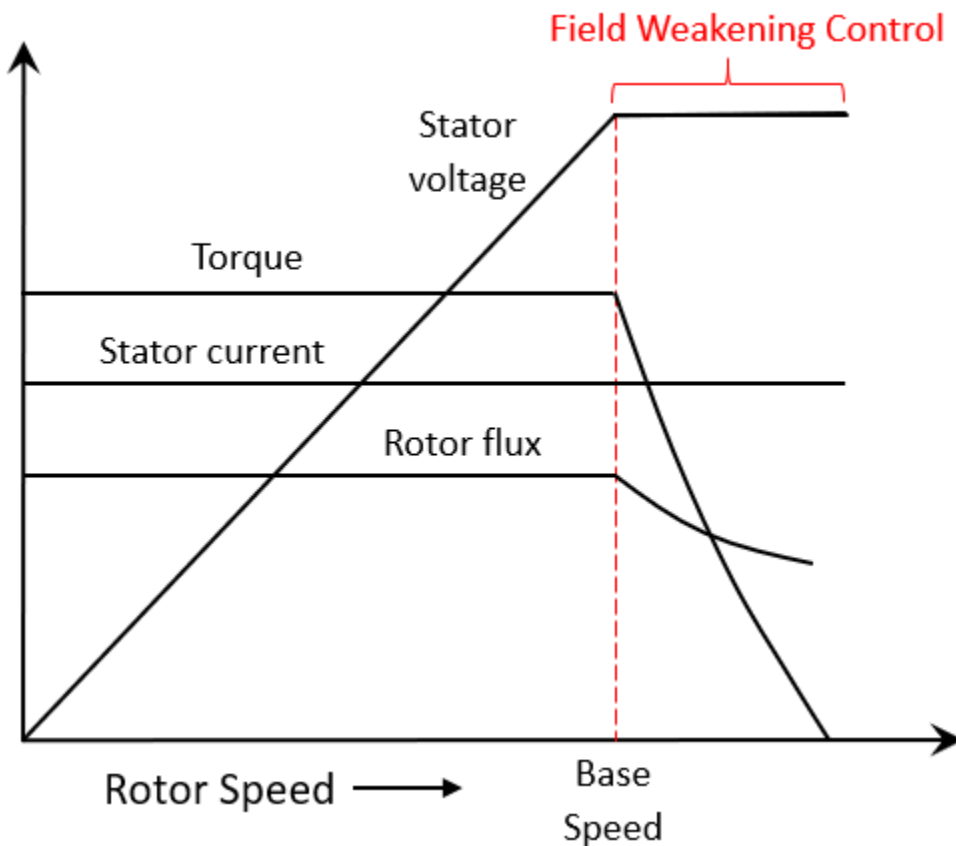
Note: If you are using a F28379D based controller, you can also select the debug signals that you want to monitor.

Field-Weakening Control (with MTPA) of PMSM

This example implements the field-oriented control (FOC) technique to control the torque and speed of a three-phase permanent magnet synchronous motor (PMSM). The FOC algorithm requires rotor position feedback, which is obtained by a quadrature encoder sensor. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

Field-Weakening Control

When you use the FOC algorithm to run a motor with rated flux, the maximum speed is limited by the stator voltages, rated current, and back emf. This speed is called the base speed. Beyond this speed, the operation of the machine is complex because the back emf is more than the supply voltage. However, if you set the d-axis stator current (I_d) to a negative value, the rotor flux linkage reduces, which allows the motor to run above the base speed. This operation is known as field-weakening control of the motor.



Depending upon the connected load and rated current of the machine, the reference d-axis current (I_d) in the field-weakening control also limits the reference q-axis current (I_q), and therefore, limits the torque output. Therefore, the motor operates in the constant torque region until the base speed. It operates in the constant power region with a limited torque above the base speed, as illustrated in the preceding figure.

The computations for the reference current I_d depend on the motor and inverter parameters.

Note:

- For some surface PMSMs, (depending upon the parameters) it may not be possible to achieve higher speeds at the rated current. To achieve higher speeds, you need to overload the motor with maximum currents that are higher than the rated current (if the thermal conditions of the machine are within the permissible limits).
- When you operate the motor above the base speed, we recommend that you monitor the temperature of the motor. During motor operation, if the motor temperature rises beyond the temperature recommended by the manufacturer, turn-off the motor for safety reasons.
- When you operate the motor above the base speed, we recommend that you increment the speed reference in small steps, to avoid the dynamics of field weakening that can make some systems unstable.

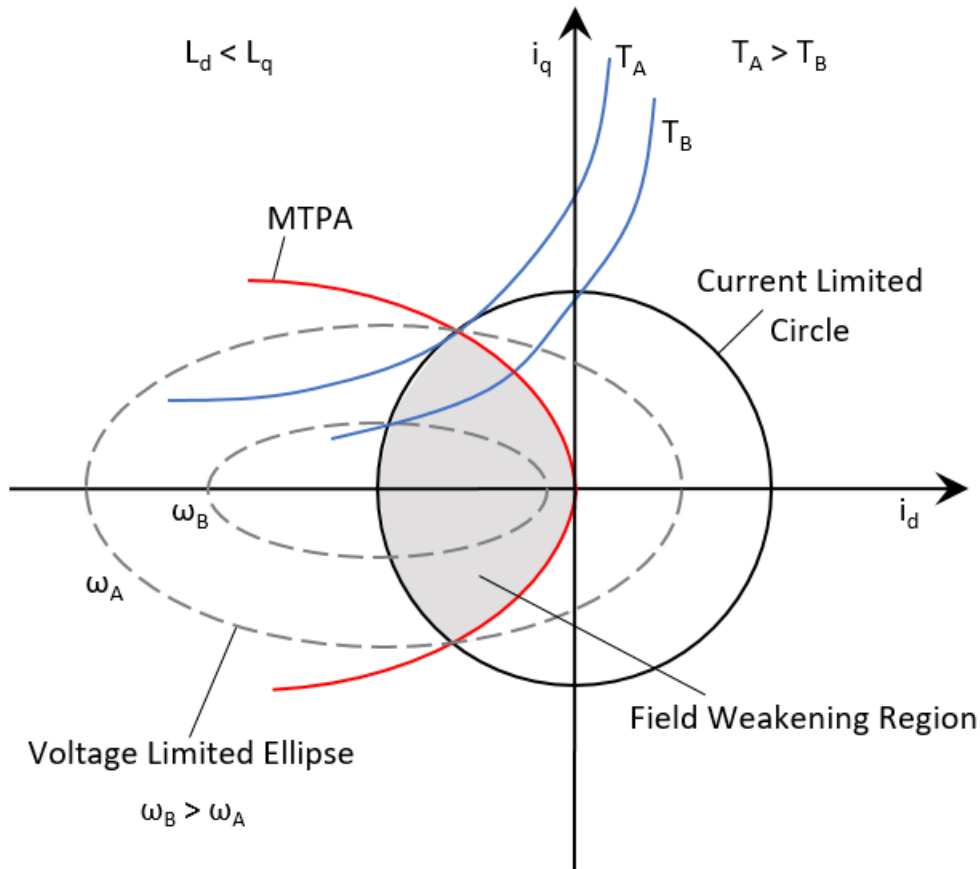
Maximum Torque Per Ampere (MTPA)

For the interior PMSMs, the saliency in the magnetic circuit of rotor results in higher $\frac{L_q}{L_d}$ ratio (greater than 1). This produces reluctance torque in the rotor (in addition to the existing electromagnetic torque). For more information, see MTPA Control Reference.

Therefore, you can operate the machine at an optimum combination of I_d and I_q , and obtain a higher torque for the same stator current,

$$I_{\max} = \sqrt{I_d^2 + I_q^2}.$$

This increases the efficiency of the machine, because the stator current losses are minimized. The algorithm that you use to generate the reference I_d and I_q currents for producing maximum torque in the machine, is called Maximum Torque Per Ampere (MTPA).



For an Interior PMSM (IPMSM), this example computes the reference I_d and I_q currents using the MTPA method until the base speed. For a Surface PMSM (SPMSM), the example achieves MTPA operation by using a zero d-axis reference current, until the base speed.

To operate the motor above the base speed, this example computes the reference I_d and I_q for MTPA and field-weakening control, depending upon the motor type. For a Surface PMSM, Constant Voltage Constant Power (CVCP) control method is used. For an Interior PMSM, Voltage and Current Limited Maximum Torque (VCLMT) control method is used.

For information related to MTPA Control Reference block, see MTPA Control Reference.

Target Communication

For hardware implementation, this example uses a host and a target model. The host model, running on the host computer, communicates with the target model deployed to the hardware connected to the motor. The host model uses serial communication to command the target model and run the motor in a closed-loop control.

Both field-weakening control and MTPA require generation of reference currents that follow the limitations related to:

- Current limited circle

- Voltage limited ellipse
- Motor temperature

To determine the operating point that follows these limits, see the plot generated by the function “Obtain Motor Characteristics” on page 3-15.

In the field-weakening region, some PMSMs may need a stator current that is higher than the rated current of the motor. For details, see the plot generated by the function “Obtain Motor Characteristics” on page 3-15.

Models

This example uses multiple models for these hardware configurations:

Speed control of PMSM with field-weakening and MTPA:

- `mcb_pmsm_fwc_qep_f28069LaunchPad`
- `mcb_pmsm_fwc_qep_f28379d`

Torque control of PMSM with MTPA:

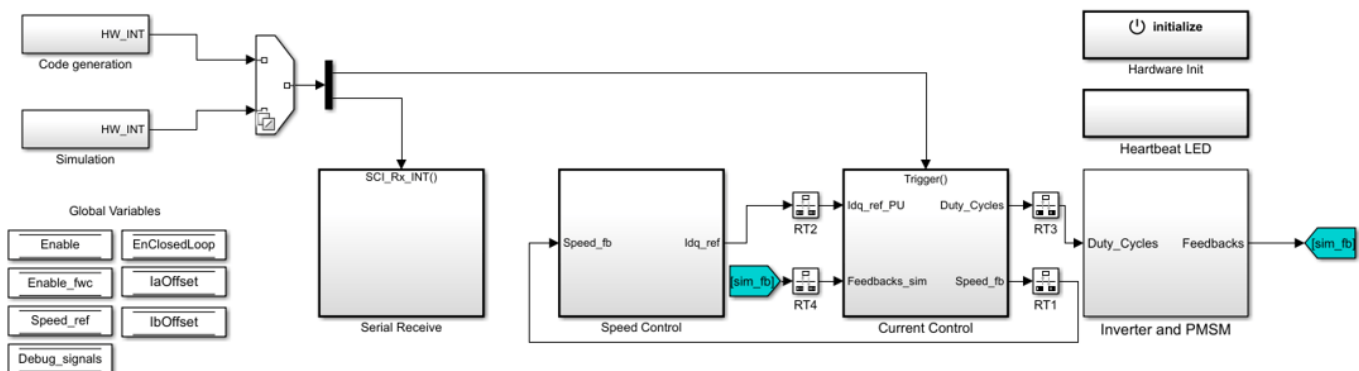
- `mcb_pmsm_mtpa_qep_f28069LaunchPad`
- `mcb_pmsm_mtpa_qep_f28379d`

You can use these models for both simulation and code generation. You can also use the `open_system` command to open the Simulink® models. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_fwc_qep_f28069LaunchPad.slx');
```

PMSM Field Weakening Control with MTPA

Note: This example requires a TI F28069m LaunchPad with a BOOSTXL-DRV8305 booster pack connected to a PMSM Motor with QEP Sensor



Explore more:

1. [Edit motor & inverter parameters](#)
2. Simulate this model
3. Review results in Data Inspector
4. Calibrate [QEP offset](#)
4. Update motor parameters with QEP offset
5. Generate code from hardware tab with "Build, Deploy & Start"
6. Control motor via [host model](#)
7. [Learn more](#) about this example.

Note:
 1) To achieve higher speeds, increase the "Max current" value in "Speed Control \ MTPA Control Reference" block (e.g. set to 2xrated).
 2) It is recommended to monitor motor's temperature for operation above base speed, while working with hardware.

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Required MathWorks® Products

To simulate model:

1. For the models: **mcb_pmsm_fwc_qep_f28069LaunchPad** and **mcb_pmsm_mtpa_qep_f28069LaunchPad**

- Motor Control Blockset™
- Fixed-Point Designer™

2. For the models: **mcb_pmsm_fwc_qep_f28379d** and **mcb_pmsm_mtpa_qep_f28379d**

- Motor Control Blockset™

To generate code and deploy model:

1. For the models: **mcb_pmsm_fwc_qep_f28069LaunchPad** and **mcb_pmsm_mtpa_qep_f28069LaunchPad**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the models: **mcb_pmsm_fwc_qep_f28379d** and **mcb_pmsm_mtpa_qep_f28379d**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor, inverter, and position sensor calibration parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter and position sensor calibration parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate (Speed Control and Torque Control) Models

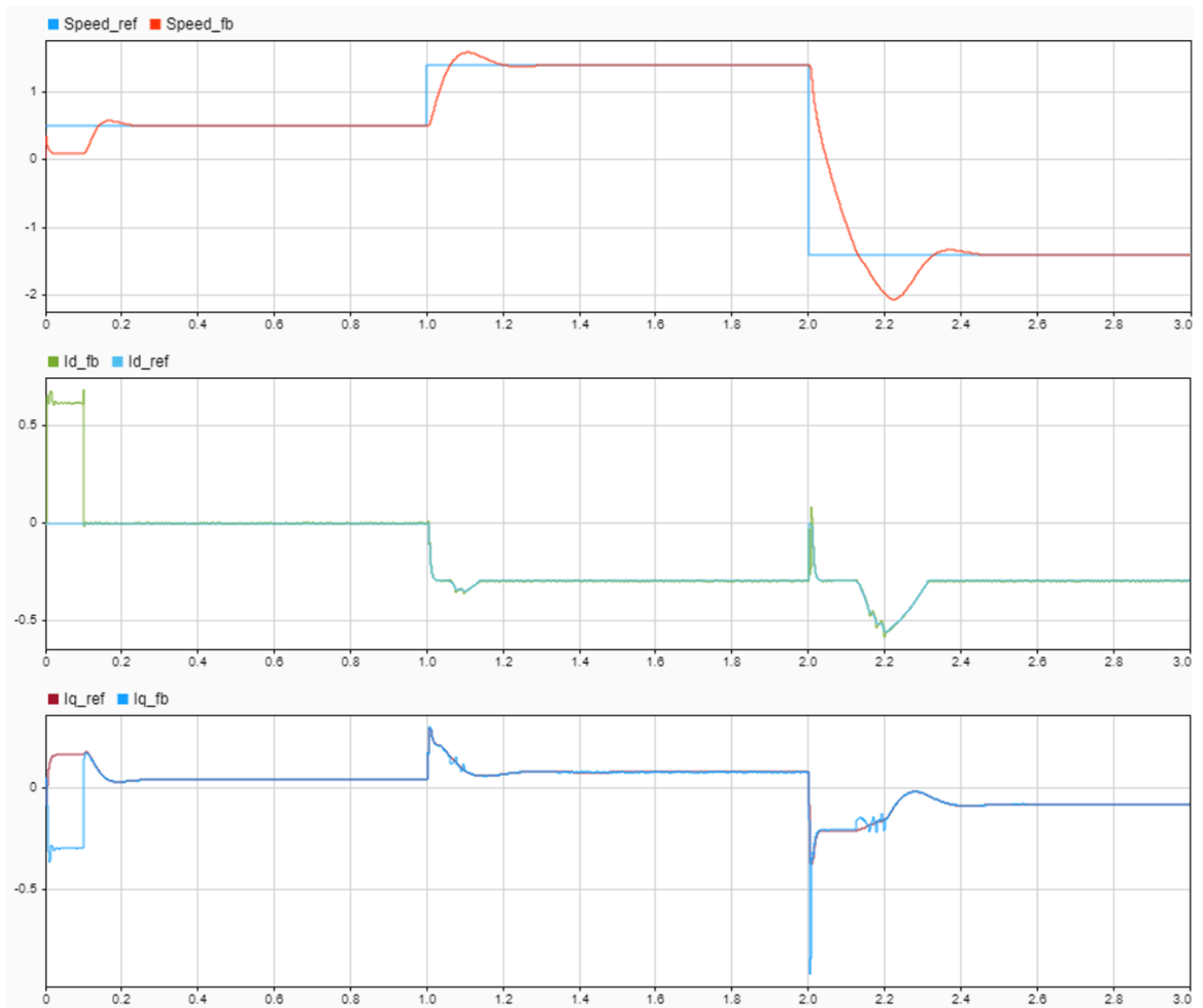
This example supports simulation. Follow these steps to simulate the model.

1. Open a model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Analyze simulation results for Speed Control Model

The model uses the per-unit system to represent speed, currents, voltages, torque, and power. Type PU System at the workspace to see the conversion of one per-unit value into SI units for these quantities.

Observe the dynamics of the system for the speed and current controllers. In addition, notice the negative I_d currents for motor operation above the base speed.



Note:

- For some surface PMSMs, (depending upon the parameters) it may not be possible to achieve higher speeds at the rated current. To achieve higher speeds, you need to overload the motor with maximum currents that are higher than the rated current (if the thermal conditions of the machine are within the permissible limits).
- When you operate the motor above the base speed, we recommend that you monitor the temperature of motor. During motor operation, if the motor temperature rises beyond the temperature recommended by the manufacturer, turn-off the motor for safety reasons.
- When you operate the motor above the base speed, we recommend that you increment the speed reference in small steps, to avoid the dynamics of field weakening that can make some systems unstable.
- In the beginning, the example runs the motor in open-loop control. After it detects the index pulse of the quadrature encoder sensor, the motor starts running using a closed-loop control.

Analyze simulation results for Torque Control Model

Run simulation with the Id and Iq reference currents generated by these three methods:

1. Generate reference currents by using the MTPA Control Reference Block.
2. Generate the MTPA reference currents manually by using the Vector Control Reference Block.
3. Generate the Control Reference without MTPA.

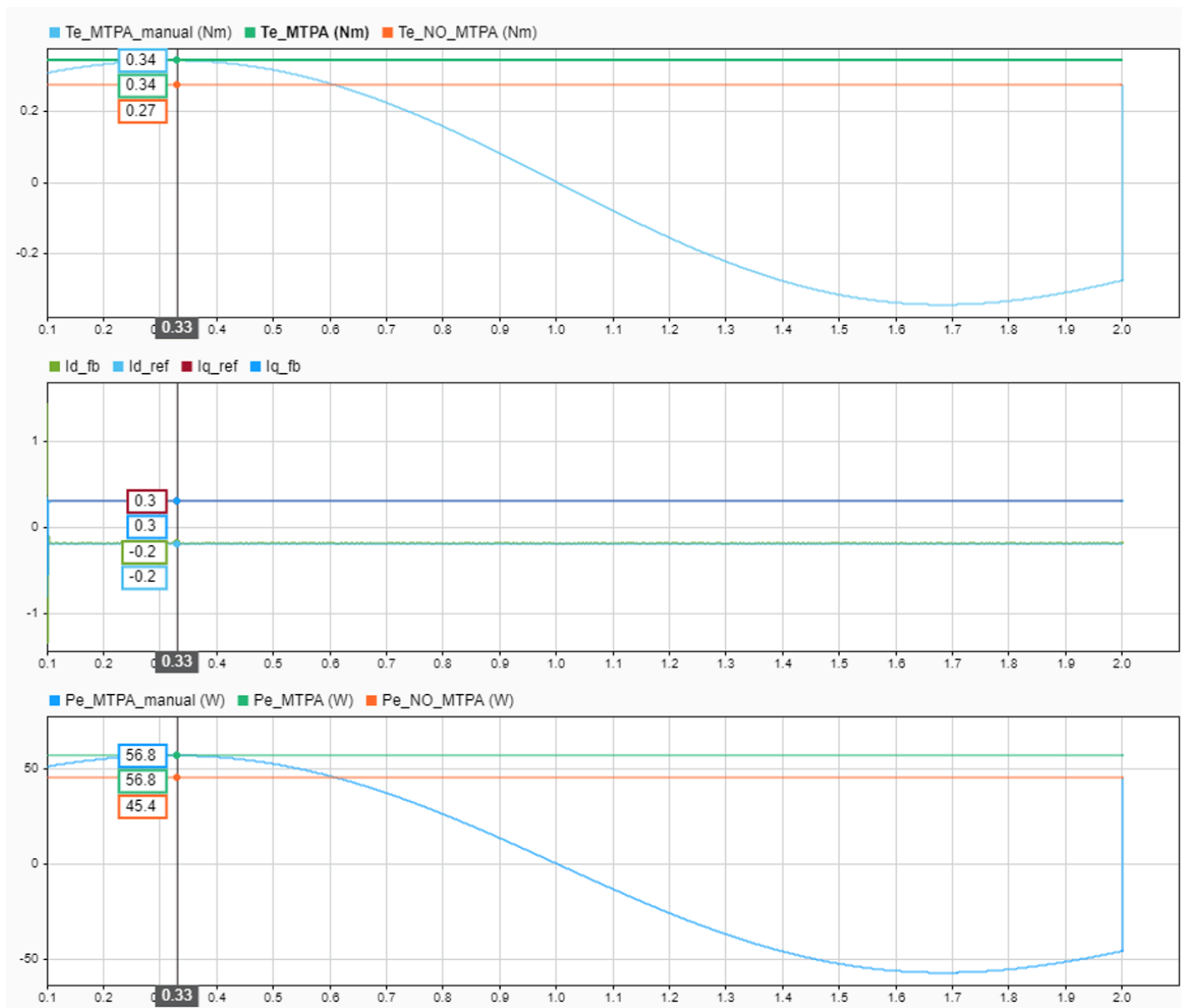
The first method uses mathematical computations to determine the reference currents Id and Iq, after assuming linear inductances.

Use the second method to manually generate the MTPA look-up tables for motors with non-linear inductances. You can illustrate this with the Id and Iq references generated by sweeping the torque angle between $+(\pi/2)$ to $-(\pi/2)$.

Use the last method to obtain the reference currents without the MTPA algorithm.

You can compare the torque and power generated by these three methods in the data inspector.

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



In the preceding example, you can notice that the electrical torque generated using MTPA is 0.34PU whereas electrical torque generated without MTPA is 0.27PU. You can also notice that with a varying torque angle, the maximum generated torque matches the torque produced by MTPA. The negative d-axis current indicates that the MTPA utilizes the reluctance torque for interior PMSM.

NOTE: If you are working with Surface PMSM, change the Type of motor parameter from Interior PMSM to Surface PMSM, in the MTPA Control Reference block located at the location: "Torque Control\MTPA_Reference\MTPA Control Reference."

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host

model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
mcb_pmsm_fwqep_f28069LaunchPad and mcb_pmsm_mtpa_qep_f28069LaunchPad
- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: mcb_pmsm_fwqep_f28379d
and mcb_pmsm_mtpa_qep_f28379d

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Run Models to implement speed and torque control with field-weakening and MTPA

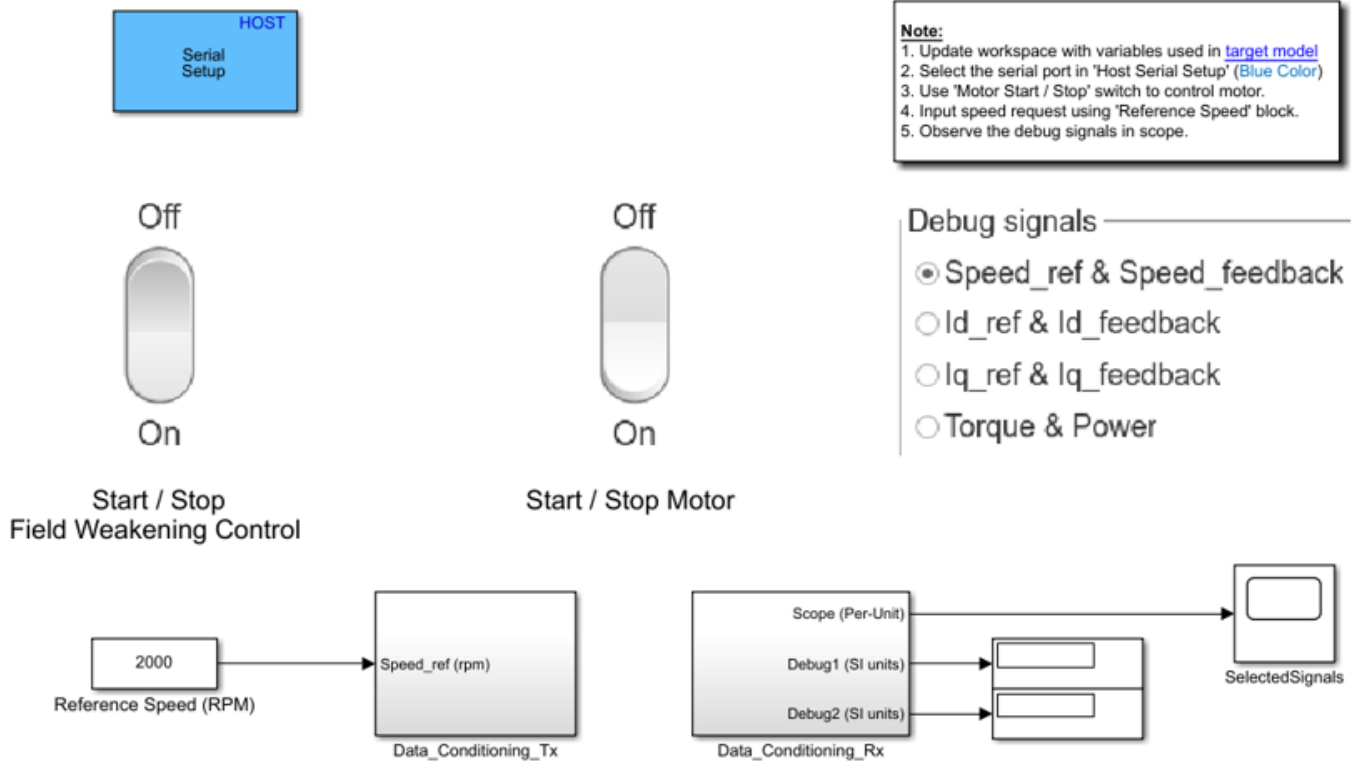
1. Simulate the model and analyze the simulation results by using the preceding section.
2. Complete the hardware connections.
3. The torque control model requires an Interior PMSM with QEP Sensor, driven by an external dynamometer with speed control (that uses the speed control model).
4. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value zero to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

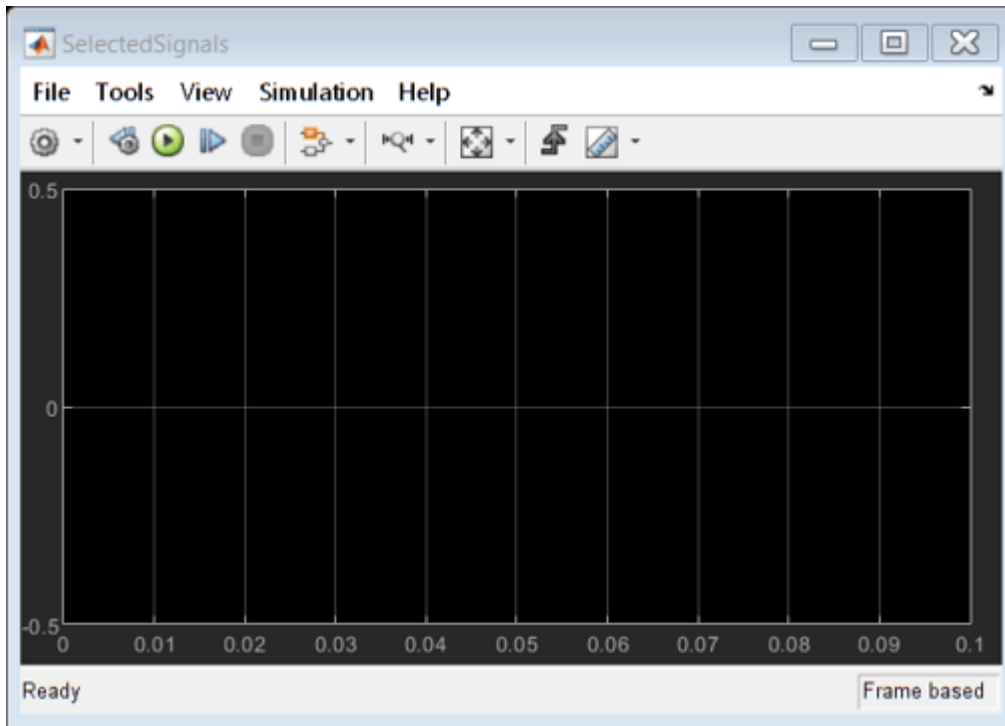
5. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.
6. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.
7. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
8. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
9. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for speed control implementation:

```
open_system('mcb_pmsm_fwqep_host_model.slx');
```

PMSM Field Weakening Control Host



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

10. In the Host Serial Setup block mask of the host model, select a **Port name**.

11. In the Speed control model, update the Reference Speed (RPM) block value. In the Torque control model, update the current request using Imag Reference block.

12. Click **Run** on the **Simulation** tab to run the host model.

13. Change the position of the Start / Stop Motor switch to On, to start and stop running the motor.

14. Enter different reference speeds (or currents) and observe the debug signals from the RX subsystem, in the Time Scope of host model.

Note

- If the position offset is incorrect, this example can lead to excessive currents in the motor. To avoid this, ensure that the position offset is correctly computed and updated in the workspace variable: `pmsm.PositionOffset`.
- When you operate the motor above the base speed, we recommend that you monitor the temperature of motor. During motor operation, if the motor temperature rises beyond the temperature recommended by the manufacturer, turn-off the motor for safety reasons.
- When you operate the motor above the base speed, we recommend that you increment the speed reference in small steps, to avoid the dynamics of field weakening that can make some systems unstable.

References

[1] B. Bose, Modern Power Electronics and AC Drives. Prentice Hall, 2001. ISBN-0-13-016743-6.

[2] Lorenz, Robert D., Thomas Lipo, and Donald W. Novotny. "Motion control with induction motors." *Proceedings of the IEEE*, Vol. 82, Issue 8, August 1994, pp. 1215-1240.

[3] Morimoto, Shigeo, Masayuka Sanada, and Yoji Takeda. "Wide-speed operation of interior permanent magnet synchronous motors with high-performance current regulator." *IEEE Transactions on Industry Applications*, Vol. 30, Issue 4, July/August 1994, pp. 920-926.

[4] Li, Muiyang. "Flux-Weakening Control for Permanent-Magnet Synchronous Motors Based on Z-Source Inverters." Master's Thesis, Marquette University, e-Publications@Marquette, Fall 2014.

[5] Briz, Fernando, Michael W. Degner, and Robert D. Lorenz. "Analysis and design of current regulators using complex vectors." *IEEE Transactions on Industry Applications*, Vol. 36, Issue 3, May/June 2000, pp. 817-825.

[6] Briz, Fernando, et al. "Current and flux regulation in field-weakening operation [of induction motors]." *IEEE Transactions on Industry Applications*, Vol. 37, Issue 1, Jan/Feb 2001, pp. 42-50.

[7] TI Application Note, "Sensorless-FOC With Flux-Weakening and MTPA for IPMSM Motor Drives."

Sensorless Field-Oriented Control of PMSM

This example implements the field-oriented control (FOC) technique to control the speed of a three-phase permanent magnet synchronous motor (PMSM). For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

This example uses the sensorless position estimation technique. You can select either the sliding mode observer or flux observer to estimate the position feedback for the FOC algorithm used in the example.

The Sliding Mode Observer (SMO) block generates a sliding motion on the error between the measured and estimated position. The block produces an estimated value that is closely proportional to the measured position. The block uses stator voltages (V_α, V_β) and currents (I_α, I_β) as inputs and estimates the electromotive force (emf) of the motor model. It uses the emf to further estimate the rotor position and rotor speed. The Flux Observer block uses identical inputs $(V_\alpha, V_\beta, I_\alpha, I_\beta)$ to estimate the stator flux, generated torque, and the rotor position.

If you use flux observer, the example can run both PMSM and brushless DC (BLDC) motors.

The sensorless observers and algorithms have known limitations regarding motor operations beyond the base speed. We recommend that you use the sensorless examples for operations upto base speed only.

Models

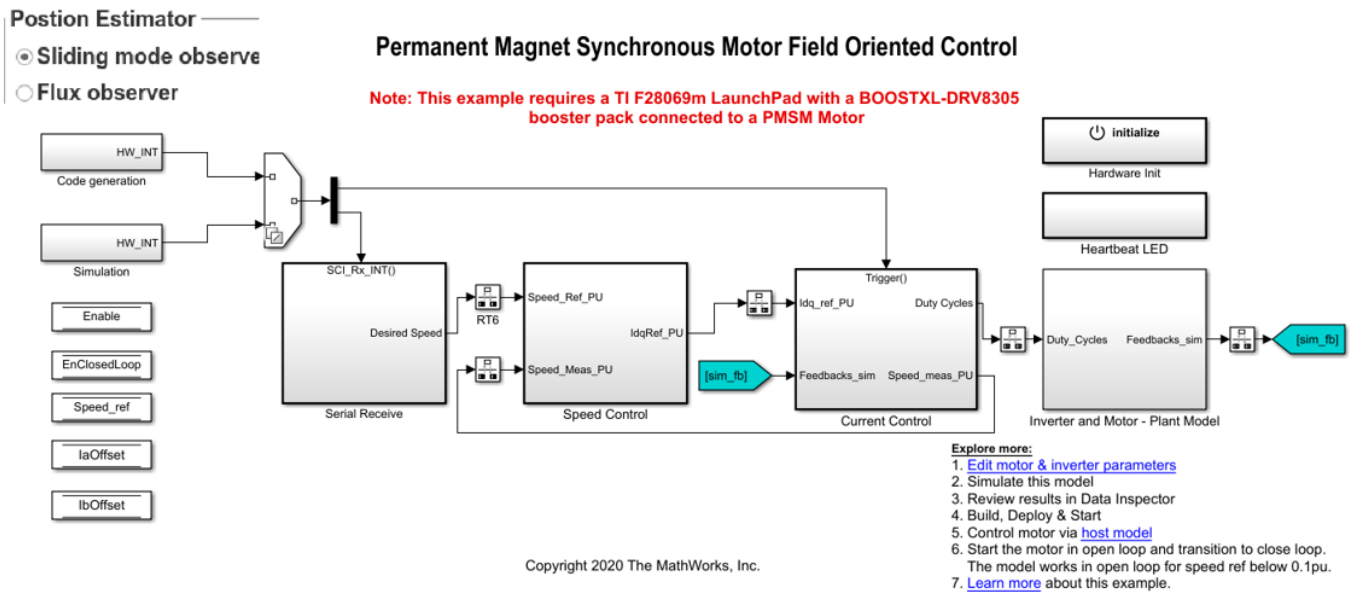
The example includes these models:

- `mcb_pmsm_foc_sensorless_f28069MLaunchPad`
- `mcb_pmsm_foc_sensorless_f28379d`

You can use these models for both simulation and code generation. You can also use the `open_system` command to open a model. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_foc_sensorless_f28069MLaunchPad.slx');
```

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



For the model names that you can use for different hardware configurations, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

1. For the model: **mcb_pmsm_foc_sensorless_f28069MLaunchPad**

- Motor Control Blockset™
- Fixed-Point Designer™

2. For the model: **mcb_pmsm_foc_sensorless_f28379d**

- Motor Control Blockset™

To generate code and deploy model:

1. For the model: **mcb_pmsm_foc_sensorless_f28069MLaunchPad**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the model: **mcb_pmsm_foc_sensorless_f28379d**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Sliding Mode Observer parameters require tuning if you are using Sliding Mode Observer with the motor parameters estimated using the parameter estimation tool.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

- 1.** Open a model included with this example.
- 2.** To simulate the model, click **Run** on the **Simulation** tab.
- 3.** To view and analyze the simulation results, click **Data Inspector** on the **Simulation** tab.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
mcb_pmsm_foc_sensorless_f28069MLaunchPad
- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter:
mcb_pmsm_foc_sensorless_f28379d

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

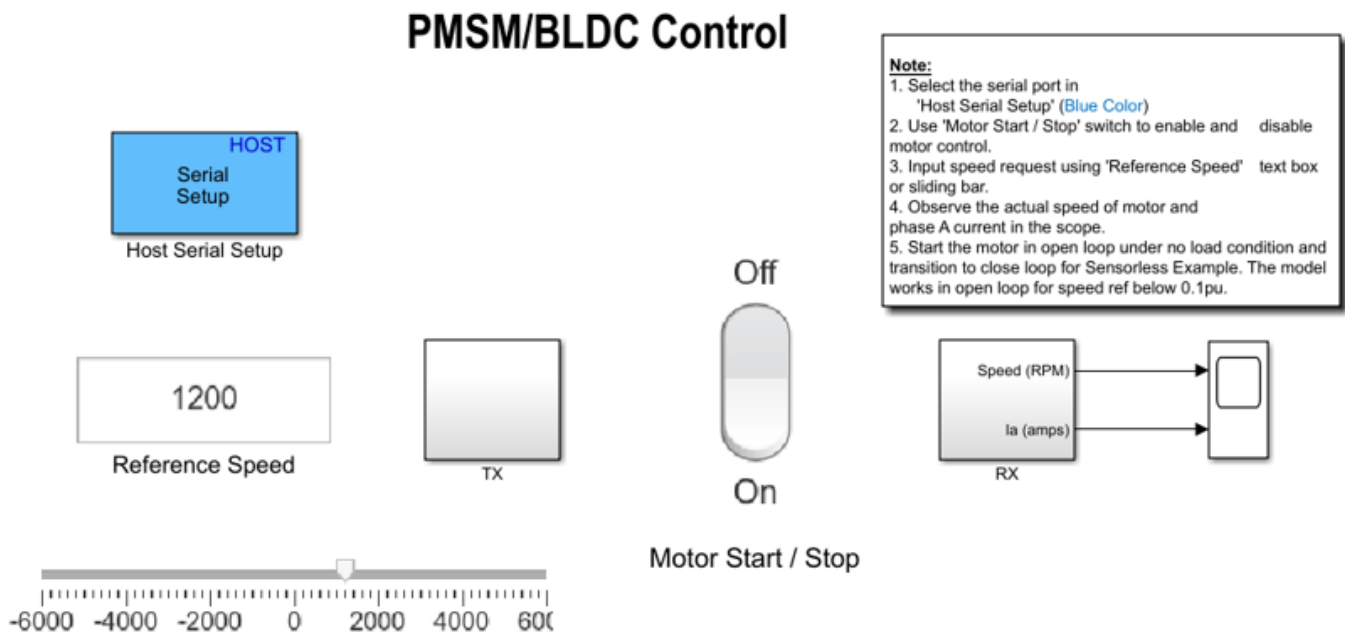
Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the Analog-to-Digital Converter (ADC) or current offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.
5. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
7. In the target model, click the **host model** hyperlink to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_host_model_f28069m.slx');
```



For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

8. In the Host Serial Setup block mask of the host model, select a **Port name**.

9. Update the Reference Speed value in the host model.

NOTE:

- Before you run the motor at the required Reference Speed (by using either Sliding Mode Observer or Flux Observer), start running the motor at $0.1 \times \text{pmsm.N_base}$ speed by using open-loop control. Then transition to closed-loop control by increasing the speed to $0.25 \times \text{pmsm.N_base}$ (where, `pmsm.N_base` is the MATLAB workspace variable for base speed of the motor).
- High acceleration and deceleration may affect the sensorless position computation.

10. Click **Run** on the **Simulation** tab to run the host model.

11. Change the position of the Start / Stop Motor switch to On, to start running the motor in the open-loop condition (by default, the motor spins at 10% of base speed).

NOTE: Do not run the motor (using this example) in the open-loop condition for a long time duration. The motor may draw high currents and produce excessive heat.

We designed the open-loop control to run the motor with a Reference Speed that is less than or equal to 10% of base speed.

When you run this example on the hardware at a low Reference Speed, due to a known issue, the PMSM may not follow the low Reference Speed.

12. Increase the motor Reference Speed beyond 10% of base speed to switch from open-loop to closed-loop control.

NOTE: To change the motor's direction of rotation, reduce the motor Reference Speed to a value less than 10% of the base speed. This brings the motor back to open-loop condition. Change the direction of rotation but keep the Reference Speed magnitude as constant. Then transition to the closed-loop condition.

13. Observe the debug signals from the RX subsystem, in the Time Scope of host model.

NOTE:

- A high reference speed and a high reference torque can affect the Sliding Mode Observer block performance.
- If you are using a F28379D based controller, you can also select the debug signals that you want to monitor.

Other Things to Try

You can use SoC Blockset™ to implement a sensorless closed-loop motor control application that addresses challenges related to ADC-PWM synchronization, controller response, and studying different PWM settings. For details, see “Integrate MCU Scheduling and Peripherals in Motor Control Application” on page 4-132.

You can also use SoC Blockset™ to develop a sensorless real-time motor control application that utilizes multiple processor cores to obtain design modularity, improved controller performance, and

other design goals. For details, see “Partition Motor Control for Multiprocessor MCUs” on page 4-141.

Field-Oriented Control of PMSM Using SI Units

This example implements the Field-Oriented Control (FOC) technique to control the speed of a three-phase Permanent Magnet Synchronous Motor (PMSM). However, instead of the per-unit representation of quantities (for details about the per-unit system, see “Per-Unit System” on page 6-16), the FOC algorithm in this example uses the SI units of signals to perform the computations. These are the signals and their SI units:

- Rotor speed - Radians/ sec
- Rotor position - Radians
- Currents - Amperes
- Voltages - Volts

Field-oriented control (FOC) needs a real time feedback of the rotor position. This example uses the quadrature encoder sensor to measure the rotor position. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

Models

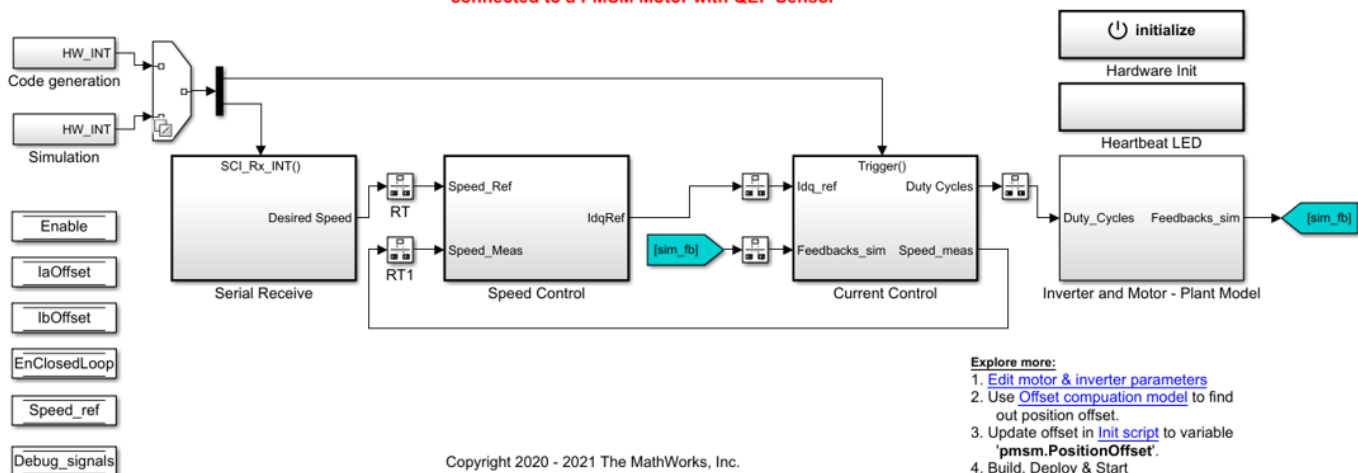
The example includes the model `mcb_pmsm_foc_qep_f28379d_SIUnit`.

You can use this model for both simulation and code generation. You can also use the `open_system` command to open the Simulink® model. For example, use this command for a F28379D based controller:

```
open_system('mcb_pmsm_foc_qep_f28379d_SIUnit.slx');
```

Permanent Magnet Synchronous Motor Field Oriented Control in SI units

Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack or BOOSTXL-3PhGaNInv connected to a PMSM Motor with QEP Sensor



Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target model and run the motor in a closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter:
mcb_pmsm_foc_qep_f28379d_SIUnit

For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

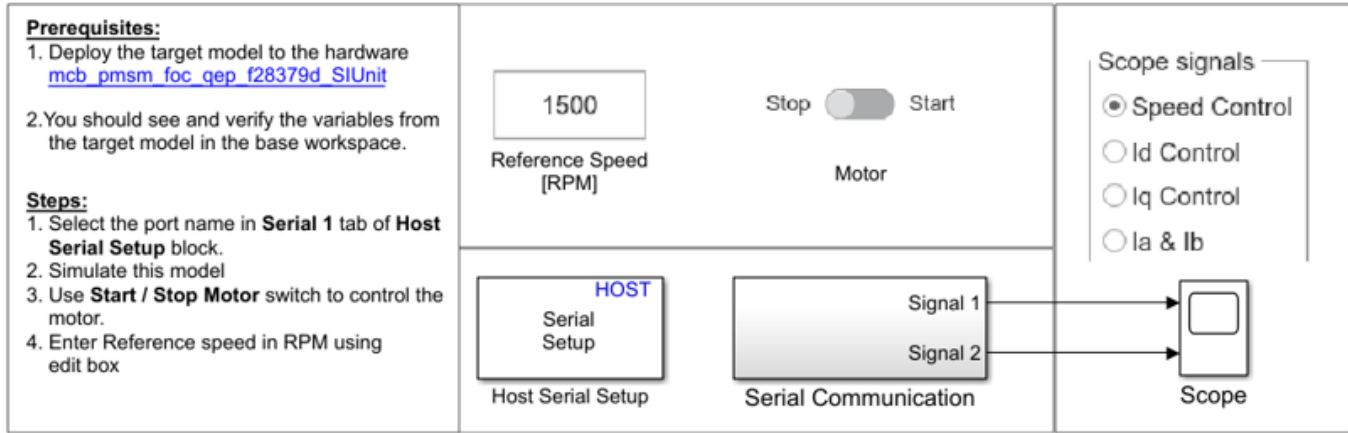
1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.
5. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.
6. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_SIUnit_host_model.slx');
```

FOC Host for SI Unit Example



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. In the Host Serial Setup block mask of the host model, select a **Port name**.
10. Update the Reference Speed value in the host model.
11. Click **Run** on the **Simulation** tab to run the host model.
12. Change the position of the Start / Stop Motor switch to On, to start running the motor.
13. Observe the debug signals from the RX subsystem, in the Time Scope of host model.

Hall Offset Calibration for PMSM Motor

This example calculates the offset between the rotor direct axis (d-axis) and position detected by the Hall sensor. The field-oriented control (FOC) algorithm needs this position offset to run the permanent magnet synchronous motor (PMSM) correctly. To compute the offset, the target model runs the motor in the open-loop condition. The model uses a constant V_d (voltage along the stator's d-axis) and a zero V_q (voltage along the stator's q-axis) to run the motor (at a low constant speed) by using a position or ramp generator. When the position or ramp value reaches zero, the corresponding rotor position is the offset value for the Hall sensors.

The control algorithm (available in the field-oriented control and parameter estimation examples) uses this offset value to compute an accurate position of d-axis of the rotor. The controller needs this offset to optimally run the PMSM.

Models

This example includes these models:

- `mcb_pmsm_hall_offset_f28069m`
- `mcb_pmsm_hall_offset_f28379d`

You can use these models only for code generation. You can also use the `open_system` command to open the Simulink® models. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_hall_offset_f28069m.slx');
```

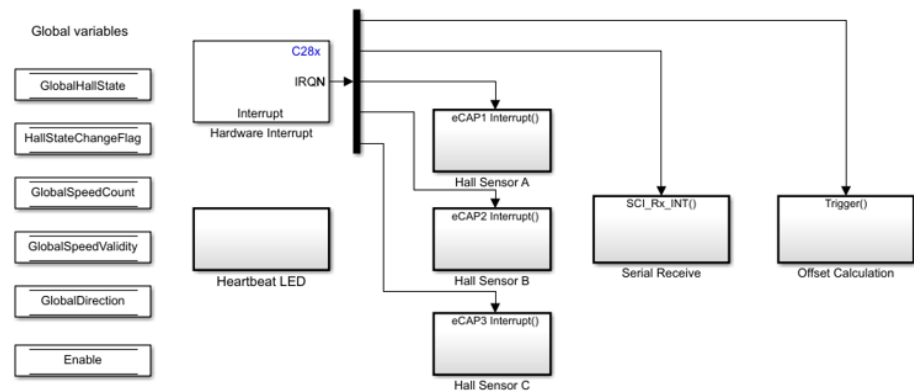
Offset Computation with Hall sensor

Note: This example requires a TI F28069m controller card mounted on DRV8312 inverter connected to a PMSM Motor with Hall Sensor

Steps:

1. Enter parameters in the Configuration panel.
2. Click **Build, Deploy & Start** in the **Hardware** tab.
3. Perform calibration by using [host model](#).
4. If the motor does not start or rotate smoothly, increase **Vd Ref in Per Unit voltage** (that can have a maximum value of 1) in the Configuration panel.
5. If the current drawn by the connected motor is too high, reduce the value mentioned in step 4.
6. [Learn more](#) about this example.

Configuration	
Number of Pole Pairs	<input type="text" value="4"/>
PWM Frequency [Hz]	<input type="text" value="20000"/>
Data type for control algorithm	<input type="text" value="single"/>
Vd Ref in Per Unit voltage	<input type="text" value="0.15"/>



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For the model names that you can use for different hardware configurations, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To generate code and deploy model:

1. For the model: **mcb_pmsm_hall_offset_f28069m**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the model: **mcb_pmsm_hall_offset_f28379d**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the motor by using open-loop control.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board.

The host model uses serial communication to command the target model and run the motor in an open-loop configuration. You can use the host model to control the motor rotations and validate direction of rotation of the motor. The **Incorrect motor direction** LED in the host model turns red to indicate that the motor is running in the opposite direction. When the LED turns red, you must reverse the motor phase connections to change the direction of rotation. The host model displays the calculated offset value.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- F28069M controller card + DRV8312-69M-KIT inverter: `mcb_pmsm_hall_offset_f28069m`

For connections related to the preceding hardware configuration, see “F28069 control card configuration” on page 7-2.

- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter: `mcb_pmsm_hall_offset_f28379d`

To configure the model **mcb_pmsm_hall_offset_f28379d**, set the **Inverter Enable Logic** field (in the **Configuration** panel of target model) to:

- **Active High:** To use the model with BOOSTXL-DRV8305 inverter.
- **Active Low:** To use the model with BOOSTXL-3PHGANINV inverter.

For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Complete the hardware connections.

2. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.

3. Update the motor parameters in the **Configuration** panel of the target model.

- **Number of Pole Pairs**
- **PWM Frequency [Hz]**
- **Data type for control algorithm**
- **Vd Ref in Per Unit voltage**

4. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

5. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

6. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_host_offsetComputation_f28069m.slx');
```

PMSM Position Sensor (Hall / QEP) Offset Calibration Host

<p>Prerequisites:</p> <ol style="list-style-type: none"> 1. Deploy the target model to the hardware mcb_pmsm_hall_offset_f28069m mcb_pmsm_qep_offset_f28069m mcb_pmsm_qep_offset_f28069mLaunchPad 2. You should see and verify the variables from the target model in the base workspace. <p>Steps:</p> <ol style="list-style-type: none"> 1. Select the port name in Serial 1 tab of Host Serial Setup block. 2. Simulate this model to start calibration. Motor starts running when calibration begins 3. After calibration completes, simulation ends and motor stops automatically. 4. Push the Emergency Motor Stop button to stop the motor during emergency. 	<table style="width: 100%; border-collapse: collapse;"> <tr> <td style="width: 50%; border-right: 1px solid black; padding: 5px;"> <p>Calibration Output</p> <div style="border: 1px solid gray; width: 100px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div> <p style="text-align: center; font-size: small;">Position Sensor Offset [Per-unit position]</p> </td> <td style="width: 50%; padding: 5px;"> <p>Calibration Status</p> <div style="border: 1px solid gray; width: 150px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div> </td> </tr> <tr> <td colspan="2" style="padding: 5px;"> <p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p> </td> </tr> <tr> <td style="border-right: 1px solid black; padding: 5px; vertical-align: top;"> <p style="text-align: center;">Communication Port</p> <div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">HOST Serial Setup</div> <p style="font-size: x-small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">Position_PU Serial Communication</div> </div> </td> <td style="padding: 5px; vertical-align: top;"> <div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 150px; margin: 0 auto; border-radius: 5px;">Emergency Motor Stop</div> <p style="font-size: small; margin: 0;">Push for emergency stop</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 40px; height: 40px; margin: 0 auto; display: flex; align-items: center; justify-content: center;"> <div style="width: 10px; height: 10px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 20px; height: 20px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 10px; height: 10px; border: 1px solid gray;"></div> </div> <p style="font-size: x-small; margin: 0;">Scope</p> </div> </td> </tr> </table>	<p>Calibration Output</p> <div style="border: 1px solid gray; width: 100px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div> <p style="text-align: center; font-size: small;">Position Sensor Offset [Per-unit position]</p>	<p>Calibration Status</p> <div style="border: 1px solid gray; width: 150px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div>	<p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p>		<p style="text-align: center;">Communication Port</p> <div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">HOST Serial Setup</div> <p style="font-size: x-small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">Position_PU Serial Communication</div> </div>	<div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 150px; margin: 0 auto; border-radius: 5px;">Emergency Motor Stop</div> <p style="font-size: small; margin: 0;">Push for emergency stop</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 40px; height: 40px; margin: 0 auto; display: flex; align-items: center; justify-content: center;"> <div style="width: 10px; height: 10px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 20px; height: 20px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 10px; height: 10px; border: 1px solid gray;"></div> </div> <p style="font-size: x-small; margin: 0;">Scope</p> </div>
<p>Calibration Output</p> <div style="border: 1px solid gray; width: 100px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div> <p style="text-align: center; font-size: small;">Position Sensor Offset [Per-unit position]</p>	<p>Calibration Status</p> <div style="border: 1px solid gray; width: 150px; height: 30px; margin: 5px auto; text-align: center; background-color: #f0f0f0;">--</div>						
<p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p>							
<p style="text-align: center;">Communication Port</p> <div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">HOST Serial Setup</div> <p style="font-size: x-small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 100px; margin: 0 auto;">Position_PU Serial Communication</div> </div>	<div style="text-align: center; margin-bottom: 10px;"> <div style="border: 1px solid gray; padding: 5px; width: 150px; margin: 0 auto; border-radius: 5px;">Emergency Motor Stop</div> <p style="font-size: small; margin: 0;">Push for emergency stop</p> </div> <div style="text-align: center;"> <div style="border: 1px solid gray; padding: 5px; width: 40px; height: 40px; margin: 0 auto; display: flex; align-items: center; justify-content: center;"> <div style="width: 10px; height: 10px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 20px; height: 20px; border: 1px solid gray; margin-right: 5px;"></div> <div style="width: 10px; height: 10px; border: 1px solid gray;"></div> </div> <p style="font-size: x-small; margin: 0;">Scope</p> </div>						

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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

You can use the Scope in the host model to monitor the rotor position and offset values.

7. In the Host Serial Setup block mask of the host model, select a **Port name**.

8. Click **Run** on the **Simulation** tab to run the host model. The motor runs and calibration begins when you start simulation. After the calibration process is complete, simulation ends and the motor stops automatically.

9. See the **Calibration Status** section to know the status of the calibration process:

- The **Calibration in progress** LED turns orange when the motor starts running. Notice the rotor position and the variation in the offset value in the Scope (the position signal indicates a ramp signal with an amplitude between 0 and 1). After the calibration process is complete, the LED turns grey.
- The **Calibration complete** LED turns green when the calibration process is complete. Then the **Calibration Output** field displays the computed offset value.
- The **Incorrect motor direction** LED turns red if the motor runs in the opposite direction. Then the **Calibration Output** field displays the value "NaN." Turn off the DC power supply (24V) and reverse the motor phase connections from ABC to CBA. Repeat steps 5 to 8 and check if the **Calibration complete** LED is green. Verify that the **Calibration Output** field displays the offset value.

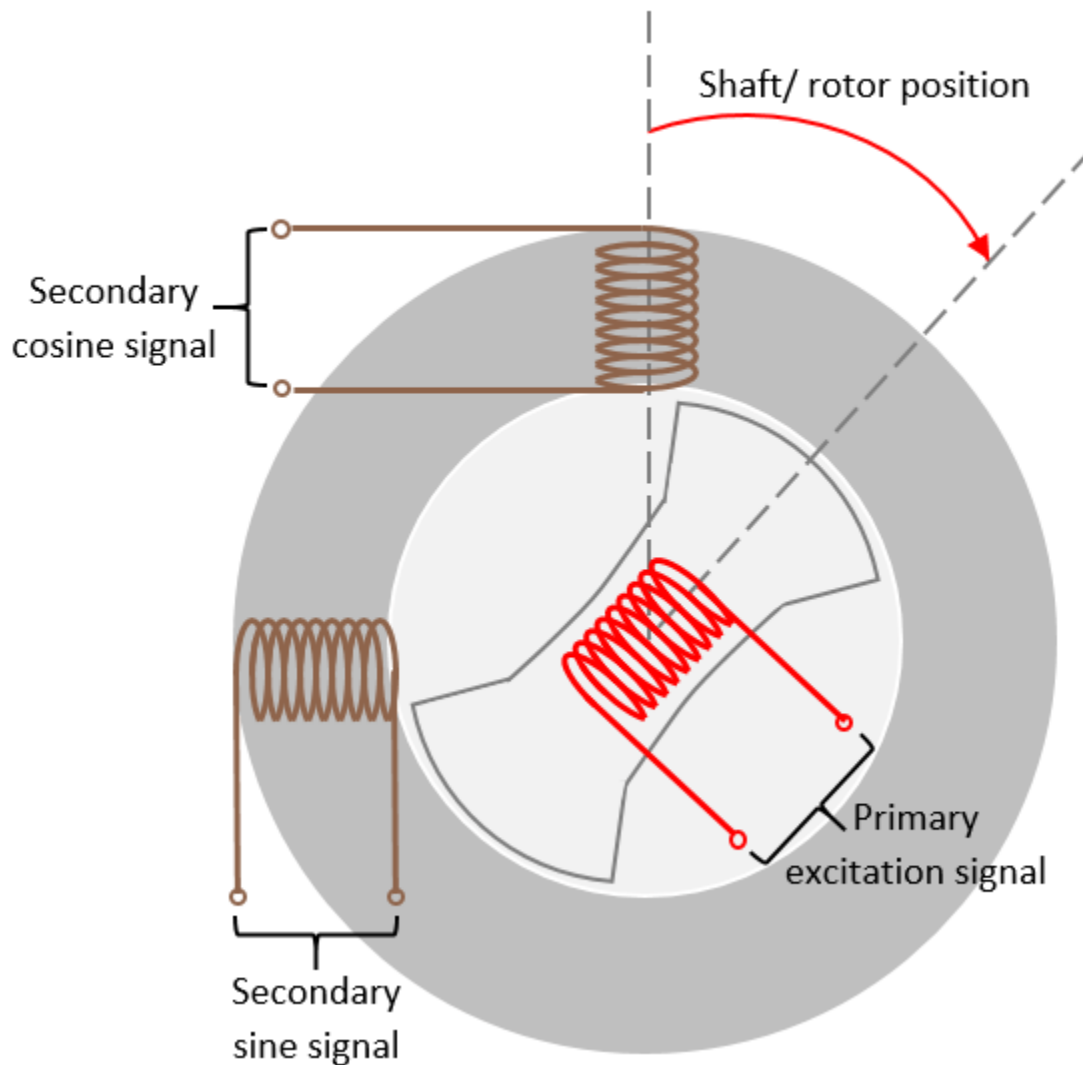
Note: To immediately stop the motor, click the **Emergency Motor Stop** button.

This example does not support simulation. The example automatically saves the computed offset value in the **PositionOffset** variable available in the base workspace.

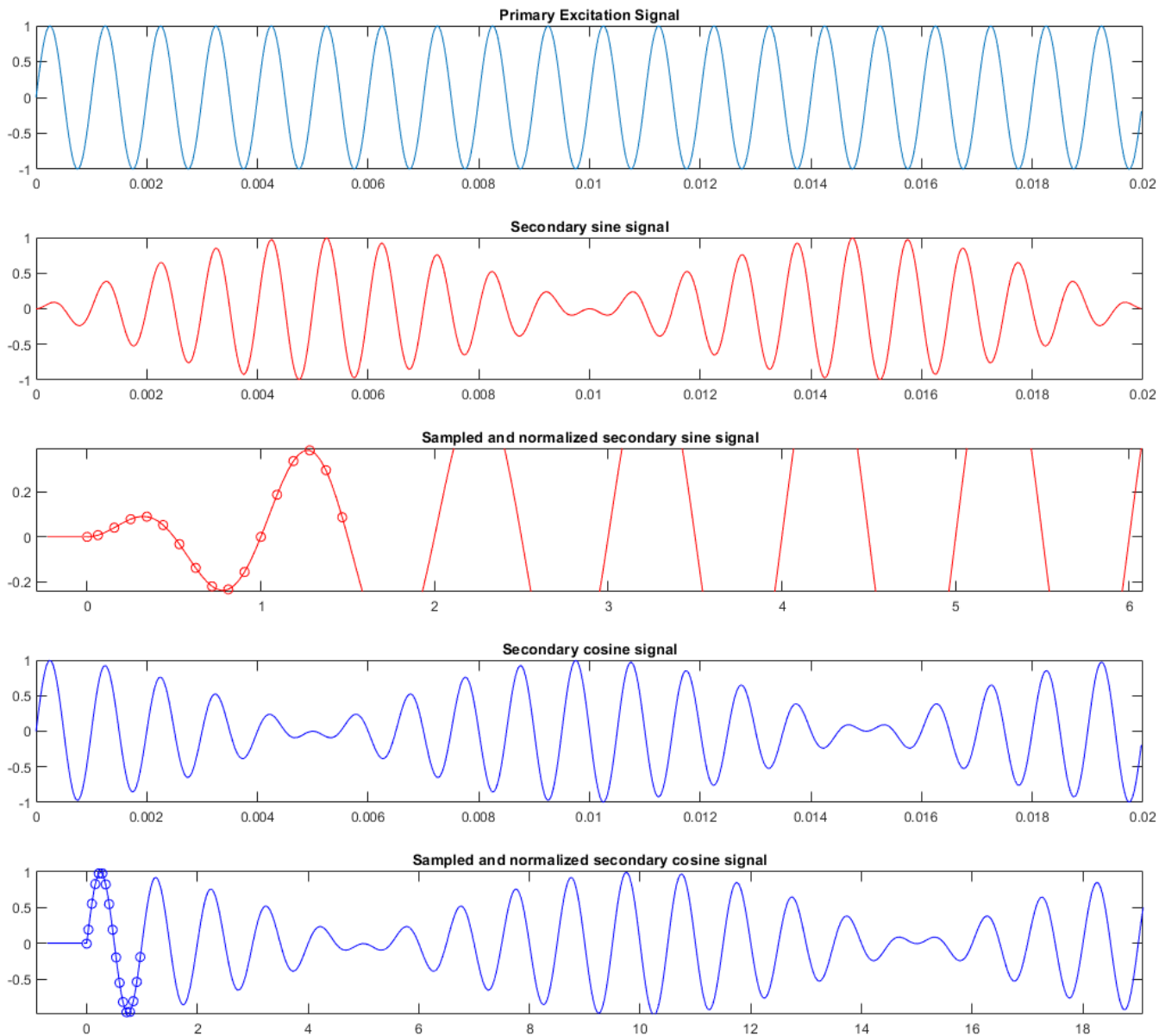
For examples that implement FOC using a Hall sensor, update the computed offset in the **pmsm.PositionOffset** parameter in the model initialization script linked to the example. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

Monitor Resolver Using Serial Communication

This example operates the resolver sensor to measure the rotor position. The resolver consists of two orthogonally placed stator windings placed around the resolver rotor winding. After you mount the resolver sensor over a PMSM, the resolver rotor winding rotates along with the shaft of the running motor. The controller provides a fixed frequency alternating excitation signal to the resolver rotor winding. When the resolver rotor rotates, the resolver stator windings produce output (secondary sine and cosine) signals that are modulated with the sine and cosine of the shaft angle or position. After receiving the secondary signals, the controller samples and normalizes them.



4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



Models

The example includes the model `mcb_resolver_f28069m`.

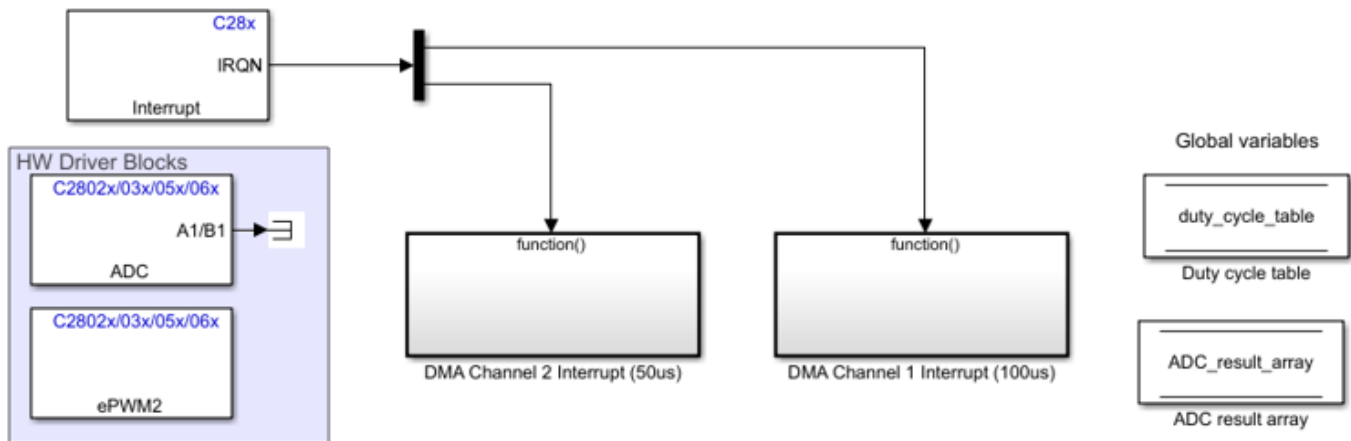
You can use this model only for code generation. You can also use the `open_system` command to open the Simulink® model. For example, use this command for a F28069M based controller:

```
open_system('mcb_resolver_f28069m.slx');
```

Rotor position measurement using Resolver

Note: This example requires a TI F28069m Launchpad Connected to C2000 resolver to digital conversion Kit (TMDSRSLVR) with Resolver

Explore More:
[Learn more](#) about this example



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Required MathWorks® Products

For the model: **mcb_resolver_f28069m**

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

Prerequisite

We provide default inverter parameters with the target model. If you want to change the default values, you can update the inverter parameters in the model initialization script associated with the Simulink® model. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The controller in the target model uses the Resolver Decoder block to process the sampled and normalized secondary sine and cosine signals to obtain the shaft (or motor) position. The host model uses serial communication to command the target model and obtain the computed shaft angle from the controller. You can observe the computed shaft position in the Time Scope block of the host model.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter: `mcb_resolver_f28069m`

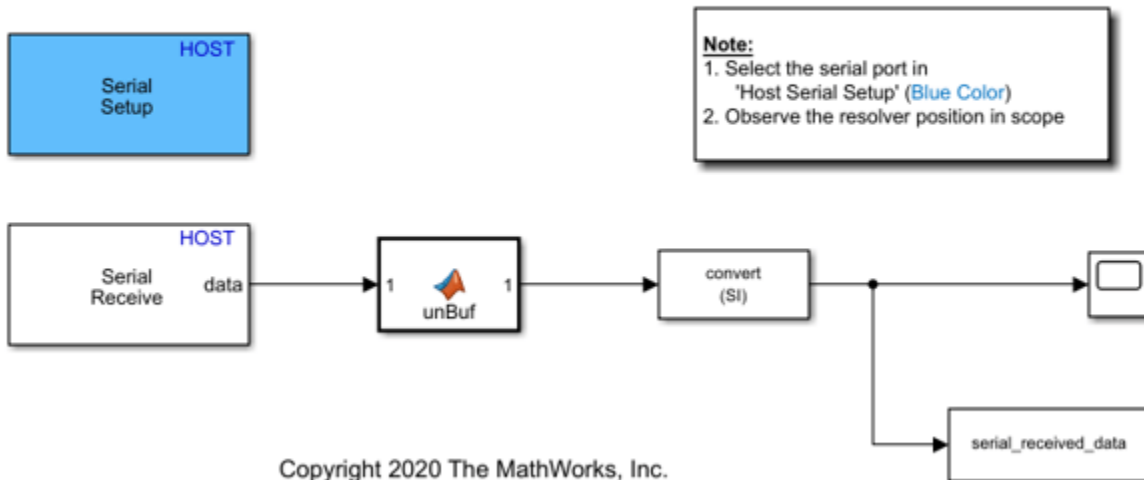
For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

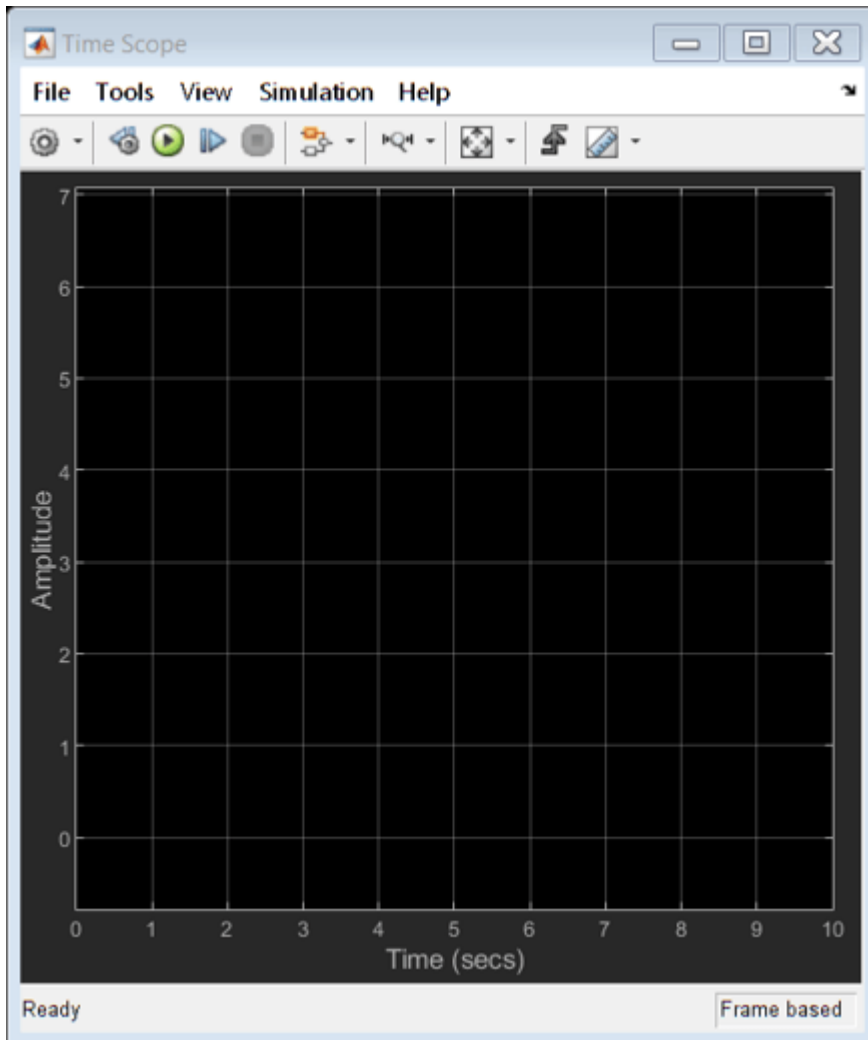
Generate Code and Run Model on Target Hardware

1. Complete the hardware connections and open the target model `mcb_resolver_f28069m`.
2. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
3. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
4. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for the F28069M based controller:

```
open_system('mcb_resolver_host_read.slx');
```

Resolver Host





For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

5. In the Serial Receive and Serial Configuration block masks of the host model, select a Communication port value.
6. If you want to change the default baud rate (in the host and target models), use the Serial Configuration block mask in the models to select a different Baud rate value.
7. Click **Run** on the **Simulation** tab to run the host model.
8. Open the Time Scope block in the host model.
9. Rotate the resolver shaft and observe the computed shaft position signal in the Time Scope block.

Quadrature Encoder Offset Calibration for PMSM Motor

This example calculates the offset between the d-axis of the rotor and encoder index pulse position as detected by the quadrature encoder sensor. The control algorithm (available in the field-oriented control and parameter estimation examples) uses this offset value to compute an accurate and precise position of the d-axis of rotor. The controller needs this position to implement the field-oriented control (FOC) correctly in the rotor flux reference frame (d-q reference frame), and therefore, run the permanent magnet synchronous motor (PMSM) correctly.

Models

The example includes these models:

- `mcb_pmsm_qep_offset_f28069m`
- `mcb_pmsm_qep_offset_f28069mLaunchPad`
- `mcb_pmsm_qep_offset_f28379d`

You can use these models only for code generation. You can also use the `open_system` command to open the Simulink® models. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_qep_offset_f28069m.slx');
```

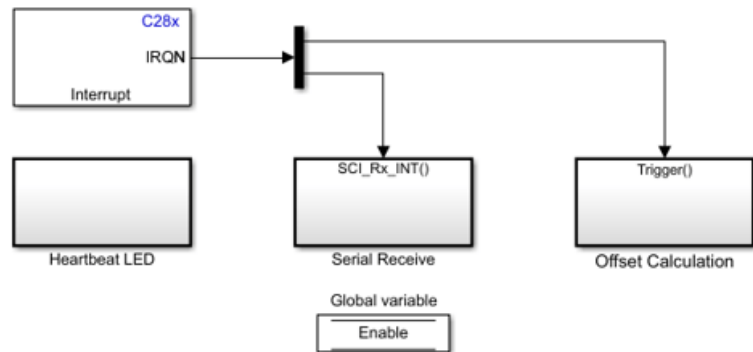
Offset Computation for QEP

Steps:

1. Enter parameters in the Configuration panel.
2. Click **Build, Deploy & Start** in the **Hardware** tab.
3. Perform calibration by using [host model](#).
4. If the motor does not start or rotate smoothly, increase **Vd Ref in Per Unit voltage** (that can have a maximum value of 1) in the Configuration panel.
5. If the current drawn by the connected motor is too high, reduce the value mentioned in step 4.
6. [Learn more](#) about this example.

Configuration	
Number of Pole Pairs:	<input type="text" value="4"/>
QEP Slits	<input type="text" value="1250"/>
PWM Frequency [Hz]	<input type="text" value="20000"/>
Data type for control algorithm	<input type="text" value="single"/>
Vd Ref in Per Unit voltage	<input type="text" value="0.15"/>

Note: This example requires a TI F28069m controller card mounted on DRV8312 inverter connected to a PMSM Motor with QEP Sensor



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For the model names that you can use for different hardware configurations, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To generate code and deploy model:

1. For the models: `mcb_pmsm_qep_offset_f28069m` and `mcb_pmsm_qep_offset_f28069mLaunchPad`

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™

2. For the model: `mcb_pmsm_qep_offset_f28379d`

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the motor by using open-loop control.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board.

The host model uses serial communication to command the target model and run the motor in an open-loop configuration. You can use the host model to control the motor rotations and validate the direction of rotation of motor. The **Incorrect motor direction** LED in the host model turns red to indicate that the motor is running in the opposite direction. When the LED turns red, you must reverse the motor phase connections (from ABC to CBA) to change the direction of rotation. The host model displays the calculated offset value.

Required Hardware

This example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- F28069M controller card + DRV8312-69M-KIT inverter: `mcb_pmsm_qep_offset_f28069m`

For connections related to the preceding hardware configuration, see “F28069 control card configuration” on page 7-2.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
`mcb_pmsm_qep_offset_f28069mLaunchPad`
- LAUNCHXL-F28379D controller + (BOOSTXL-3PHGANINV or BOOSTXL-DRV8305) inverter:
`mcb_pmsm_qep_offset_f28379d`

To configure the model `mcb_pmsm_qep_offset_f28379d`, set the **Inverter Enable Logic** field (in the **Configuration** panel of target model) to:

- **Active High:** To use the model with BOOSTXL-DRV8305 inverter.
- **Active Low:** To use the model with BOOSTXL-3PHGANINV inverter.

NOTE: When using BOOSTXL-3PHGANINV inverter, ensure that proper insulation is available between bottom layer of BOOSTXL-3PHGANINV and the LAUNCHXL board.

For connections related to the preceding hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Complete the hardware connections.
2. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.
3. Update the motor parameters in the **Configuration** panel of the target model.
 - **Number of Pole Pairs**
 - **QEP Slits**
 - **PWM Frequency [Hz]**
 - **Data type for control algorithm**
 - **Vd Ref in Per Unit voltage**
3. Load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
4. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
5. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28069M based controller:

```
open_system('mcb_pmsm_host_offsetComputation_f28069m.slx');
```


PMSM Position Sensor (Hall / QEP) Offset Calibration Host

<p>Prerequisites:</p> <ol style="list-style-type: none"> 1. Deploy the target model to the hardware mcb_pmsm_hall_offset_f28069m mcb_pmsm_qep_offset_f28069m mcb_pmsm_qep_offset_f28069mLaunchPad 2. You should see and verify the variables from the target model in the base workspace. <p>Steps:</p> <ol style="list-style-type: none"> 1. Select the port name in Serial 1 tab of Host Serial Setup block. 2. Simulate this model to start calibration. Motor starts running when calibration begins 3. After calibration completes, simulation ends and motor stops automatically. 4. Push the Emergency Motor Stop button to stop the motor during emergency. 	<table style="width: 100%; border-collapse: collapse;"> <tr> <td style="width: 50%; border-right: 1px solid black; padding: 5px;"> <p style="text-align: center;">Calibration Output</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div> <p style="text-align: center;">Position Sensor Offset [Per-unit position]</p> </td> <td style="width: 50%; padding: 5px;"> <p style="text-align: center;">Calibration Status</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div> </td> </tr> <tr> <td colspan="2" style="padding: 5px;"> <p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p> </td> </tr> <tr> <td style="border-right: 1px solid black; padding: 5px;"> <p style="text-align: center;">Communication Port</p> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="color: blue; font-weight: bold; margin: 0;">HOST</p> <p style="margin: 0;">Serial Setup</p> <p style="font-size: small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="font-size: small; margin: 0;">Position_PU</p> <p style="font-size: small; margin: 0;">Serial Communication</p> </div> </td> <td style="padding: 5px;"> <div style="text-align: center; margin: 5px auto; width: 100px;"> <div style="border: 1px solid gray; border-radius: 10px; padding: 5px; display: inline-block; margin: 0 auto;">Emergency Motor Stop</div> <p style="margin: 5px 0 0 0;">Push for emergency stop</p> </div> <div style="text-align: center; margin: 10px auto; width: 50px;"> <p style="font-size: small; margin: 0;">Scope</p> </div> </td> </tr> </table>	<p style="text-align: center;">Calibration Output</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div> <p style="text-align: center;">Position Sensor Offset [Per-unit position]</p>	<p style="text-align: center;">Calibration Status</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div>	<p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p>		<p style="text-align: center;">Communication Port</p> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="color: blue; font-weight: bold; margin: 0;">HOST</p> <p style="margin: 0;">Serial Setup</p> <p style="font-size: small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="font-size: small; margin: 0;">Position_PU</p> <p style="font-size: small; margin: 0;">Serial Communication</p> </div>	<div style="text-align: center; margin: 5px auto; width: 100px;"> <div style="border: 1px solid gray; border-radius: 10px; padding: 5px; display: inline-block; margin: 0 auto;">Emergency Motor Stop</div> <p style="margin: 5px 0 0 0;">Push for emergency stop</p> </div> <div style="text-align: center; margin: 10px auto; width: 50px;"> <p style="font-size: small; margin: 0;">Scope</p> </div>
<p style="text-align: center;">Calibration Output</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div> <p style="text-align: center;">Position Sensor Offset [Per-unit position]</p>	<p style="text-align: center;">Calibration Status</p> <div style="text-align: center; border: 1px solid gray; width: 100px; height: 30px; margin: 0 auto 10px auto;">--</div>						
<p>Note: If motor is not rotating in correct direction, turn off the power supply to the target, interchange any two motor phase connections, and simulate the host model again. If motor is not rotating, check hardware setup.</p>							
<p style="text-align: center;">Communication Port</p> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="color: blue; font-weight: bold; margin: 0;">HOST</p> <p style="margin: 0;">Serial Setup</p> <p style="font-size: small; margin: 0;">Host Serial Setup</p> </div> <div style="text-align: center; border: 1px solid gray; padding: 5px; margin: 5px auto; width: 100px;"> <p style="font-size: small; margin: 0;">Position_PU</p> <p style="font-size: small; margin: 0;">Serial Communication</p> </div>	<div style="text-align: center; margin: 5px auto; width: 100px;"> <div style="border: 1px solid gray; border-radius: 10px; padding: 5px; display: inline-block; margin: 0 auto;">Emergency Motor Stop</div> <p style="margin: 5px 0 0 0;">Push for emergency stop</p> </div> <div style="text-align: center; margin: 10px auto; width: 50px;"> <p style="font-size: small; margin: 0;">Scope</p> </div>						

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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

You can use the Scope in the host model to monitor the rotor position and offset values.

6. In the Host Serial Setup block mask of the host model, select a **Port name**.

7. Click **Run** on the **Simulation** tab to run the host model. The motor runs and calibration begins when you start simulation. After the calibration process is complete, simulation ends and the motor stops automatically.

9. See the **Calibration Status** section to know the status of the calibration process:

- The **Calibration in progress** LED turns orange when the motor starts running. Notice the rotor position and the variation in the offset value in the Scope (the position signal indicates a ramp signal with an amplitude between 0 and 1). After the calibration process is complete, the LED turns grey.
- The **Calibration complete** LED turns green when the calibration process is complete. Then the **Calibration Output** field displays the computed offset value.
- The **Incorrect motor direction** LED turns red if the motor runs in the opposite direction. Then the **Calibration Output** field displays the value "NaN." Turn off the DC power supply (24V)

and reverse the motor phase connections from ABC to CBA. Repeat steps 5 to 8 and check if the Calibration complete LED is green. Verify that the Calibration Output field displays the offset value.

Note: To immediately stop the motor, click the **Emergency Motor Stop** button.

This example does not support simulation. The example automatically saves the computed offset value in the `PositionOffset` variable available in the base workspace.

For examples that implement FOC using a quadrature encoder sensor, update the computed quadrature encoder offset value in the `pmsm.PositionOffset` parameter in the model initialization script linked to the example. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

Model Switching Dynamics in Inverter Using Simscape Electrical

This example uses field-oriented control (FOC) to control the speed of a three-phase permanent magnet synchronous motor (PMSM). It gives you the option to use these Simscape Electrical blocks as an alternative to the Average Value Inverter block in Motor Control Blockset™:

- Converter (Three-Phase)
- Ideal Semiconductor Switch

The example also gives you the option to use the PMSM block from Simscape™ Electrical™ as an alternative to the Surface Mount PMSM block from Motor Control Blockset™. These Simscape™ Electrical™ blocks enable you to generate high-fidelity simulations.

Field-oriented control (FOC) needs a real time feedback of the rotor position. This example uses the quadrature encoder sensor to measure the rotor position. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

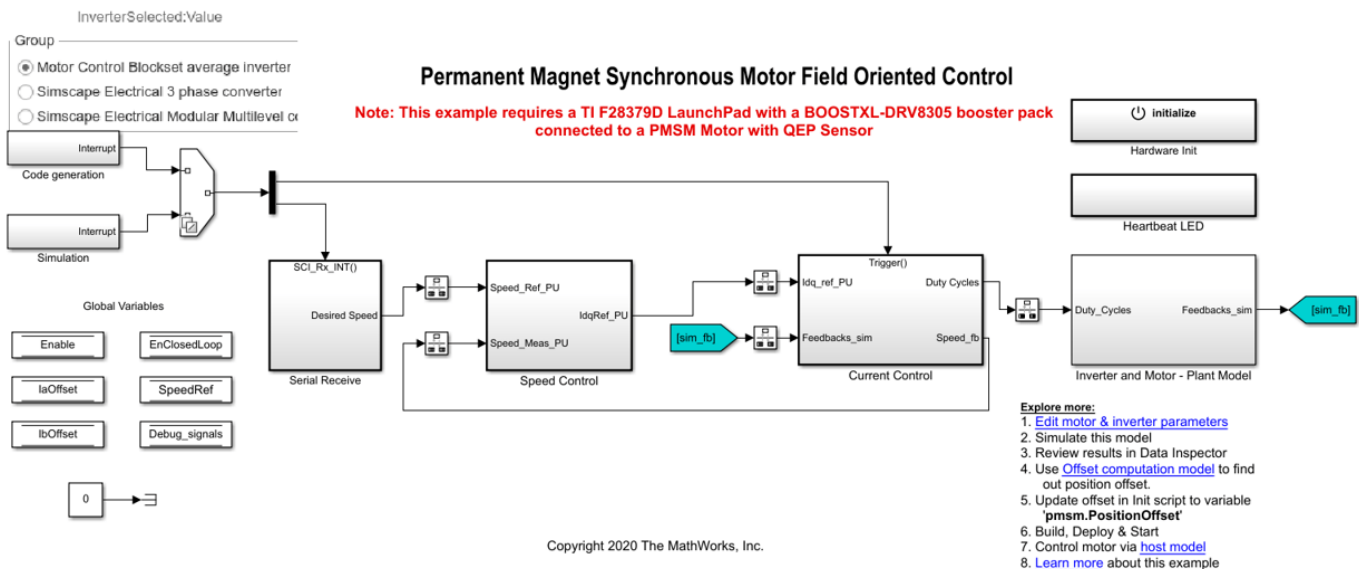
You can use this example to simulate the target model by using different inverters and monitor the feedback current for each inverter. You can also generate the code and use the host model along with the target model.

Models

The example includes the model `mcb_ee_pmsm_foc`.

You can use this model for both simulation and code generation. You can also use the `open_system` command to open the Simulink® model. For example, use this command for a F28379D based controller:

```
open_system('mcb_ee_pmsm_foc.slx');
```



Required MathWorks® Products

To simulate model:

- Motor Control Blockset™
- Simscape™ Electrical™

To generate code and deploy model:

- Motor Control Blockset™
- Simscape™ Electrical™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated *motorParam* workspace variable.

Simulate Model

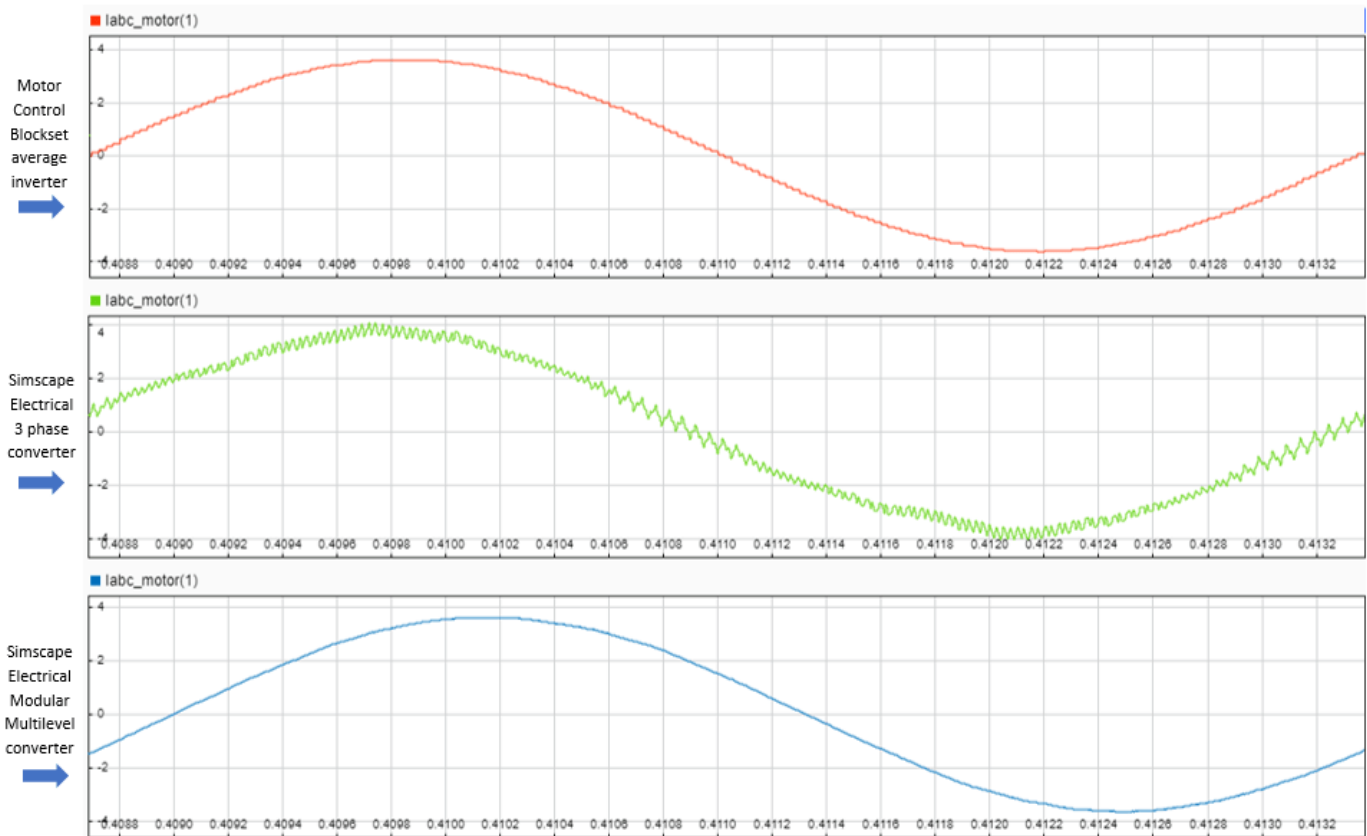
This example supports simulation. Follow these steps to simulate the model.

1. Open the target model **mcb_ee_pmsm_foc**.
2. Select one of these options in the InverterSelected radio group in the target model to simulate an inverter variant:
 - **Motor Control Blockset average inverter** - Select this option to use the Average Inverter and Surface Mount PMSM blocks.
 - **Simscape Electrical 3 phase converter** - Select this option to use the Converter (Three-Phase) and PMSM blocks.
 - **Simscape Electrical Modular Multilevel converter** - Select this option to use the Ideal Semiconductor Switch and PMSM blocks. This option simulates the Simscape Electrical modular multilevel converter using a low voltage.

3. Select an option from the InverterSelected radio group and click **Run** on the **Simulation** tab to simulate the target model.

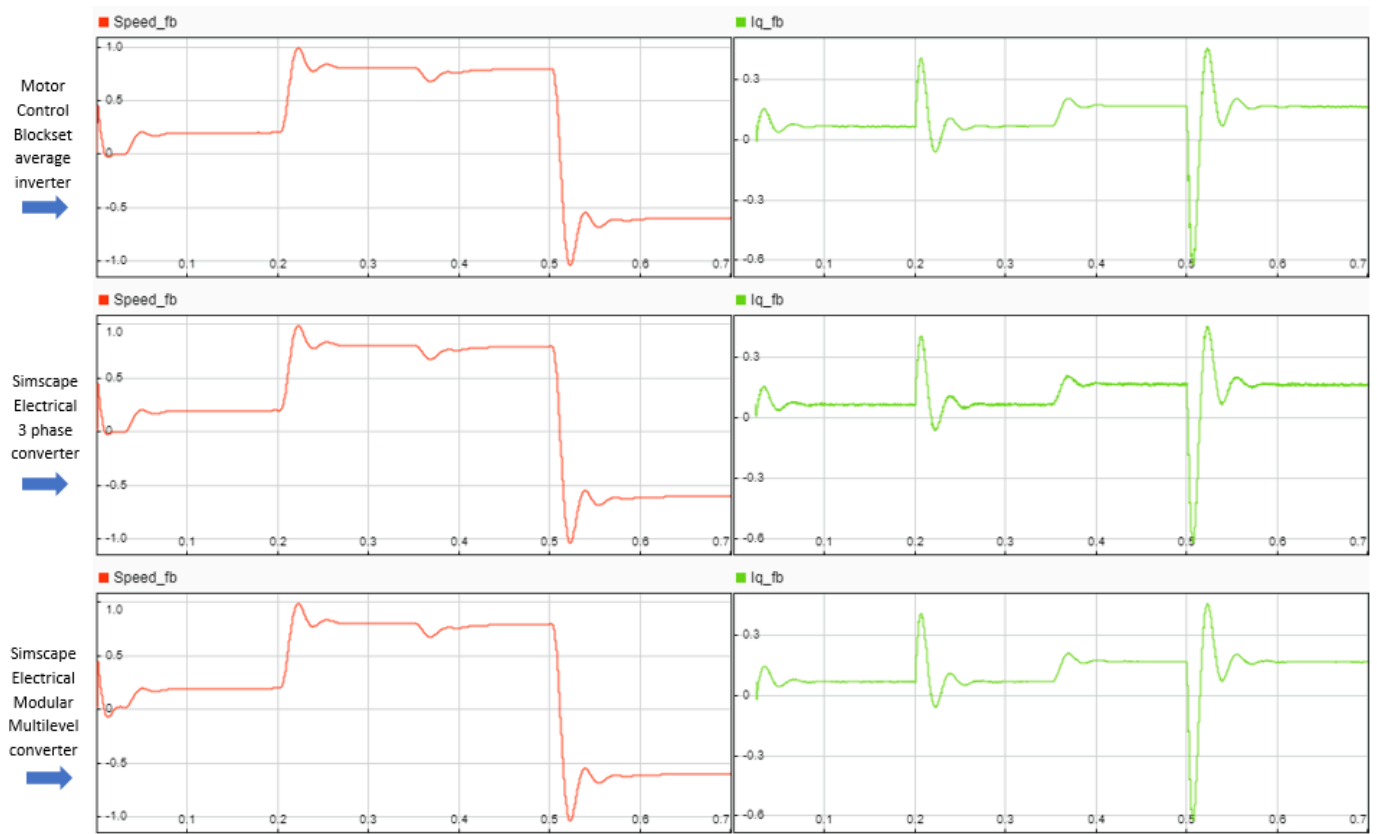
4. On the target model, click **Data Inspector** on the **Simulation** tab to view results from the three simulation runs.

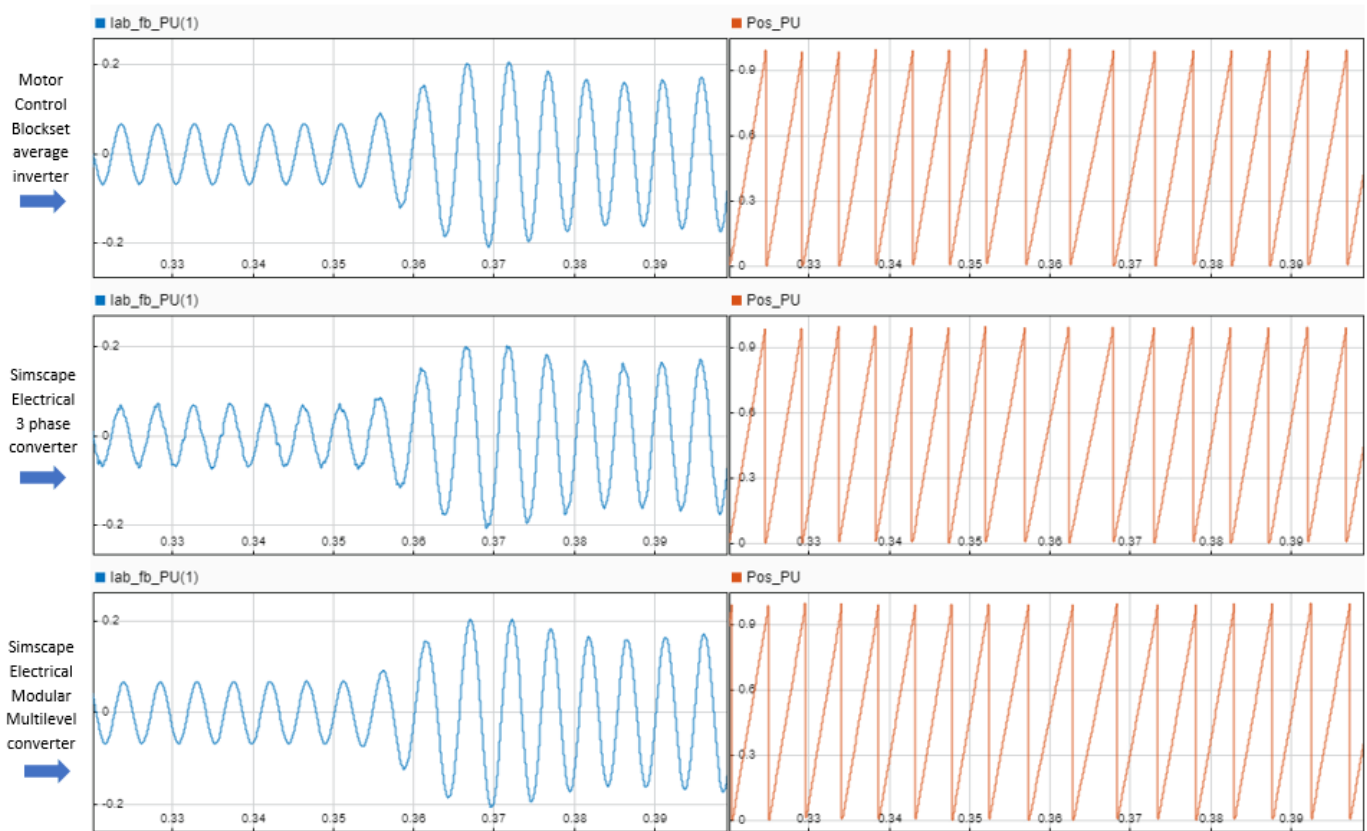
This image shows the simulation results for I_a phase current:



These images show the comparison of rotor speed, I_q current, I_{ab} phase current, and rotor position for the three inverter types:

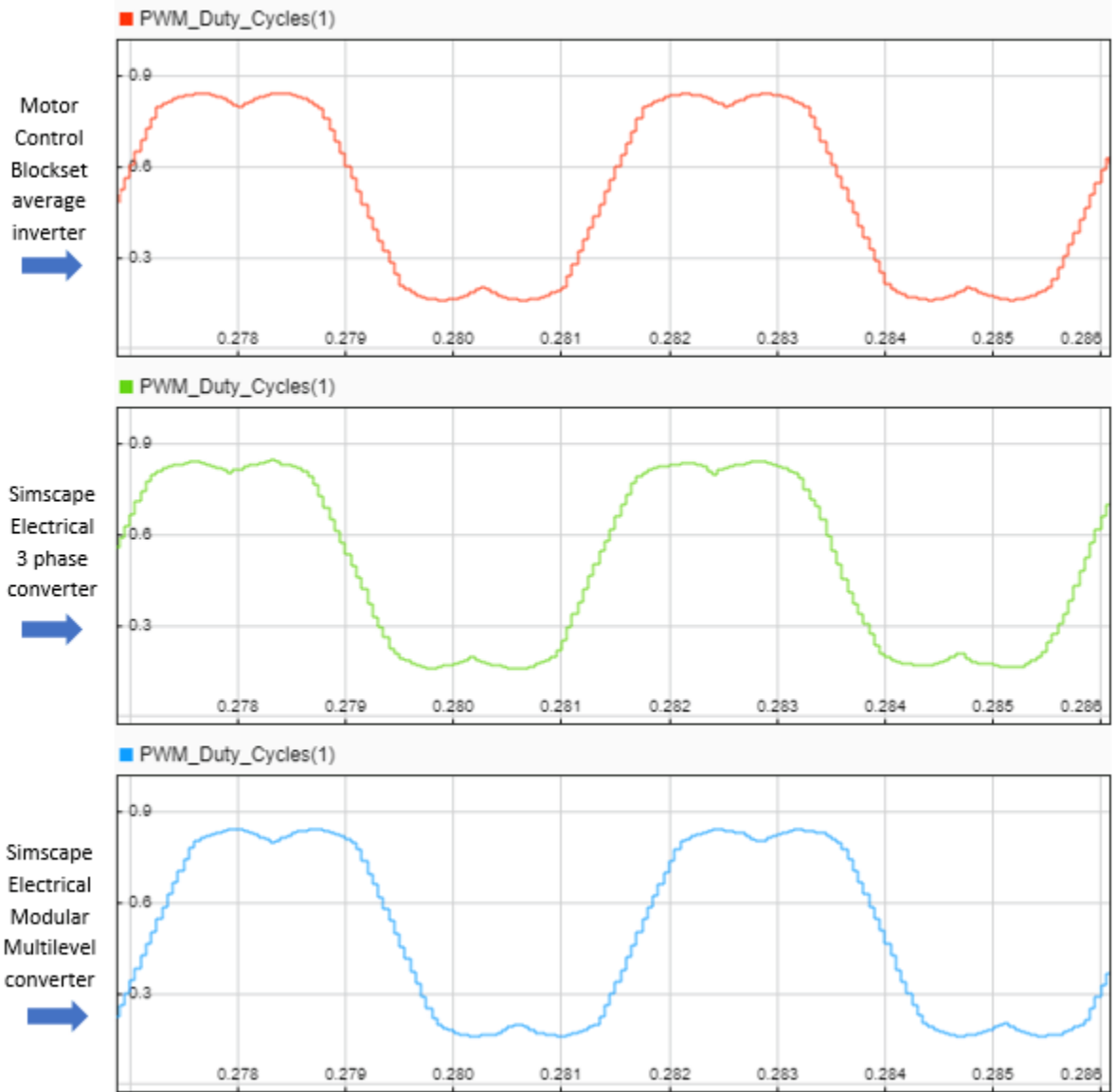
4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)

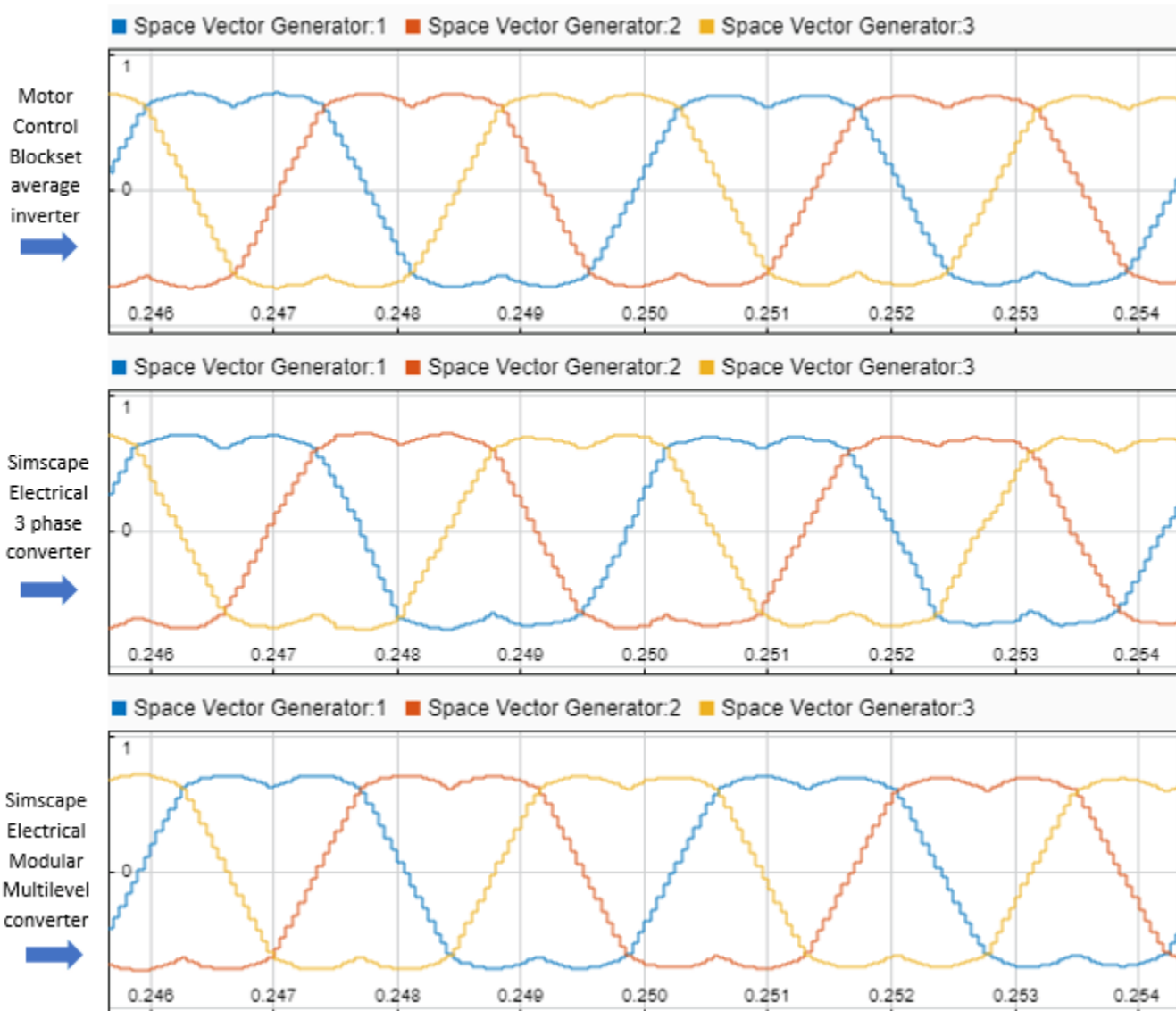




These images show the comparison of PWM modulation waveforms for the three inverter types:

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)





Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: `mcb_ee_pmsm_foc`

For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

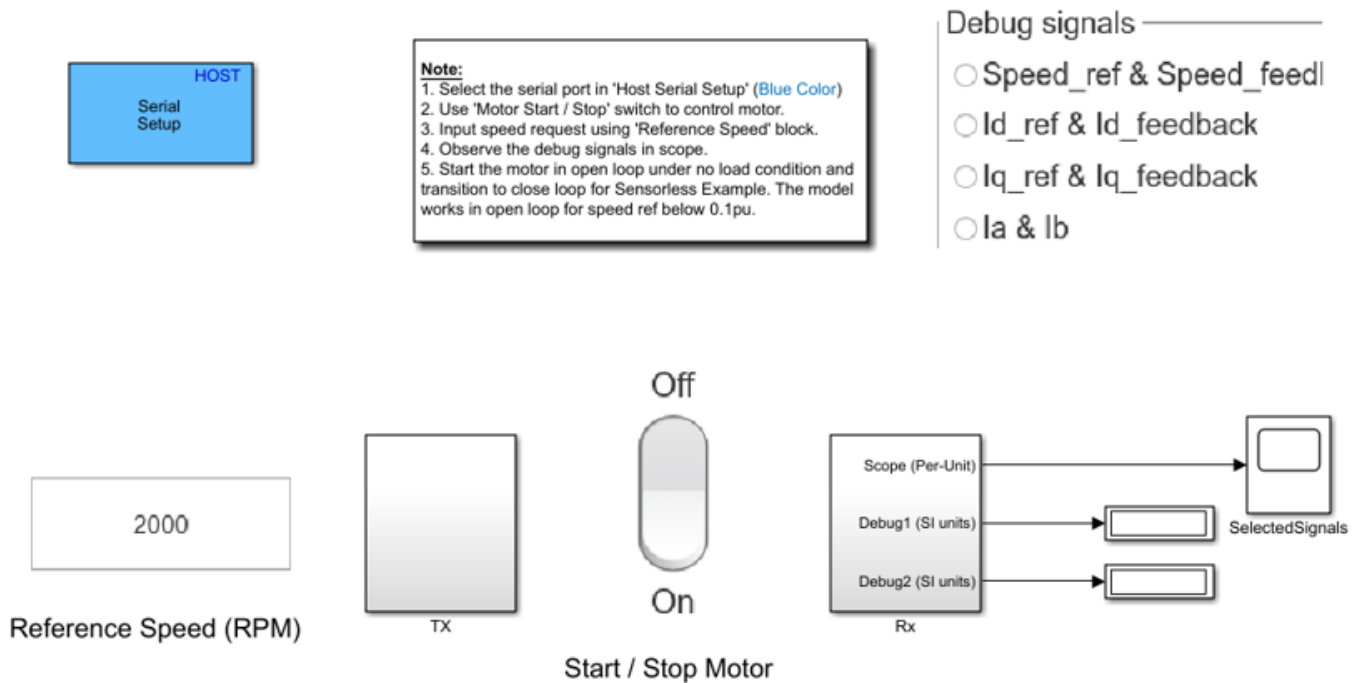
1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.
5. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.
6. To ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1, load a sample program to CPU2 of LAUNCHXL-F28379D, for example, a program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`).
7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. For example, use this command for a F28379D based controller:

```
open_system('mcb_pmsm_foc_host_model_f28379d.slx');
```

PMSM Control Host



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. In the Host Serial Setup block mask of the host model, select a **Port name**.
10. Update the **Reference Speed** value in the host model.
11. Click **Run** on the **Simulation** tab to run the host model.
12. Change the position of the Start / Stop Motor switch to On, to start running the motor.
13. Observe the debug signals from the RX subsystem, in the Time Scope and Display blocks of the host model.

Note: In the host model, you can also select the debug signals that you want to monitor.

Other Things to Try

You can also use SoC Blockset™ to implement a closed-loop motor control application that addresses challenges related to ADC-PWM synchronization, controller response, and studying different PWM

settings. You can use Simscape™ Electrical™ to implement high fidelity inverter simulation. For details, see “Integrate MCU Scheduling and Peripherals in Motor Control Application” on page 4-132.

Control PMSM Loaded with Dual Motor (Dyno)

This example uses field-oriented control (FOC) to control two three-phase permanent magnet synchronous motors (PMSM) coupled in a dyno setup. Motor 1 runs in the closed-loop speed control mode. Motor 2 runs in the torque control mode and loads Motor 1 because they are mechanically coupled. You can use this example to test a motor in different load conditions.

The example simulates two motors that are connected back-to-back. You can use a different speed reference for Motor 1 and a different torque reference for Motor 2 (derived from the magnitude and electrical position of the Motor 2 reference stator current). Motor 1 runs at the reference speed for the load conditions provided by Motor 2 (with a different torque reference).

These equations describe the computation of d-axis and q-axis components of the Motor 2 reference stator current.

$$I_d^{ref} = I_{mag}^{ref} \times \cos\theta_e$$

$$I_q^{ref} = I_{mag}^{ref} \times \sin\theta_e$$

where:

- I_d^{ref} is the d-axis component of the Motor 2 reference stator current.
- I_q^{ref} is the q-axis component of the Motor 2 reference stator current.
- I_{mag}^{ref} is the magnitude of the Motor 2 reference stator current.
- θ_e is the electrical position of the Motor 2 reference stator current.

The example runs in the controller hardware board. You can input the speed reference for Motor 1 and current reference for Motor 2 using a host model. The host model uses serial communication to communicate with the controller hardware board.

Current control loops in Motor 1 and Motor 2 control algorithms are offset by $T_s/2$, where T_s is the control-loop execution rate.

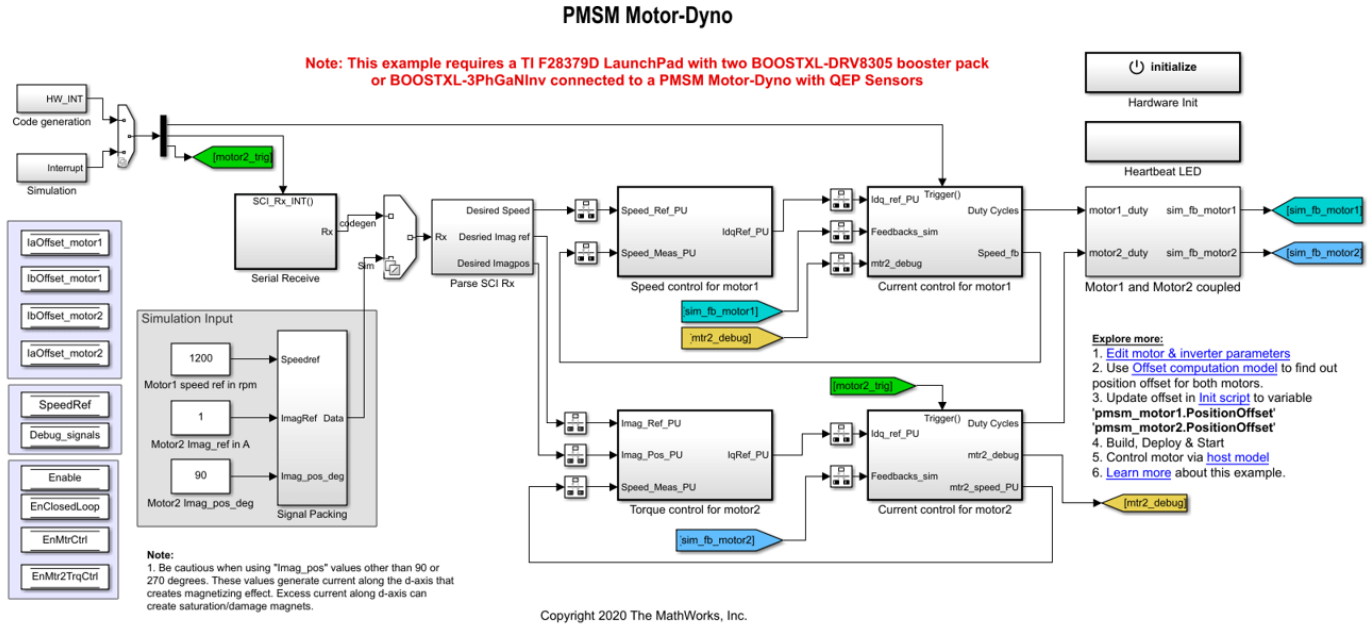
Models

The example includes the model `mcb_pmsm_foc_f28379d_dyno`.

You can use this model for both simulation and code generation. You can also use the `open_system` command to open the Simulink® model. For example, use this command for a F28379D based controller:

```
open_system('mcb_pmsm_foc_f28379d_dyno.slx');
```

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters for both Motor 1 and Motor 2. We provide default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use, by using the Motor Control Blockset™ parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

2. Update the motor parameters (that you obtained from the datasheet, other sources, or parameter estimation tool) and inverter parameters in the model initialization script associated with the Simulink® model. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

For this example, update the motor parameters for both the motors in the model initialization script.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open a model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.
4. Input a different speed reference for Motor 1 and a different current reference (load) for Motor 2. Observe the measured speed and other logged signals in the Data Inspector.

Generate Code and Deploy Model to Target Hardware

This section instructs you to generate code and run the FOC algorithm on the target hardware.

The example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + 2 BOOSTXL-DRV8305 inverters: `mcb_pmsm_foc_f28379d_dyno`
- LAUNCHXL-F28379D controller + 2 BOOSTXL-3PHGANINV inverters:
`mcb_pmsm_foc_f28379d_dyno`

For connections related to the preceding hardware configuration, see “Instructions for Dyno (Dual Motor) Setup” on page 7-9.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization scripts associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

For this example, update the QEP offset values in the `pmsm_motor1.PositionOffset` and `pmsm_motor2.PositionOffset` variables in initialization script.

5. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

6. To ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1, load a sample program to CPU2 of LAUNCHXL-F28379D, for example, a program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx).

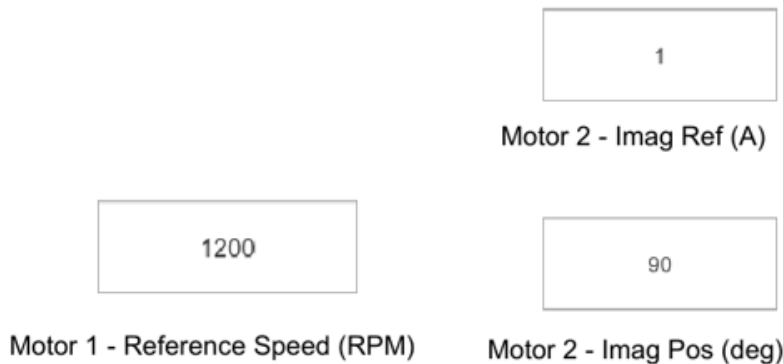
7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the model to the hardware.

8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the open_system command to open the host model:

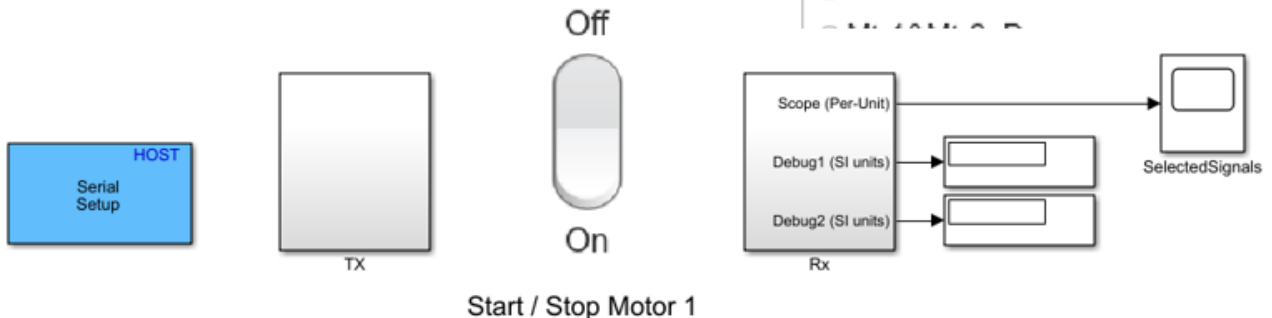
```
open_system('mcb_pmsm_foc_host_model_dyno.slx');
```

PMSM Dyno Control Host

Note:
 1. Select the serial port in 'Host Serial Setup' (Blue Color)
 2. Use 'Motor Start / Stop' switch to control motor.
 3. Input speed request for Motor 1 using 'Motor 1 Reference Speed' knob.
 4. Input Iq ref for Motor 2 using 'Motor 2 - IqRef (PU)' Knob
 4. Observe the debug signals in scope.



- Debug signals
- Mtr1: Speed ref & Speed feed
 - Mtr1: Id ref & Id feedback
 - Mtr1: Iq ref & Iq feedback
 - Mtr1: Vd & Vq
 - Mtr1: Ia & Ib feedback
 - Mtr1: Pm & Te
 - Mtr2: Id ref & Id feedback
 - Mtr2: Iq ref & Iq feedback
 - Mtr2: Vd & Vq
 - Mtr2: Ia & Ib feedback
 - Mtr2: Pm & Te
 - Mtr1&Mtr2: Pm
 - Mtr1&Mtr2: Te



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9. In the Host Serial Setup block mask of the host model, select a **Port name**.

10. Click **Run** on the **Simulation** tab to run the host model.

11. Change the position of the **Start / Stop Motor 1** switch to On, to start running the motor.

12. Update the **Motor 1 - Reference Speed (RPM)**, **Motor 2 - Imag Ref (A)**, and **Motor 2 - Imag Pos (deg)** in the host model.

Note: Be cautious when using values other than 90 or 270 degrees in the **Motor 2 - Imag Pos (deg)** field. These values generate current along the d-axis that creates a magnetizing effect. Excess current along the d-axis can create saturation and can damage the motor magnets.

13. Select the debug signals that you want to monitor, to observe them in the Time Scope block of host model.

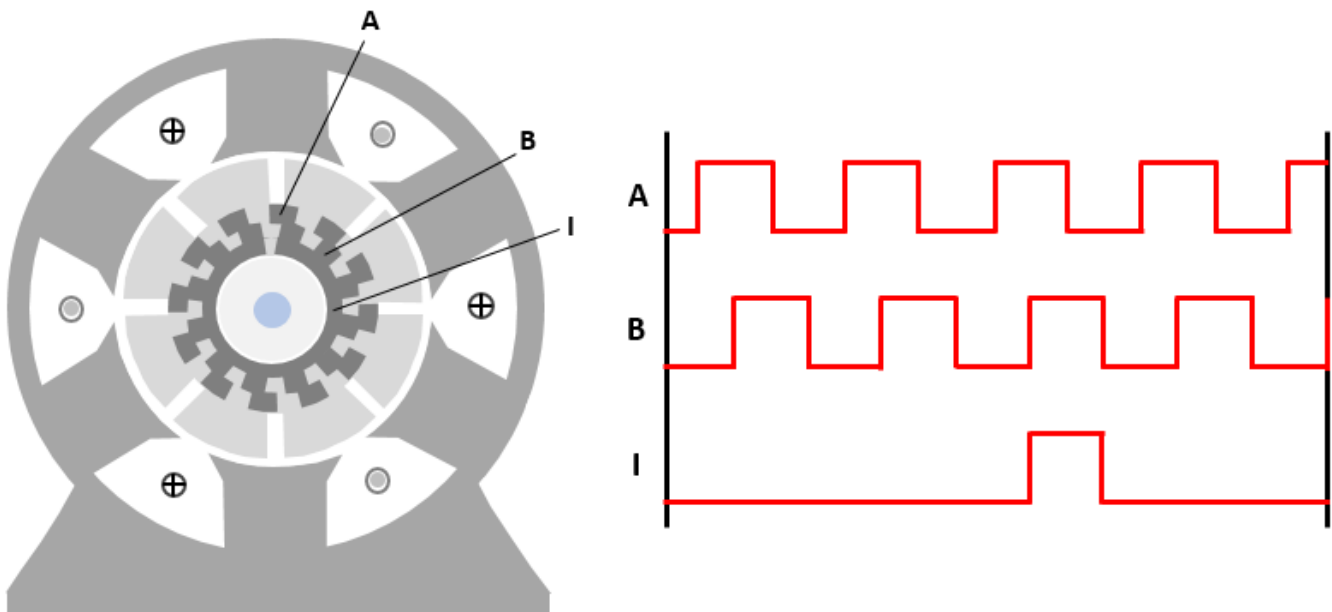
Other Things to Try

You can also use SoC Blockset™ to develop a real-time motor control application for a dual motor setup that utilizes multiple processor cores to obtain design modularity, improved controller performance, and other design goals. For details, see “Partition Motor Control for Multiprocessor MCUs” on page 4-141.

Field-Oriented Control of Induction Motor Using Speed Sensor

This example implements the field-oriented control (FOC) technique to control the speed of a three-phase AC induction motor (ACIM). The FOC algorithm requires rotor speed feedback, which is obtained in this example by using a quadrature encoder sensor. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

This example uses the quadrature encoder sensor to measure the rotor speed. The quadrature encoder sensor consists of a disk with two tracks or channels that are coded 90 electrical degrees out of phase. This creates two pulses (A and B) that have a phase difference of 90 degrees and an index pulse (I). Therefore, the controller uses the phase relationship between A and B channels and the transition of channel states to determine the direction of rotation of the motor.



Model

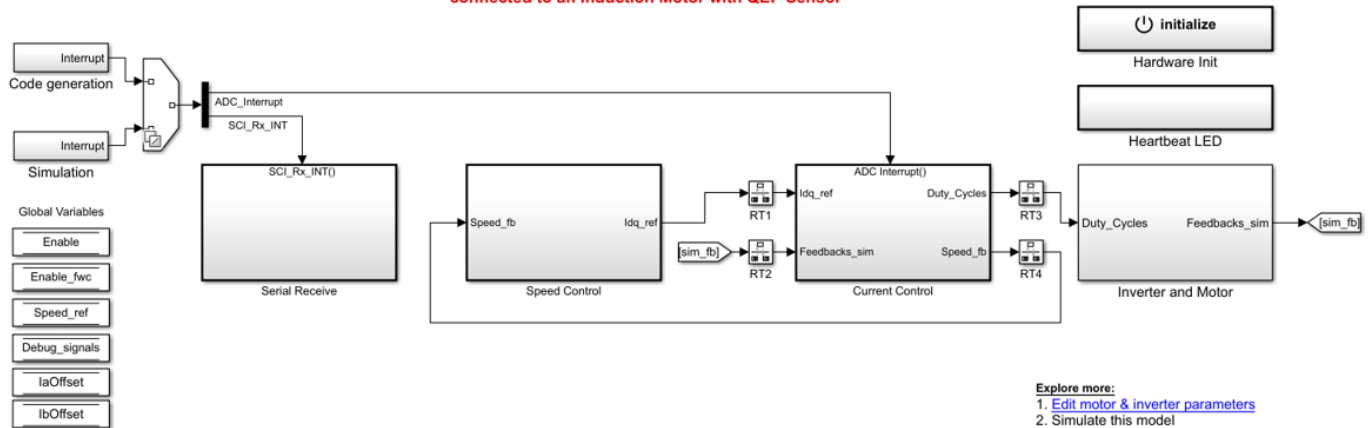
The example includes the model `mcb_acim_foc_qep_f28379d`.

You can use this model for simulation and code generation. You can also use the `open_system` command to open the Simulink® model.

```
open_system('mcb_acim_foc_qep_f28379d.slx');
```

Field-Oriented Control of AC Induction Motor

Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack connected to an Induction Motor with QEP Sensor



Note:

- 1) To achieve higher speeds, increase the "Max current" value in "Speed Control | ACIM Control Reference" block (e.g. set to 2xrated).
- 2) It is recommended to monitor motor's temperature for operation above base speed, while working with hardware.

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Explore more:

1. [Edit motor & inverter parameters](#)
2. [Simulate this model](#)
3. [Review results in Data Inspector](#)
4. [Generate code from hardware tab with "Build, Deploy & Start"](#)
5. [Control motor via host model](#)
6. [Learn more](#) about this example.

For details on the supported hardware configuration, see the Required Hardware section under Generate Code and Deploy Model to Target Hardware.

Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (needed only for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide the default motor parameters with the Simulink® model that you can replace with values from either the motor datasheet or other sources.
2. If you obtain the motor parameters from the datasheet or other sources, update the motor and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see "Estimate Control Gains from Motor Parameters" on page 3-2.
3. The initialization script also computes the derived parameters. For example, total leakage factor, rated flux, rated torque, stator and rotor inductances of the induction motor.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the model included with this example.

2. Click **Run** on the **Simulation** tab to simulate the model.

3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section instructs you on how to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in closed-loop control.

Required Hardware

This example supports the following hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: `mcb_acim_foc_qep_f28379d`

For connections related to the preceding hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.

2. Complete the hardware connections.

3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Open the target model. If you want to change the default hardware configuration settings in the model, see “Model Configuration Parameters” on page 2-2.

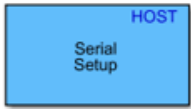
5. Load a sample program to CPU2 of the LAUNCHXL-F28379D, for example program that operates the CPU2 blue LED, by using the GPIO31 pin (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

7. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_acim_foc_host_model.slx');
```

AC Induction Motor Field Oriented Control Host



Note:
 1. Update workspace with variables used in [target model](#)
 2. Select the serial port in 'Host Serial Setup' (Blue Color)
 3. Use 'Motor Start / Stop' switch to control motor.
 4. Input speed request using 'Reference Speed' block.
 5. Observe the debug signals in scope.



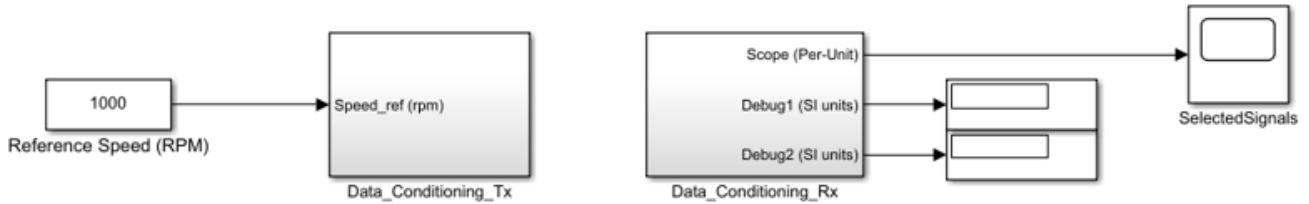
Start / Stop
Field Weakening Control



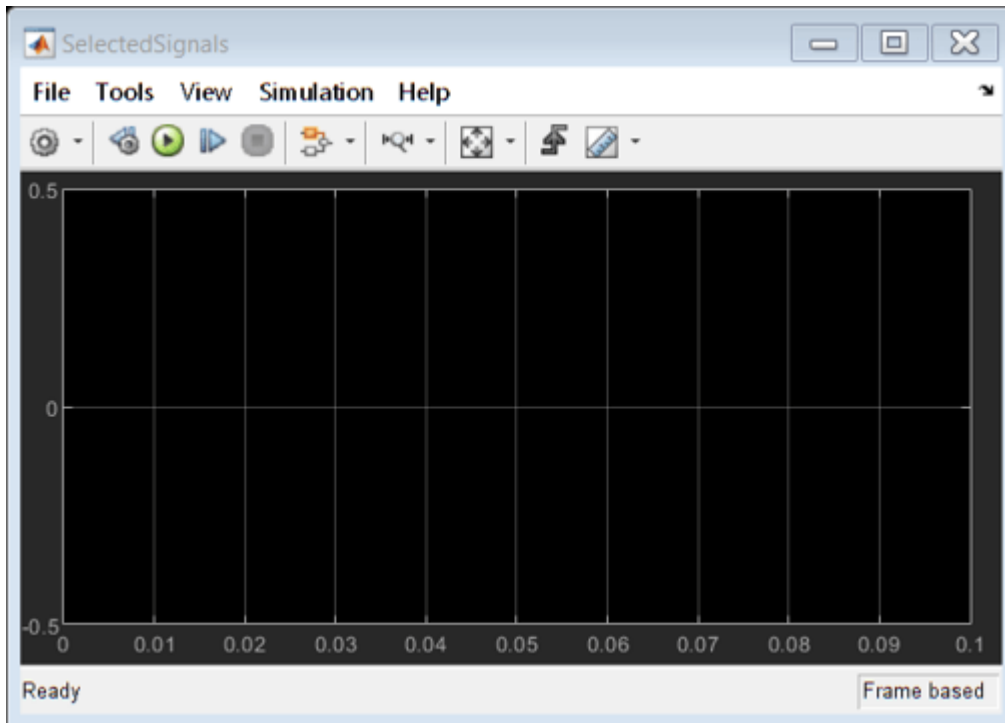
Start / Stop Motor

Debug signals _____

- Speed_ref & Speed_feedback
- Id_ref & Id_feedback
- Iq_ref & Iq_feedback
- Torque & Power



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

8. In the Host Serial Setup block mask of the host model, select a **Port name**.
9. Update the *Reference Speed* value in the host model.
10. In the **Debug signals** section, select a signal that you want to monitor.
11. Click **Run** on the **Simulation** tab to run the host model.
12. Change the position of the Start / Stop Motor switch to On to start running the motor.
13. Observe the debug signals from the RX subsystem in the **SelectedSignals** time scope of the host model.

NOTE: This example depends on the positive speed feedback for the positive rotation of the space vectors. If the motor does not run, try these steps to resolve the issue:

- Try interchanging any two motor phase connections.
- Modify and use the example “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6 with a speed feedback and confirm the positive direction of rotation for a positive reference speed.

See Also

- Field-Oriented Control of Induction Motors with Simulink and Motor Control Blockset

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (needed only for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide the default motor parameters with the Simulink® model that you can replace with the values from either the motor datasheet or other sources.
2. If you obtain the motor parameters from the datasheet or other sources, update the motor and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.
3. The initialization script also computes the derived parameters. For example, total leakage factor, rated flux, rated torque, stator and rotor inductances of the induction motor.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section instructs you on how to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model for the corresponding hardware configuration from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: `mcb_acim_foc_qep_f28379d`

For connections related to this hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.

3. The model automatically computes the Analog-to-Digital Converter (ADC) or current offset values. To disable this functionality (enabled by default), update the value 0 to the variable `inverter.ADCOffsetCalibEnable` in the model initialization script.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Open the target model. If you want to change the default hardware configuration settings in the model, see “Model Configuration Parameters” on page 2-2.

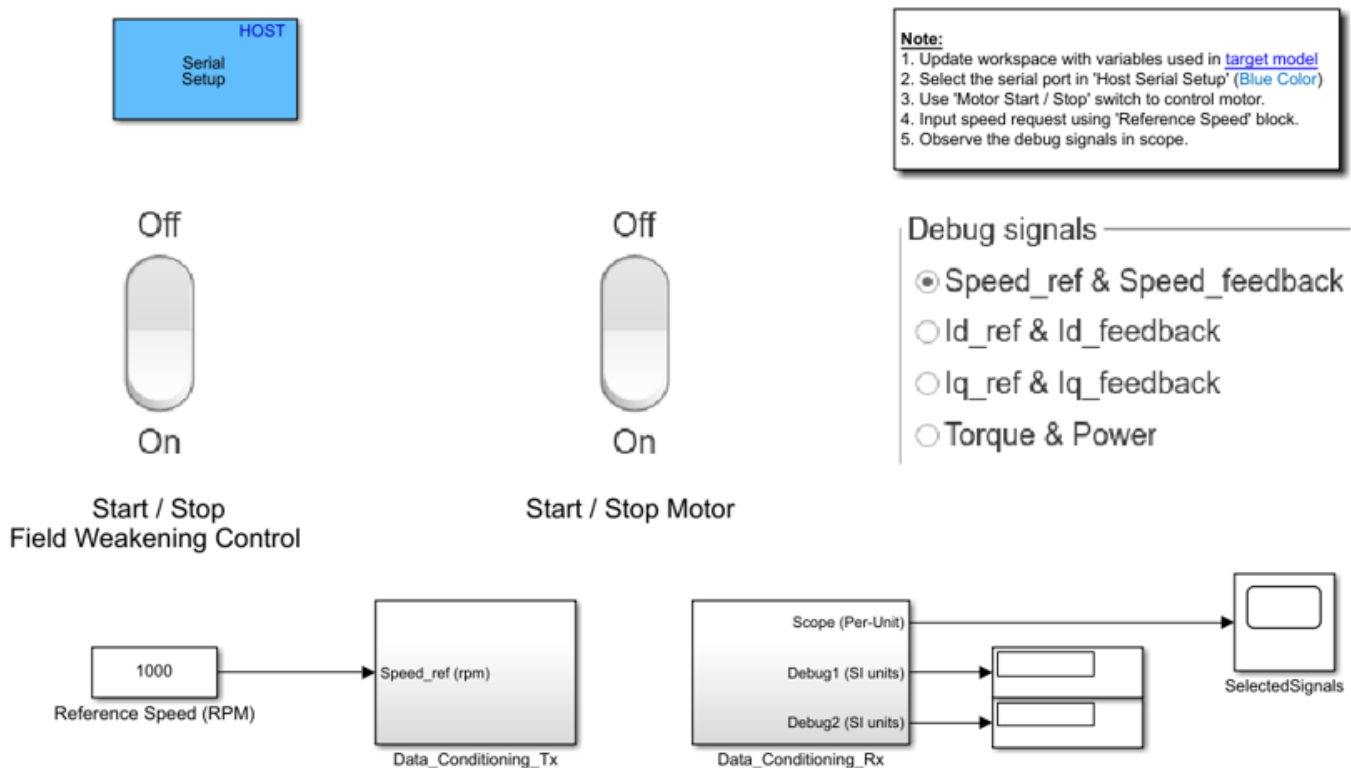
5. Load a sample program to CPU2 of the LAUNCHXL-F28379D, for example program that operates the CPU2 blue LED, using the GPIO31 pin (`c28379D_cpu2_blink.slx`), to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

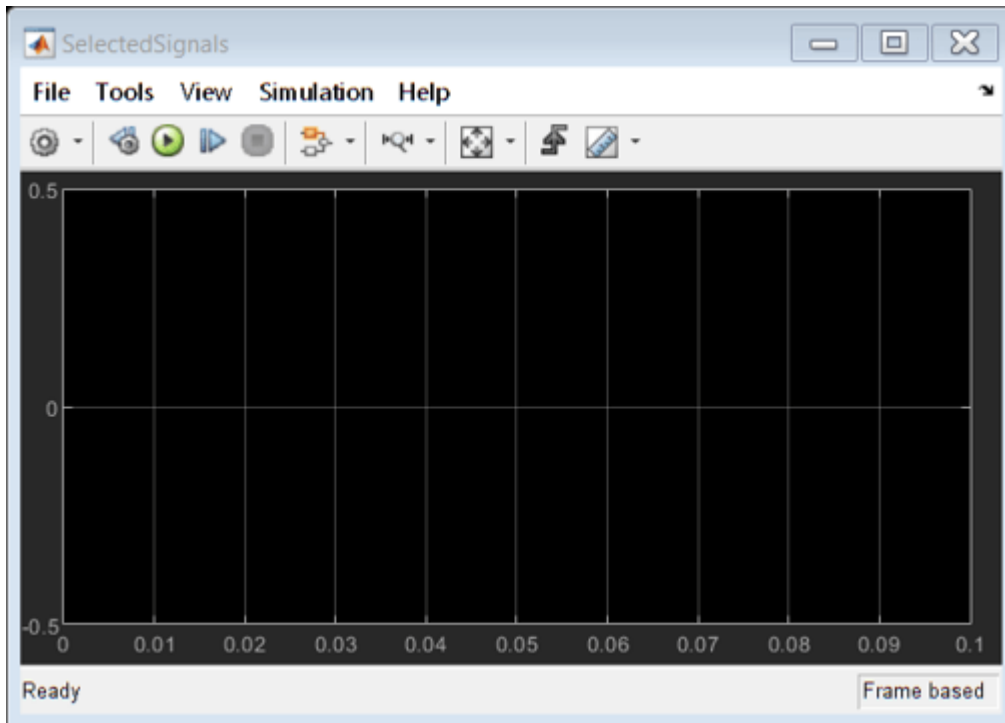
7. In the target model, click the **host model** hyperlink to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_acim_foc_host_model.slx');
```

AC Induction Motor Field Oriented Control Host



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For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

8. In the Host Serial Setup block mask of the host model, select a **Port name**.

9. Update the *Reference Speed* value in the host model.

10. In the **Debug signals** section, select a signal that you want to monitor.

11. Click **Run** on the **Simulation** tab to run the host model.

12. Change the position of the Start / Stop Motor switch to On, to start running the motor in the open-loop condition (by default, the motor spins at 10% of the base speed).

Note: Do not run the motor (using this example) in the open-loop condition for long. The motor may draw high currents and produce excessive heat.

We designed the open-loop control to run the motor with a Reference Speed that is less than or equal to 10% of base speed.

13. Increase the motor *Reference Speed* beyond 10% of the base speed to switch from open-loop to closed-loop control.

NOTE: To change the motor's direction of rotation, reduce the motor *Reference Speed* to a value less than 10% of the base speed. This brings the motor back to the open-loop condition. Change the direction of rotation, but keep the *Reference Speed* magnitude constant. Then transition to the closed-loop condition.

14. Observe the debug signals from the RX subsystem in the **SelectedSignals** time scope of the host model.

Tune PI Controllers Using Field Oriented Control Autotuner Block on Real-Time Systems

This example computes the gain values of proportional-integral (PI) controllers within the speed and current controllers by using the Field Oriented Control Autotuner block. For details about field-oriented control, see “Field-Oriented Control (FOC)” on page 4-2.

This model supports both simulation and code generation. When you run the model, it uses the simple values of gains for the PI controllers to achieve the steady state of the speed-control operation.

The model begins tuning only in the steady state. It introduces disturbances in the controller output depending on the controller goals (bandwidth and phase margin). The model uses the system response to disturbances to calculate the optimal controller gain.

Model

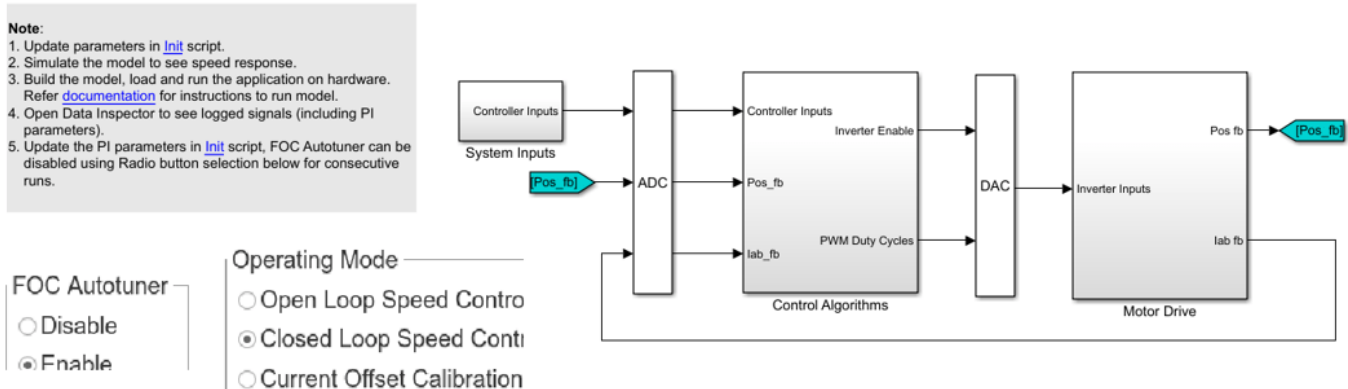
The example includes the model `mcb_pmsm_foc_autotuner_speedgoat`.

You can use this model for both simulation and code generation. You can use the `open_system` command to open the Simulink® model.

```
open_system('mcb_pmsm_foc_autotuner_speedgoat.slx');
```

Tuning PI controllers for current and speed using FOC Autotuner on Real-Time Target

Note: This example requires Speedgoat Baseline Real-Time Target machine with [IO-397](#) and [Electric motor control kit](#)



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For details on the supported hardware configuration, see the Required Hardware section under Generate Code and Deploy Model to Target Hardware.

Required MathWorks® Products

- Motor Control Blockset™
- Simulink Control Design™
- Simulink Real-Time™

- Speedgoat I/O Blockset

Prerequisites

1. The motor parameters available in the example model are for the motor that comes with the Speedgoat Electric Motor Control Kit. You can modify these parameters for any other motor by replacing them with values from either the motor datasheet or other sources.
2. If you obtain the motor parameters from the datasheet or other sources, update the motor and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Model Initialization Script” on page 3-3.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the model included with this example.
2. Check the reference speed profile configured in the signal builder (available in `mcb_pmsm_foc_autotuner_speedgoat/System Inputs/Speed Reference`).
3. Check and update the FOC Autotuner parameters in the Field Oriented Control Autotuner block mask (available in the Control Algorithms/FOC_AutoTuner subsystem). For details about the Field Oriented Control Autotuner block, see Field Oriented Control Autotuner.
4. Check and update the simple gain values in the model initialization script associated with the model.
5. Click **Run** on the **Simulation** tab to simulate the model.
6. Verify that the motor reaches steady state operation for at least half of the rated speed using the simple gain values that you entered. The model begins field-oriented control (FOC) tuning (using the Field Oriented Control Autotuner block) at the seventeenth second.
7. After tuning completes, observe the computed PI controller gain values in the Display PI Params block available in the Control Algorithms subsystem.
8. Observe the system response with the newly computed PI parameters by using the Simulation Data Inspector.

For more details, see “Tune PI Controllers Using Field Oriented Control Autotuner” on page 4-24.

Generate Code and Deploy Model to Target Hardware

This section instructs you on how to generate code and run the FOC algorithm on the target hardware.

Required Hardware

This example supports Speedgoat Electric Motor Control Kit that includes these components:

- Three-phase inverter rated for 48 V and 20 A from Speedgoat
- 100 W three-phase brushless DC motor from Maxon Motor

- Quadrature encoder with 4096 impulses
- 150 W 254 V DC power supply

NOTE: Contact Speedgoat for the bit stream file that is valid for your hardware.

For details about Speedgoat hardware setup, see [Speedgoat Software Configuration Guide](#).

Generate Code and Run Model on Target Hardware

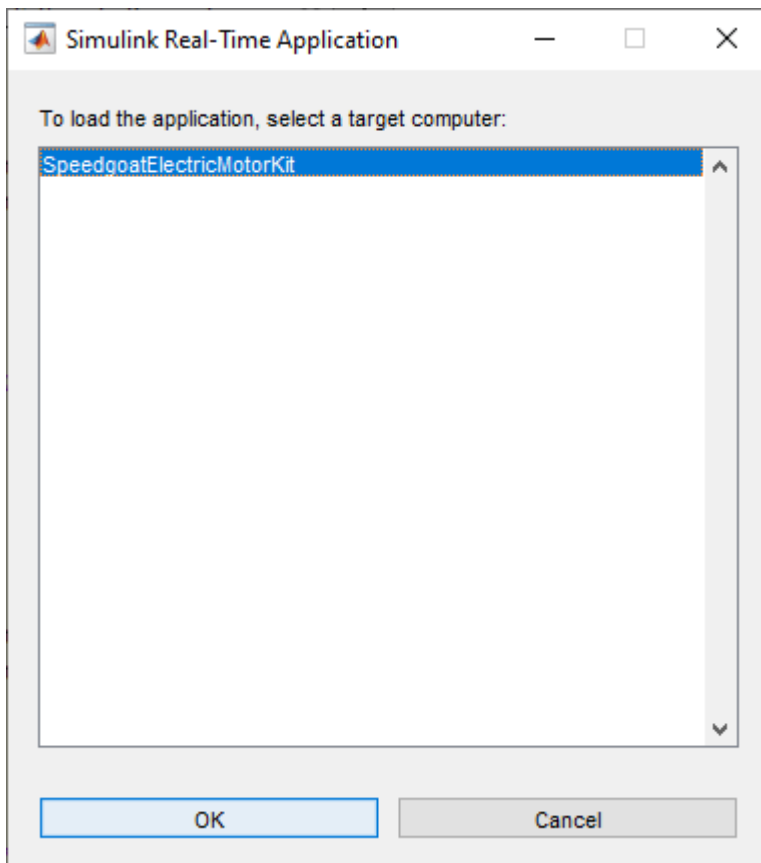
1. Simulate the model and verify that you are obtaining the desired controller response.
2. Complete the hardware connections for the Speedgoat Electric Motor Control Kit.

- **Calibrate current offset**

1. In the model, set **Operating Mode** to **Current Offset Calibration**.
2. In the **Real-Time** tab on the Simulink toolstrip, click **Build Model** in the **Run on Target** drop-down menu to build the model.

NOTE: Do not click **Run on Target** because this example model does not support real-time execution in external mode.

3. Navigate to the folder where Simulink built the model. Double click the file `mcb_pmsm_foc_autotuner_speedgoat.mldatx` to open the Simulink Real-Time Application dialog box.



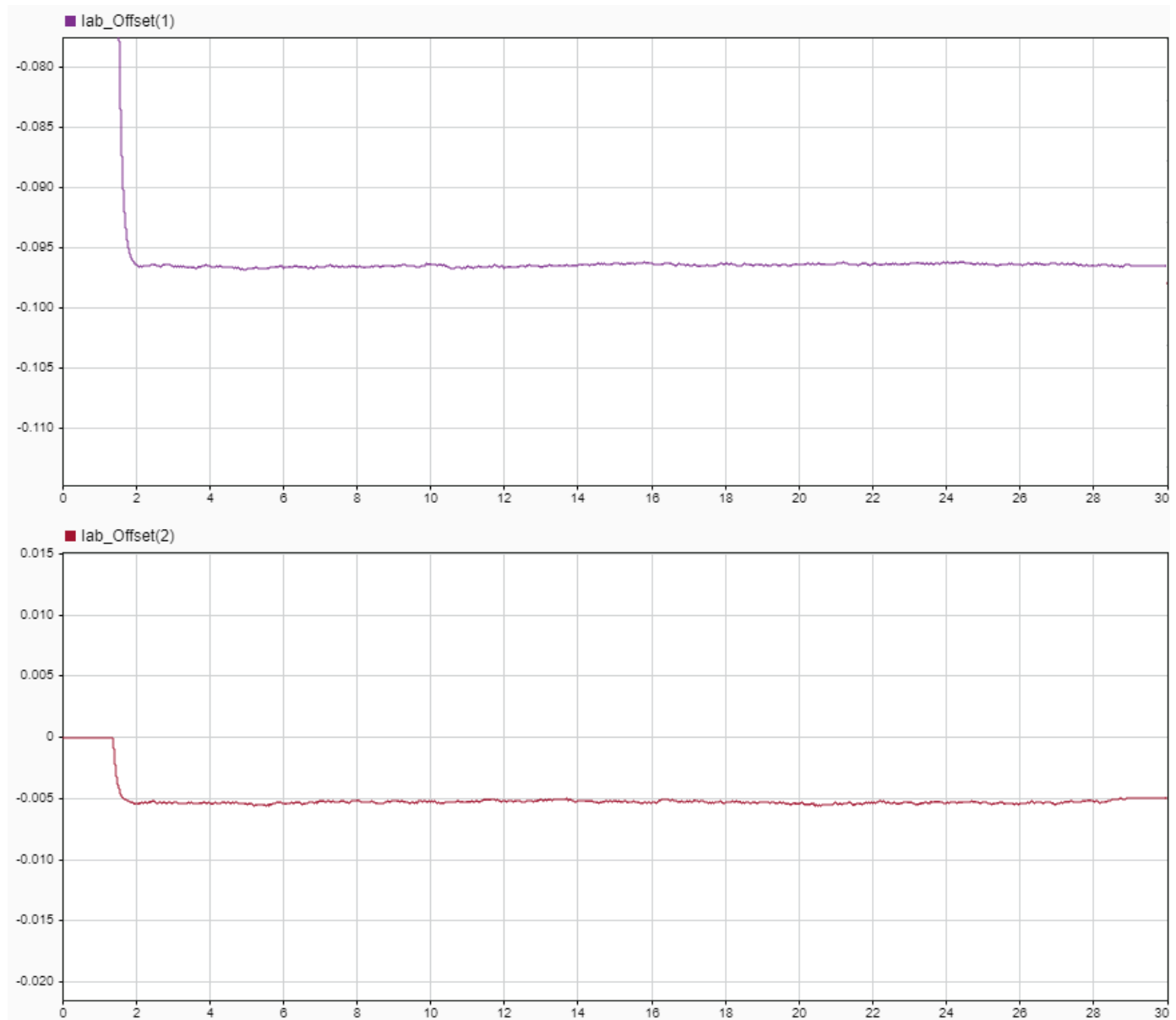
4. In the Simulink Real-Time Application dialog box, select the target computer to which you are connected. Click **OK** to load the application file to the hardware.

5. Enter these commands (in the same order) at the MATLAB command prompt to execute the loaded application on the hardware.

- `tg = slrealtime;`
- `tg.start;`

6. After the model runs successfully, use **Data Inspector** on the **Simulation** tab to see the logged signals. The stabilized `Iab_offset` signals are the current offsets.

7. Update the current offset values in the `inverter.CtSensAOffset` and `inverter.CtSensBOffset` variables available in the model initialization script associated with the Simulink model.



- **Run motor in open-loop control**

1. In the model, set **Operating Mode** to **Open Loop Speed Control**.

2. In the **Real-Time** tab on the Simulink toolstrip, click **Build Model** in the **Run on Target** drop-down menu to build the model.

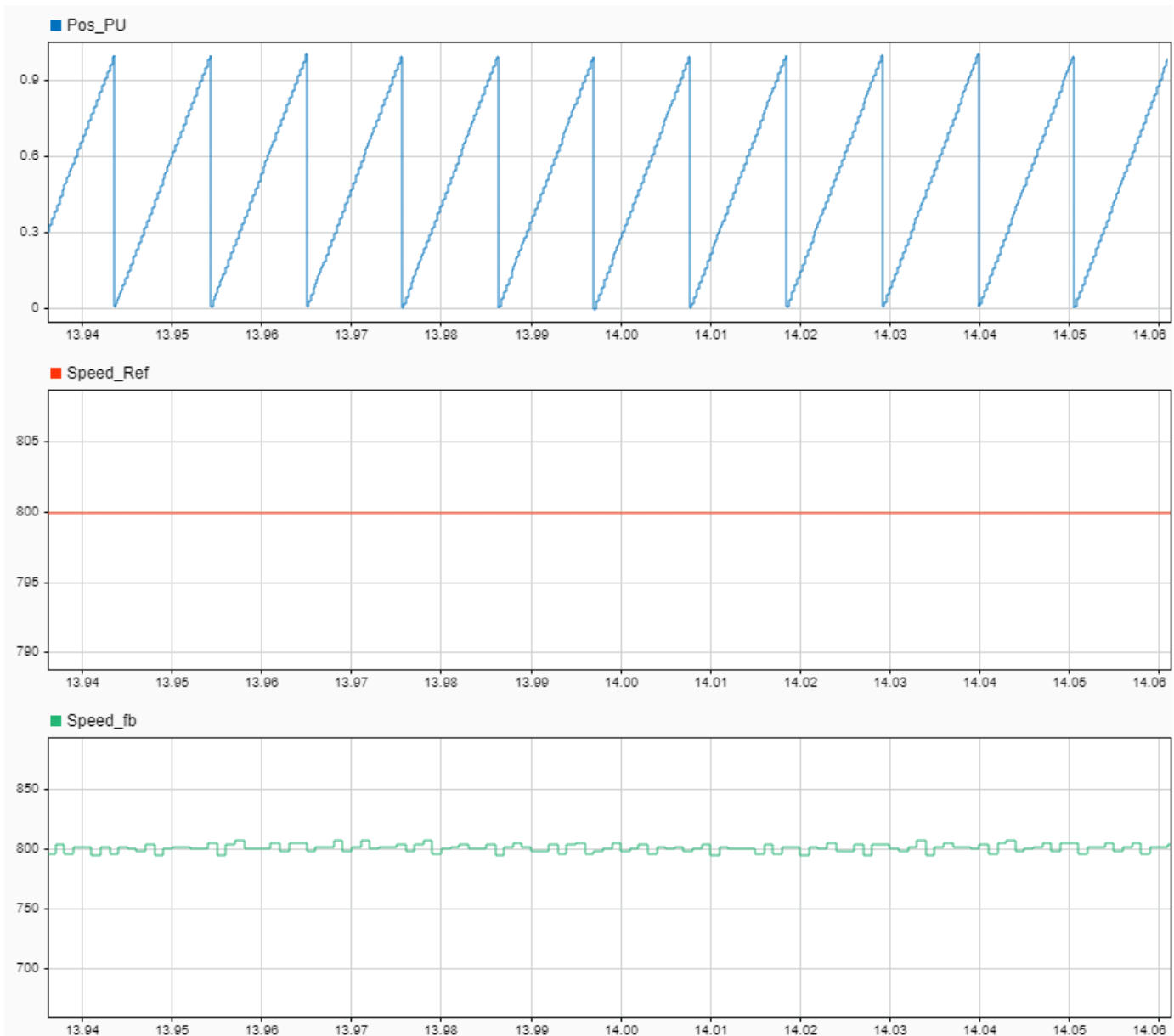
3. Navigate to the folder where Simulink built the model. Double click the file `mcb_pmsm_foc_autotuner_speedgoat.mldatx` to open the Simulink Real-Time Application dialog box.

4. In the Simulink Real-Time Application dialog box, select the target computer to which you are connected. Click **OK** to load the application file to the hardware.

5. Enter these commands (in the same order) at the MATLAB command prompt to execute the loaded application on the hardware.

- `tg = slrealtime;`
- `tg.start;`

6. After the model executes, use **Data Inspector** on the **Simulation** tab to see the logged signals. Verify that speed feedback (`Speed_fb`) follows the reference speed (`Speed_Ref`) signal.



For example, verify that the positive reference speed has a positive speed feedback, and the position signal (`Pos_PU`) has a positive ramp.

If there is a mismatch in the sign of the reference speed and speed feedback signals, change the **A leads B** parameter (of the Inverter and Plant model/SpeedGoatDrivers/Condition Encoder block)

either from 0 to 1 or from 1 to 0. Then follow steps 2 to 6 in this section to execute the model again on the hardware.

NOTE: In the Open Loop Speed Control mode, the motor speed is limited between 500 rpm and 1200 rpm.

- **Run motor in closed-loop control**

1. In the model, set **Operating Mode** to **Closed Loop Speed Control**.

2. Set the **FOC Autotuner** button on the model to **Disable** to disable the field-oriented control (FOC) Autotuner.

3. In the **Real-Time** tab on the Simulink toolstrip, click **Build Model** in the **Run on Target** drop-down menu to build the model.

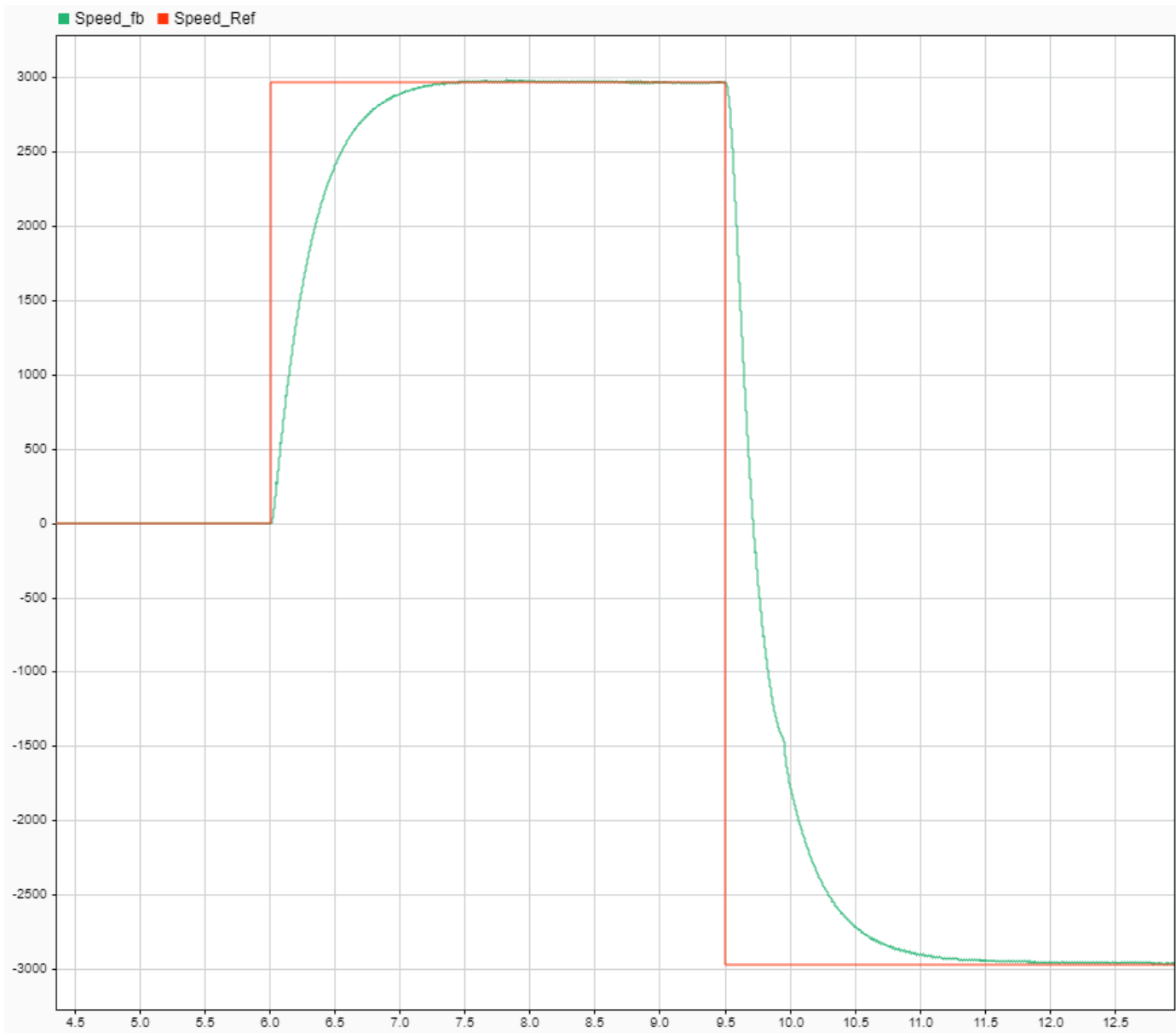
4. Navigate to the folder where Simulink built the model. Double-click the file `mcb_pmsm_foc_autotuner_speedgoat.mldatx` to open the Simulink Real-Time Application dialog box.

5. In the Simulink Real-Time Application dialog box, select the target computer to which you are connected. Click **OK** to load the application file to the hardware.

6. Enter these commands (in the same order) at the MATLAB command prompt to execute the loaded application on the hardware and run the motor.

- `tg = slrealtime;`
- `tg.start;`

The motor runs in closed-loop control at a speed that is configured in the signal builder.



7. Verify that the motor reaches steady state operation because the FOC Autotuner will not work if the motor speed is unstable.

If the motor fails to reach the steady state, change the PI parameters manually in the model initialization script (associated with the model), until the motor speed stabilizes to half the base speed of the motor.

NOTE: When tuning the PI parameters in the model initialization script, the motor may show a slow speed response.

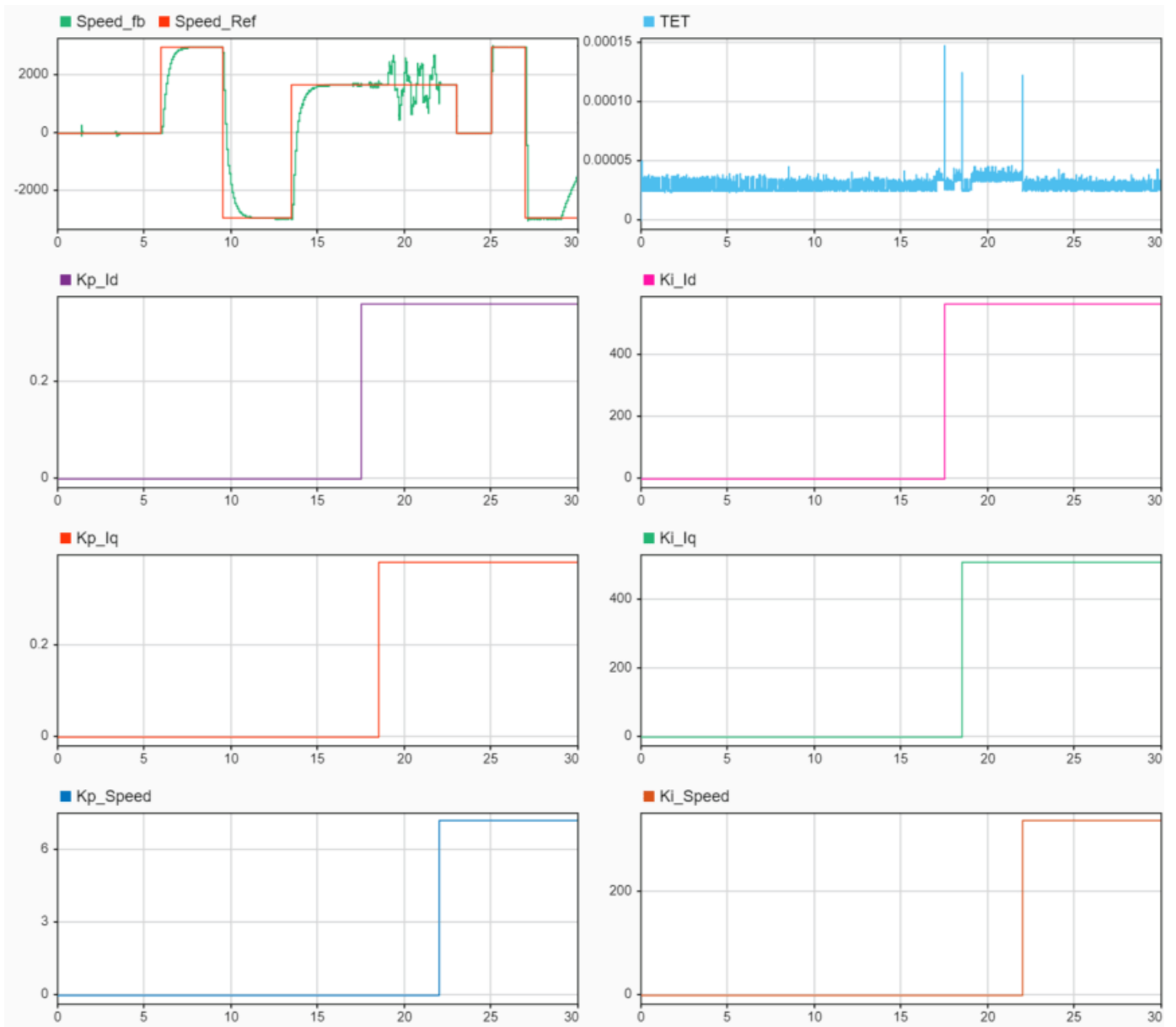
8. If the motor reaches a stable speed, follow the steps to run FOC Autotuner.

- **Run FOC Autotuner**

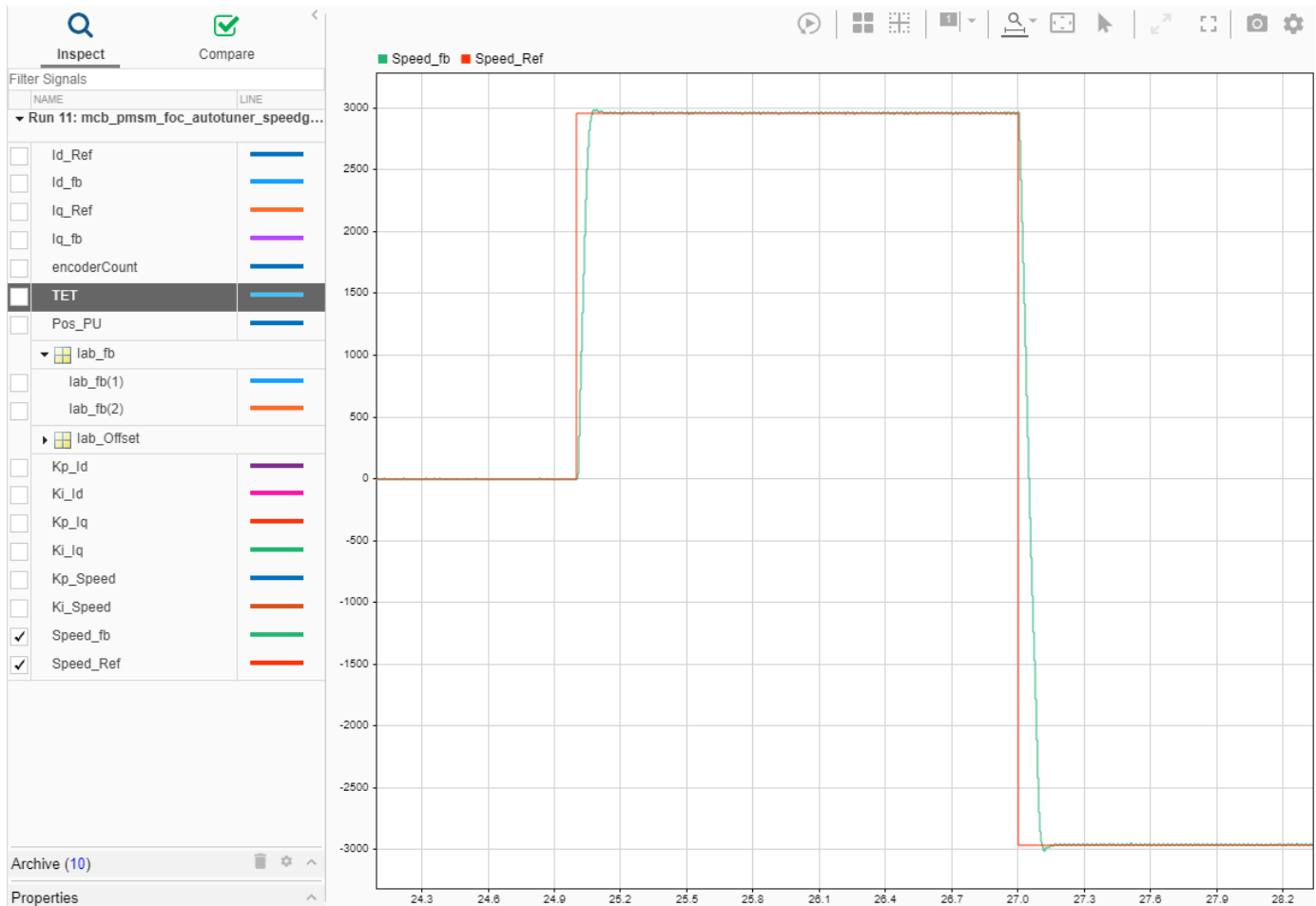
1. Set the **FOC Autotuner** button on the model to **Enable** to enable the field-oriented control autotuner.
2. Verify if **Operating Mode** is set to **Closed Loop Speed Control**.
3. Check and update the FOC Autotuner parameters (such as autotuner trigger timing and controller target) in the Field Oriented Control Autotuner block mask (available inside Control Algorithms/FOC_AutoTuner subsystem). For details about the Field Oriented Control Autotuner block, see Field Oriented Control Autotuner.
4. In the **Real-Time** tab on the Simulink toolstrip, click **Build Model** in the **Run on Target** drop-down menu to build the model.
5. Navigate to the folder where Simulink built the model. Double click the file `mcb_pmsm_foc_autotuner_speedgoat.mldatx` to open the Simulink Real-Time Application dialog box.
6. In the Simulink Real-Time Application dialog box, select the target computer to which you are connected. Click **OK** to load the application file to the hardware.
7. Enter these commands (in the same order) at the MATLAB command prompt to execute the loaded application on the hardware and run the motor.
 - `tg = slrealtime;`
 - `tg.start;`

The model begins field-oriented control (FOC) tuning (using the Field Oriented Control Autotuner block) at the seventeenth second after model execution begins on the hardware. It logs the PI controller gain values (`kp_Id`, `ki_Id`, `kp_Iq`, `ki_Iq`, `kp_speed`, `ki_speed`) in the Simulation Data Inspector.

8. Observe and compare the system response with the PI parameters before tuning and after tuning in the Simulation Data Inspector.



4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



9. If the system response after tuning is satisfactory, update the gain values in the model initialization script associated with the model. For consecutive model executions, you can disable the FOC tuning using the FOC Autotuner button in the model and continue with the closed-loop testing using the new PI parameters.

NOTE: Do not reconfigure or change the reference speed value in the signal builder such that the reference speed changes during the tuning process.

Six-Step Commutation of BLDC Motor Using Sensor Feedback

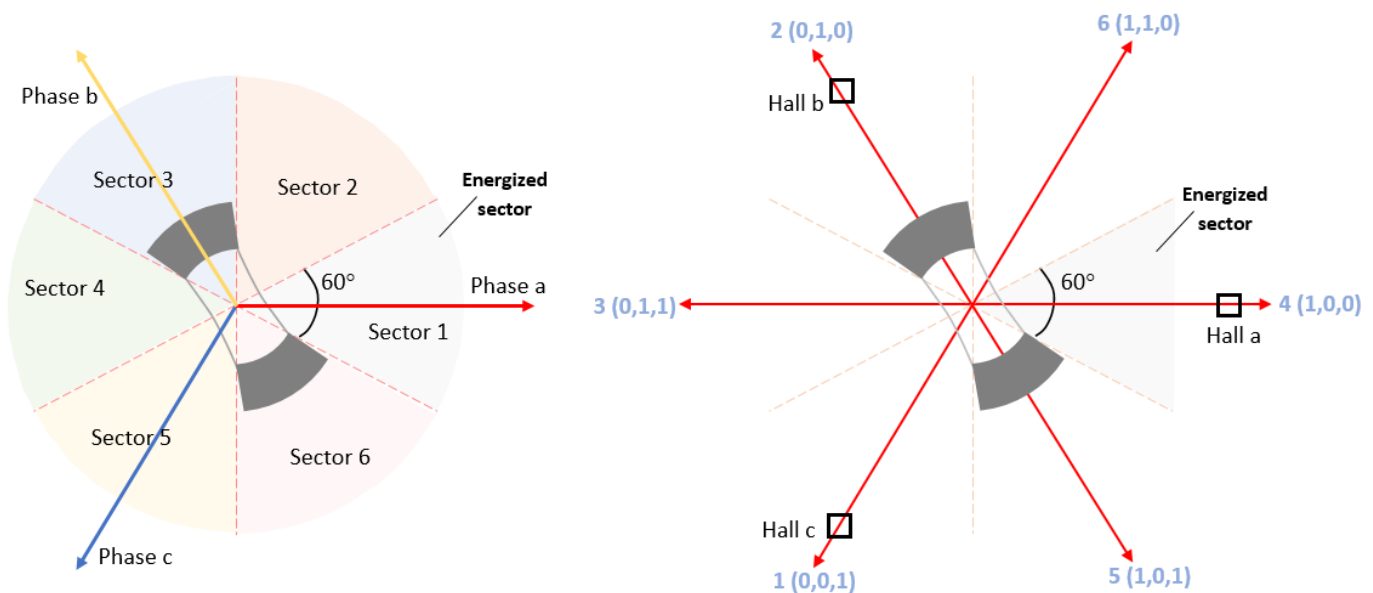
This example uses 120-degree conduction mode to implement the six-step commutation technique to control speed and direction of rotation of a three-phase brushless DC (BLDC) motor. The example uses the switching sequence generated by the Six Step Commutation block to control three-phase stator voltages, and therefore, control the rotor speed and direction. For more details about this block, see Six Step Commutation.

The six-step commutation algorithm requires a Hall sequence or a rotor position feedback value (which is obtained from either a quadrature encoder or a Hall sensor).

The quadrature encoder sensor consists of a disk with two tracks or channels that are coded 90 electrical degrees out of phase. This creates two pulses (A and B) that have a phase difference of 90 degrees and an index pulse (I). The controller uses the phase relationship between the A and B channels and the transition of channel states to determine the speed, position, and direction of rotation of the motor.

A Hall effect sensor varies its output voltage based on the strength of the applied magnetic field. According to the standard configuration, a BLDC motor consists of three Hall sensors located electrically 120 degrees apart. A BLDC with the standard Hall placement (where the sensors are placed electrically 120 degrees apart) can provide six valid combinations of binary states: for example, 001,010,011,100,101, and 110. The sensor provides the angular position of the rotor in degrees in the multiples of 60, which the controller uses to determine the 60-degree sector where the rotor is present.

The controller controls the motor by using the Hall sequence or the rotor position. It energizes the next two phases of the stator winding, so that the rotor always maintains a torque angle (angle between rotor d-axis and stator magnetic field) of 90 degrees with a deviation of 30 degrees.



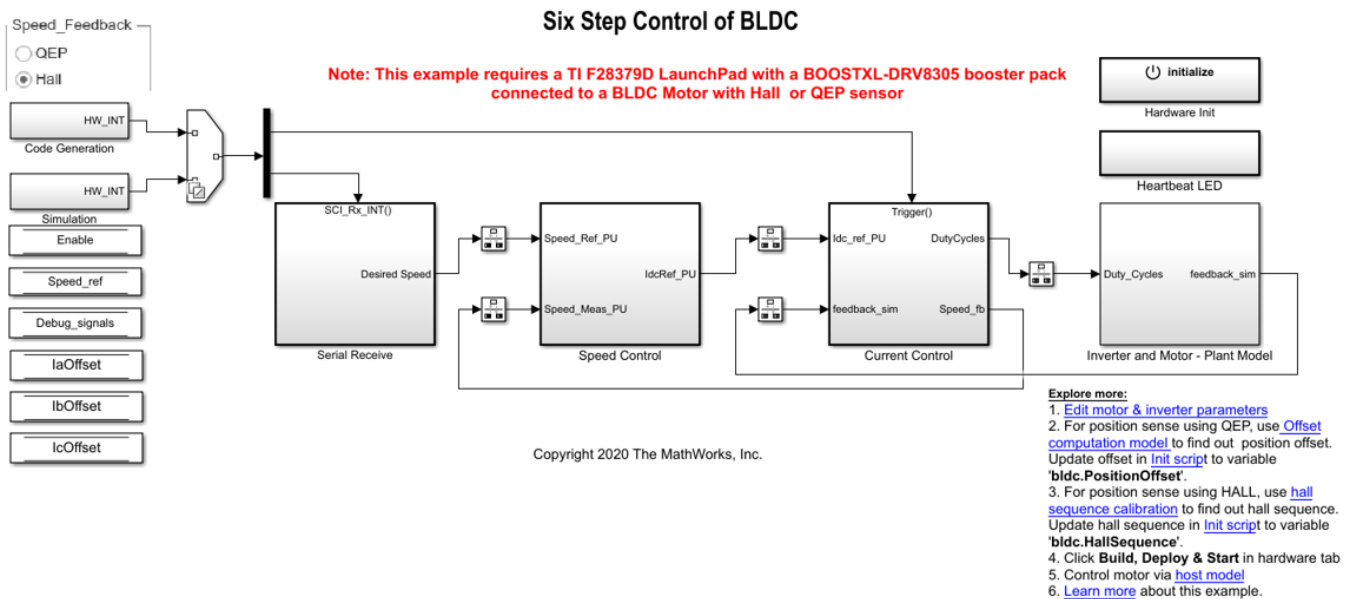
Models

The example includes these models:

- mcb_bldc_sixstep_f28069mLaunchPad
- mcb_bldc_sixstep_f28379d

You can use these models for both simulation and code generation. To open a Simulink® model, you can also use the `open_system` command at the MATLAB command prompt. For example, use this command for a F28379D based controller:

```
open_system('mcb_bldc_sixstep_f28379d.slx');
```



For details of the supported hardware configuration, see Required Hardware in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. We provide default motor parameters with the Simulink model that you can replace with values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use by using the Motor Control Blockset parameter estimation tool. For instructions, see "Estimate PMSM Parameters Using Recommended Hardware" on page 4-188.

The parameter estimation tool updates the *motorParam* variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from a motor datasheet or from other sources, update the motor parameters and the inverter parameters in the model initialization script associated with the Simulink models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts the motor parameters from the updated *motorParam* workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the model included with this example.
2. Select either the QEP or the Hall Speed_Feedback radio button in the model.
3. Click **Run** on the **Simulation** tab to simulate the model.
4. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section shows you how to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink model and run the motor in a closed-loop control.

Required Hardware

The example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
mcb_bldc_sixstep_f28069mLaunchPad
- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: mcb_bldc_sixstep_f28379d

For connections related to these hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

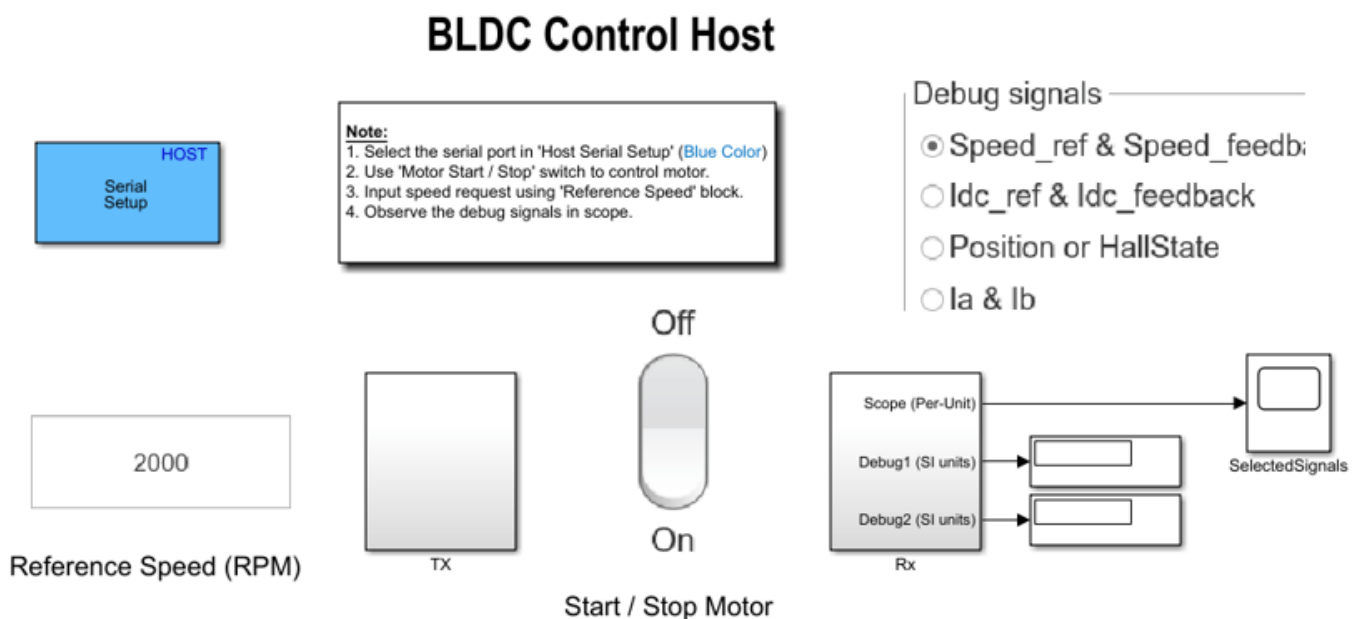
Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model computes the ADC (or current) offset values by default. To disable this functionality, update the value 0 to the variable *inverter.ADCOffsetCalibEnable* in the model initialization script.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization script. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. If you are using a quadrature encoder, compute the quadrature encoder index offset value and update it in the model initialization script associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.
5. If you are using a Hall sensor, compute the Hall sequence value and update it in the *bldc.hallsequence* variable in the model initialization script associated with the target model. For instructions, see “Hall Sensor Sequence Calibration of BLDC Motor” on page 4-122.
6. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.
7. Select either the QEP or the Hall Speed_Feedback radio button in the target model.
8. Load a sample program to CPU2 of LAUNCHXL-F28379D. For example, you can use the program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx), and ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
9. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
10. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. Use this command for a F28379D based controller.

```
open_system('mcb_bldc_host_model_f28379d.slx');
```



For on the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

11. In the Host Serial Setup block mask in the host model, select a **Port name**.
12. Update the reference speed value in the *Reference Speed (RPM)* field in the host model.

- 13.** In the host model, select the debug signals that you want to monitor.
- 14.** Click **Run** on the **Simulation** tab to run the host model.
- 15.** Change the position of the Start / Stop Motor switch to On, to start running the motor.
- 16.** Observe the debug signals from the RX subsystem, in the Scope and Display blocks in the host model.

Hall Sensor Sequence Calibration of BLDC Motor

This example calculates the Hall sensor sequence with respect to position zero of the rotor in open-loop control.

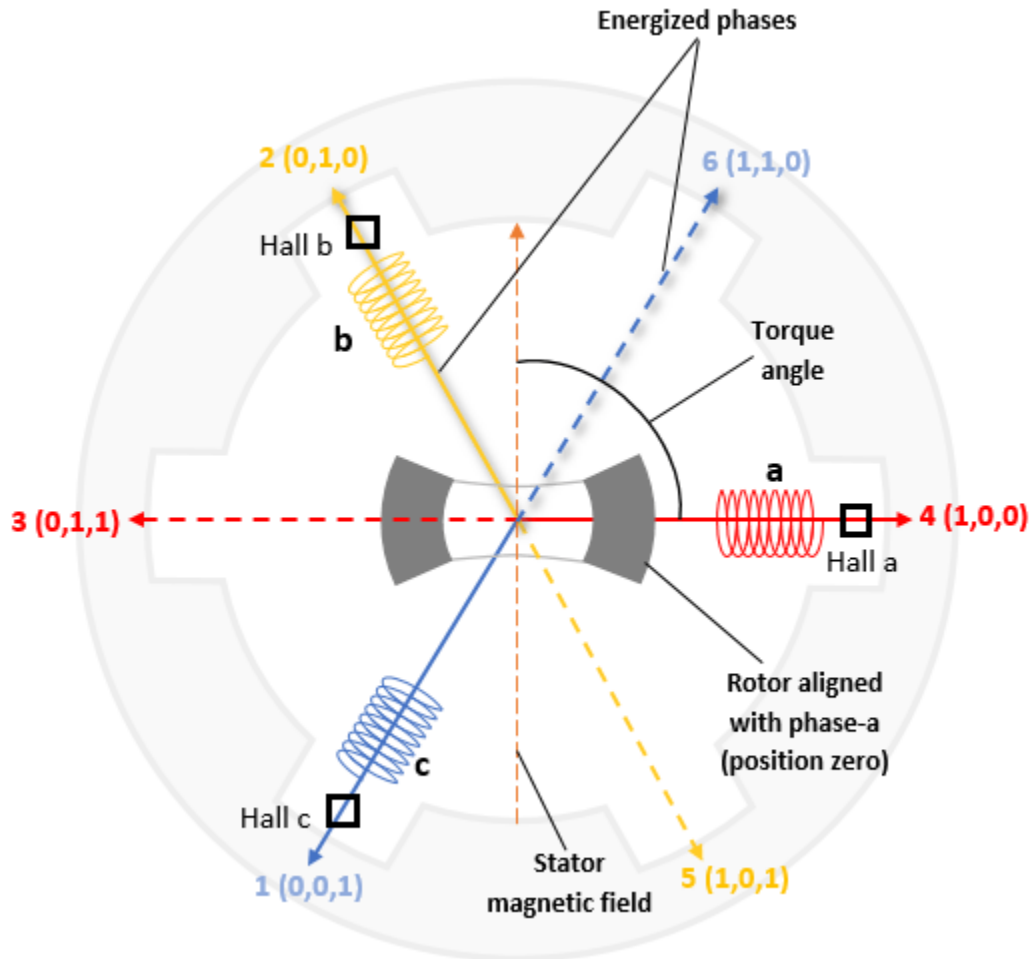
A Hall effect sensor varies its output voltage based on the strength of the applied magnetic field. According to the standard configuration, a brushless DC (BLDC) consists of three Hall sensors located electrically 120 degrees apart. A BLDC motor with the standard Hall placement (where the sensors are placed electrically 120 degrees apart) can provide six valid combinations of binary states: for example, 001,010,011,100,101, and 110. The sensor provides the angular position of the rotor in degrees in the multiples of 60, which the controller uses to determine the 60-degree sector where the rotor is present.

The target model runs the motor at a low speed (10 RPM) in open loop and performs V/f control on the motor. At this speed, the d-axis of the rotor closely aligns with the rotating magnetic field of the stator.

When the rotor reaches the open-loop position zero, it aligns with the phase a-axis of the stator. At this position (corresponding to a Hall state), the six-step commutation algorithm energizes the next two phases of the stator winding, so that the rotor always maintains a torque angle (angle between rotor d-axis and stator magnetic field) of 90 degrees with a deviation of 30 degrees.

The Hall sequence calibration algorithm drives the motor over a full mechanical revolution and computes the Hall sensor sequence with respect to position zero of the rotor in open-loop control.

Note: This example works for all motor-phase or Hall sensor connections.



Models

The example includes these models:

- `mcb_hall_calibration_f28069mLaunchPad`
- `mcb_hall_calibration_f28379d`.

You can use these models only for code generation. To open a Simulink® model, you can also use the `open_system` command at the MATLAB® command prompt. For example, use this command for a F28379D based controller:

```
open_system('mcb_hall_calibration_f28379d.slx');
```

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)

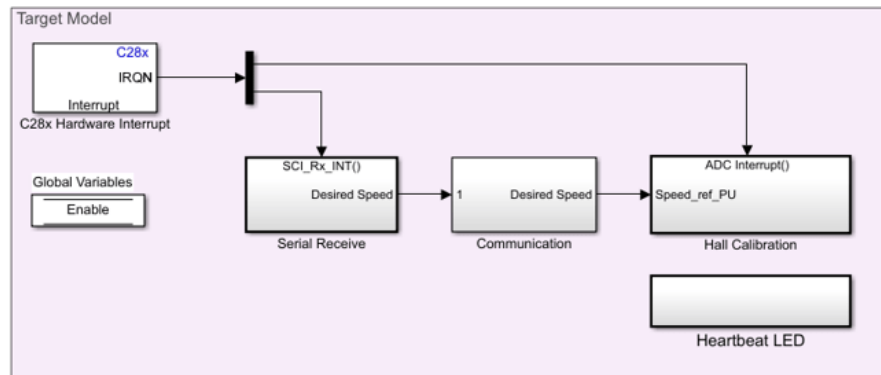
Steps:

1. Enter parameters in the Configuration panel.
2. Click **Build, Deploy & Start** in the **Hardware** tab.
3. Perform calibration by using [host model](#).
4. If the motor does not start or rotate smoothly, increase **Vd Ref in Per Unit voltage** (that can have a maximum value of 1) in the Configuration panel.
5. If the current drawn by the connected motor is too high, reduce the value mentioned in step 4.

Configuration	
Number of Pole Pairs	4
PWM Frequency [Hz]	20000
Data type for control algorithm	single
Motor Base Speed [rpm]	4000
Vd Ref in Per Unit voltage	0.1

Hall Sequence Calibration of 3-phase motors

Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack



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For details on the supported hardware configuration, see Required Hardware in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Generate Code and Deploy Model to Target Hardware

This section shows you how to generate code and run the motor by using open-loop control.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board.

The host model uses serial communication to command the target model and run the motor in an open-loop configuration by using V/f control. The host model displays the calculated Hall sensor sequence.

Required Hardware

The example supports these hardware configurations. You can also use the target model name to open the model for the corresponding hardware configuration, from the MATLAB® command prompt.

- LAUNCHXL-F28069M controller + BOOSTXL-DRV8305 inverter:
mcb_hall_calibration_f28069mLaunchPad
- LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter: mcb_hall_calibration_f28379d

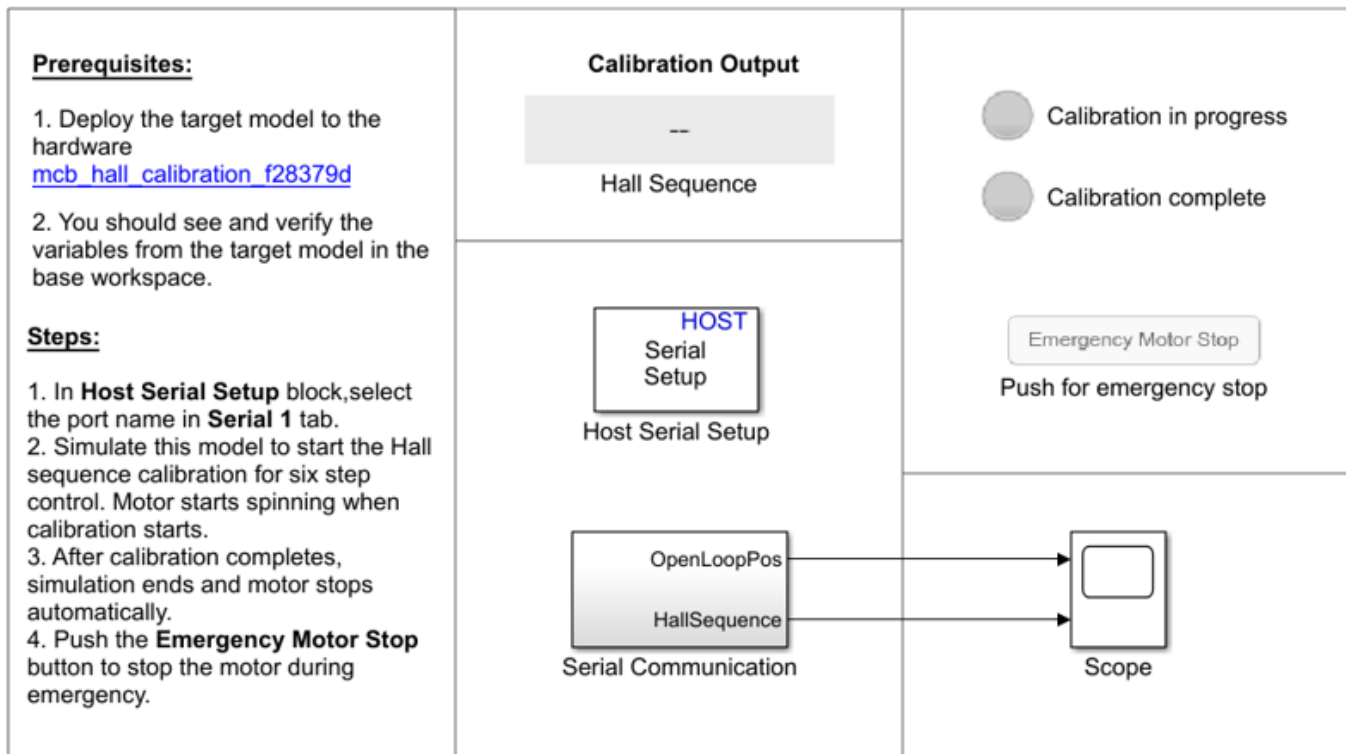
For connections related to these hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Complete the hardware connections.
2. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the target model, see “Model Configuration Parameters” on page 2-2.
3. Update these motor parameters in the **Configuration** panel of the target model.
 - **Number of pole pairs**
 - **PWM frequency [Hz]**
 - **Data type for control algorithm**
 - **Motor base speed**
 - **Vd Ref in per-unit voltage**
4. Load a sample program to CPU2 of LAUNCHXL-F28379D. For example, you can use the program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx), and ensures that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
5. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
6. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model. Use this command for a F28379D based controller:

```
open_system('mcb_hall_calibration_host_f28379d.slx');
```

Hall Sequence Calibration Host



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For details on serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

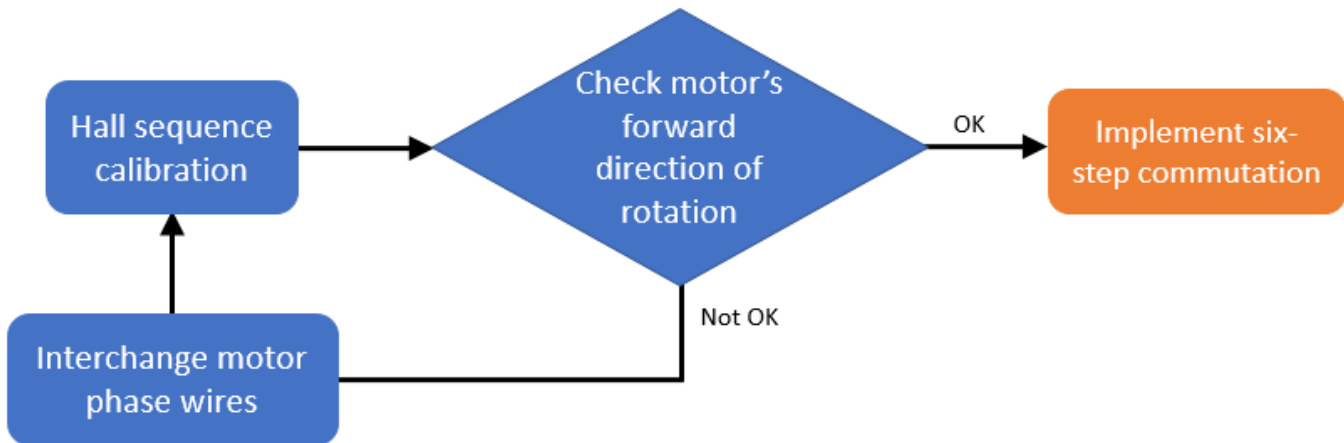
You can use the Scope in the host model to monitor the open-loop rotor position and Hall sequence values.

7. In the Host Serial Setup block mask in the host model, select a **Port name**.

8. Click **Run** on the **Simulation** tab to run the host model and start Hall sequence calibration for six-step commutation control. The motor runs and calibration begins when you start simulation. After the calibration process is complete, simulation ends and the motor stops automatically.

Note: If the motor does not start or rotate smoothly, increase the value of the **Vd Ref in Per Unit voltage** field (maximum value is 1) in the **Configuration** panel. However, if the motor draws high current, reduce this value.

As a convention, six-step commutation control uses a forward direction of rotation that is identical to the direction of rotation used during Hall sequence calibration. To change the forward direction convention, interchange the motor phase wires, perform Hall sequence calibration again, and then run the motor by using six-step commutation control.



9. See these LEDs on the host model to know the status of calibration process:

- The **Calibration in progress** LED turns orange when the motor starts running. Notice the rotor position and the variation in the Hall sequence value in the Scope (the position signal indicates a ramp signal with an amplitude between 0 and 1). After the calibration process is complete, this LED turns grey.
- The **Calibration complete** LED turns green when the calibration process is complete. Then the *Calibration Output* field displays the computed Hall sequence value.

Note: This example does not support simulation.

To immediately stop the motor during an emergency, click the **Emergency Motor Stop** button.

For examples that use six-step commutation using a Hall sensor, update the computed Hall sequence value in the *bldc.hallsequence* variable in the model initialization script linked to the example. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

Position Control of PMSM Using Quadrature Encoder

This example implements the field-oriented control (FOC) technique to control the position of a three-phase permanent magnet synchronous motor (PMSM). The FOC algorithm requires rotor position feedback, which it obtains from a quadrature encoder sensor.

You can use this example to implement position control applications by using closed-loop FOC. The example drives the motor to reach the input reference-position value. You can also configure the maximum number of rotations (in either direction) for the motor in the model initialization script.

For details about closed-loop FOC, see “Field-Oriented Control (FOC)” on page 4-2 and “Closed-Loop Motor Control” on page 6-10.

Model

The example includes the `mcb_pmsm_PosCtrl_f28379d` model.

You can use this model for both simulation and code generation. You can also open the Simulink® model using this command at the MATLAB® Command Window.

```
open_system('mcb_pmsm_PosCtrl_f28379d.slx');
```

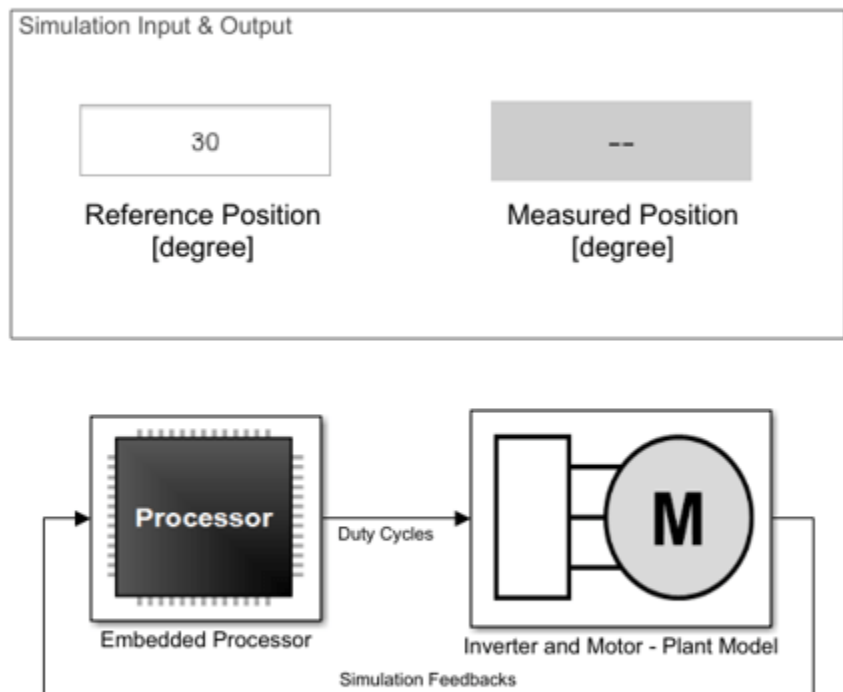
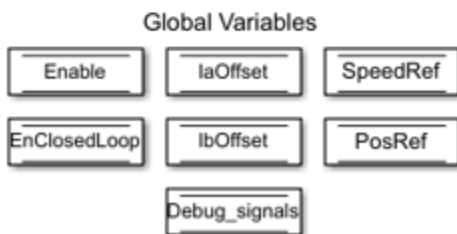
Permanent Magnet Synchronous Motor Position Control

HW Prerequisites

1. TI F8379D LaunchPad
2. BOOSTXL-DRV8305 Booster pack or BOOSTXL-3PhGaNIInv
3. PMSM motor with QEP sensor

Steps:

1. [Edit motor & inverter parameters](#)
2. Use [Offset computation model](#) to find out position offset.
3. Update offset in [Init script](#) to variable `'pmsm.PositionOffset'`
4. Click **Build, Deploy & Start** in the Hardware tab.
5. Control motor via [host model](#)
6. [Learn more](#) about this example



For details about the supported hardware configuration, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

- Motor Control Blockset™

To generate code and deploy model:

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
- Fixed-Point Designer™ (only needed for optimized code generation)

Prerequisites

1. Obtain the motor parameters. The Simulink® model uses default parameters that you can replace with values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188. The parameter estimation tool updates the `motorParam` variable (in the MATLAB® workspace) with the estimated motor parameters.

2. Update motor parameters. If you obtain the motor parameters from the datasheet or from other sources, update the motor and inverter parameters in the model initialization script associated with the Simulink® model. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts the motor parameters from the updated `motorParam` workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

- 1.** Open the model included with this example.
- 2.** Click **Run** on the **Simulation** tab to simulate the model.
- 3.** Click **Data Inspector** in the **Review Results** section to view and analyze the simulation results.

Generate Code and Deploy Model to Target Hardware

This section shows how to generate code and run the FOC algorithm on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you can run the host model on the host computer, deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model from the MATLAB® command prompt.

LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter:
mcb_pmsm_PosCtrl_f28379d

Note: When using the BOOSTXL-3PHGANINV inverter, ensure that you have proper insulation between the bottom layer of BOOSTXL-3PHGANINV and the LAUNCHXL board.

For connections related to this hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

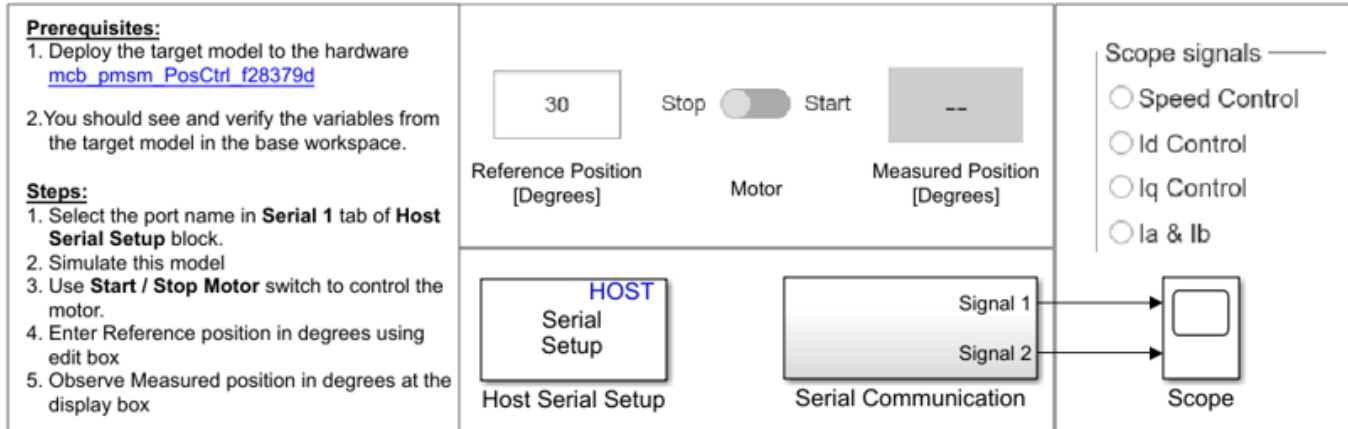
1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model by default computes the ADC offset values for phase current measurement. To disable this functionality, update the value of the `inverter.ADCOffsetCalibEnable` variable in the model initialization script to 0.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization script. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the model initialization script associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.
5. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.
6. Load a sample program to CPU2 of the LAUNCHXL-F28379D board. For example, load the program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`). This ensures that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.
7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.
8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_pmsm_host_model_PosCtrl.slx');
```

Position Control Host



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For details on serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. In the dialog of the Host Serial Setup block in the host model, select a **Port name**.

10. Update the Reference Position [Degrees] value in the host model. By default, the maximum number of rotations (in either the positive or negative direction) is five. You can change this value by setting the `PosCtrlPosLimit` variable in the model initialization script. You can open this script by using the hyperlink named **Init script** in the target model.

Maximum rotation limit (degrees) = `PosCtrlPosLimit` x 360

Note: You cannot control the speed of rotation of the motor, but you can limit it by setting the `PosCtrlSpeedLimit` variable (in per-units). For details about the per-unit system, see “Per-Unit System” on page 6-16.

11. Click **Run** on the **Simulation** tab to run the host model.

12. Change the position of the Start / Stop Motor switch to Start, to start running the motor.

13. Observe the debug signals from the RX subsystem, in the Time Scope of host model. You can select the debug signals that you want to monitor in the **Scope signals** section of the host model.

- **Speed Control** - Display speed reference and speed feedback signals in the scope.
- **Id Control** - Display Id reference and Id feedback signals in the scope.
- **Iq Control** - Display Iq reference and Iq feedback signals in the scope.
- **Ia & Ib** - Display Ia and Ib current signals in the scope.
- **Position Control** - Display position reference and position feedback signals in the scope.

Integrate MCU Scheduling and Peripherals in Motor Control Application

This example shows how to identify and resolve issues with respect to peripheral settings and task scheduling early during development.

The following are typical challenges associated with MCU peripherals and scheduling:

- ADC-PWM synchronization to achieve current sensing at mid point of PWM period
- Incorporate sensor delays to achieve the desired controller response for the closed loop system
- Studying different PWM settings while designing special algorithms

This example shows how to use SoC Blockset to address these challenges for a motor control closed-loop application in simulation and verify on hardware by deploying on to the TI Delfino F28379D LaunchPad.

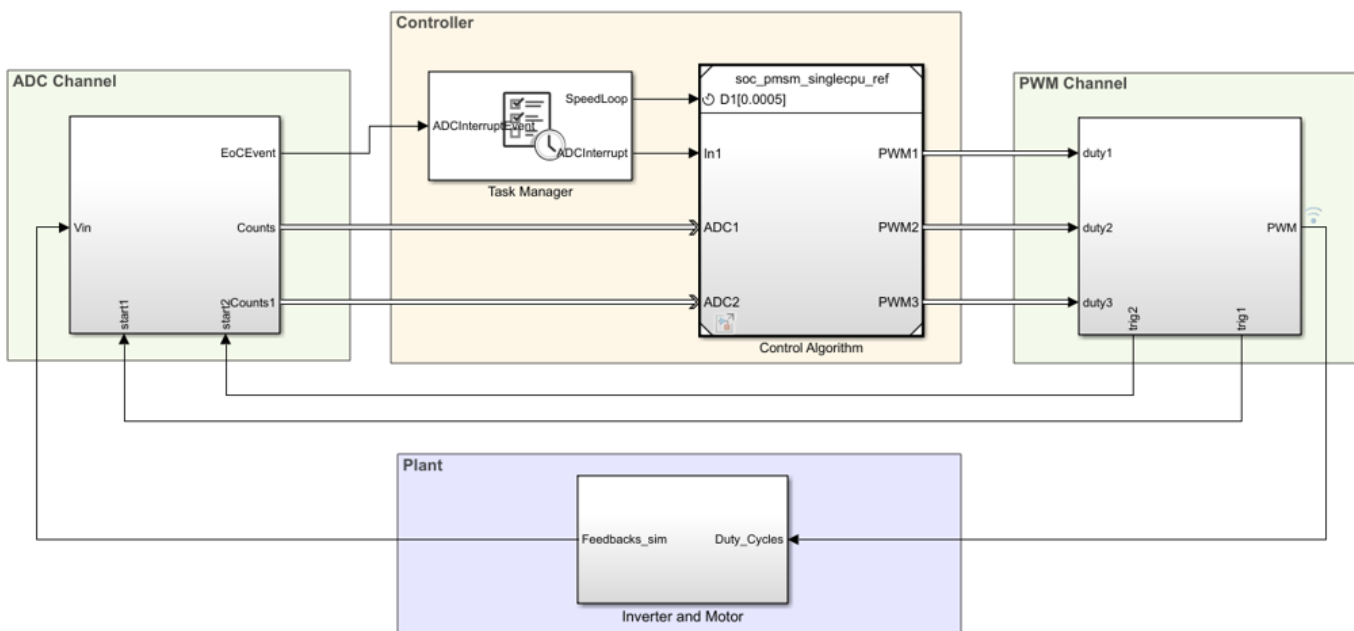
Required hardware:

- TI Delfino F28379D LaunchPad or TI Delfino F2837xD based board
- BOOSTXL-DRV8305EVM motor driver board
- Teknic M-2310P-LN-04K PMSM motor

Model Structure

```
open_system('soc_pmsm_singlecpu_foc');
```

Field Oriented Control In Single CPU



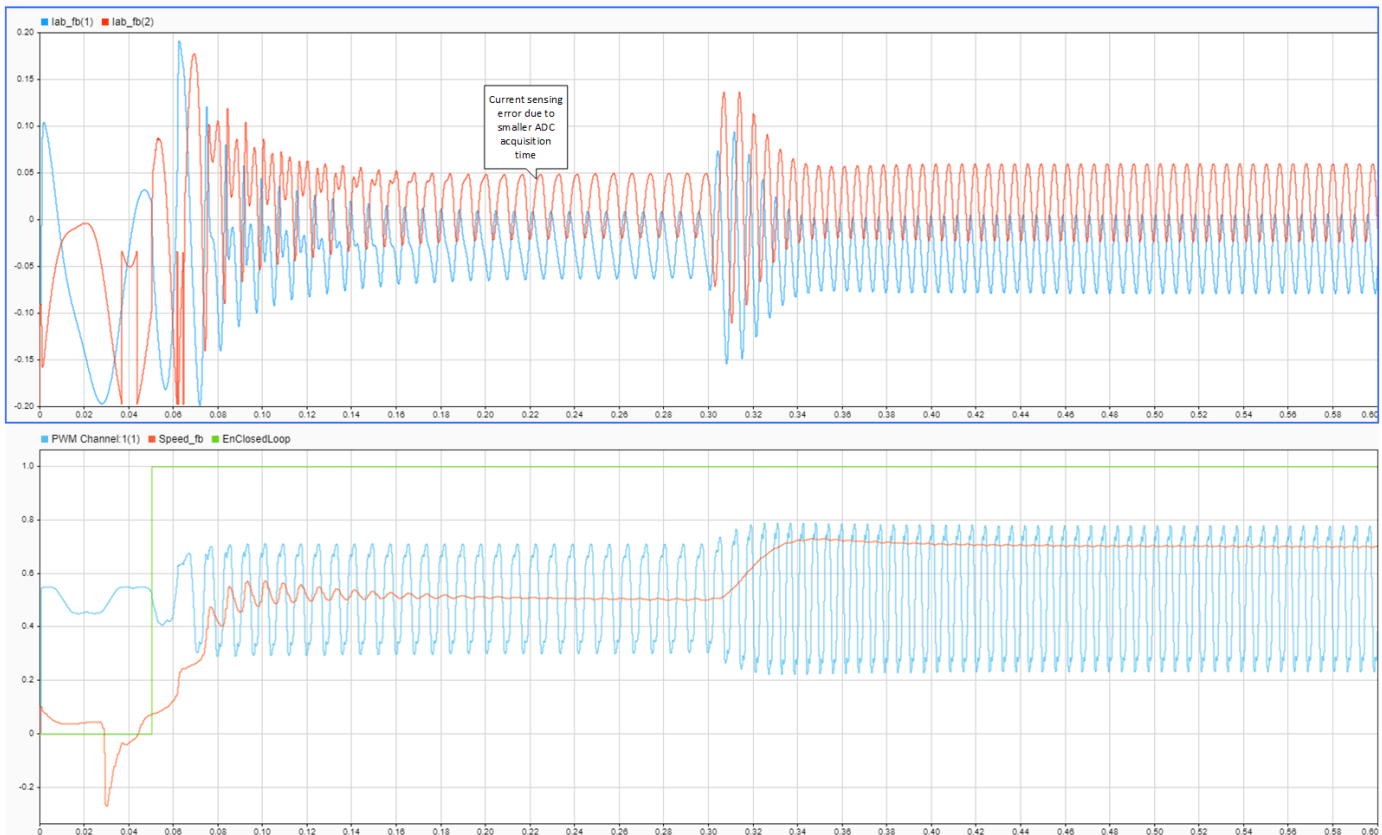
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Open the `soc_pmsm_singlecpu_foc` model. This model simulates single CPU motor controller, contained in `soc_pmsm_singlecpu_ref` model, for a Permanent magnet synchronous motor inverter system. Controller senses the outputs from the plant using ADC Interface (SoC Blockset) and actuates using PWM Interface (SoC Blockset) that drives the inverter. Algorithm blocks from Motor Control Blockset™ is used in this example.

ADC Acquisition Time

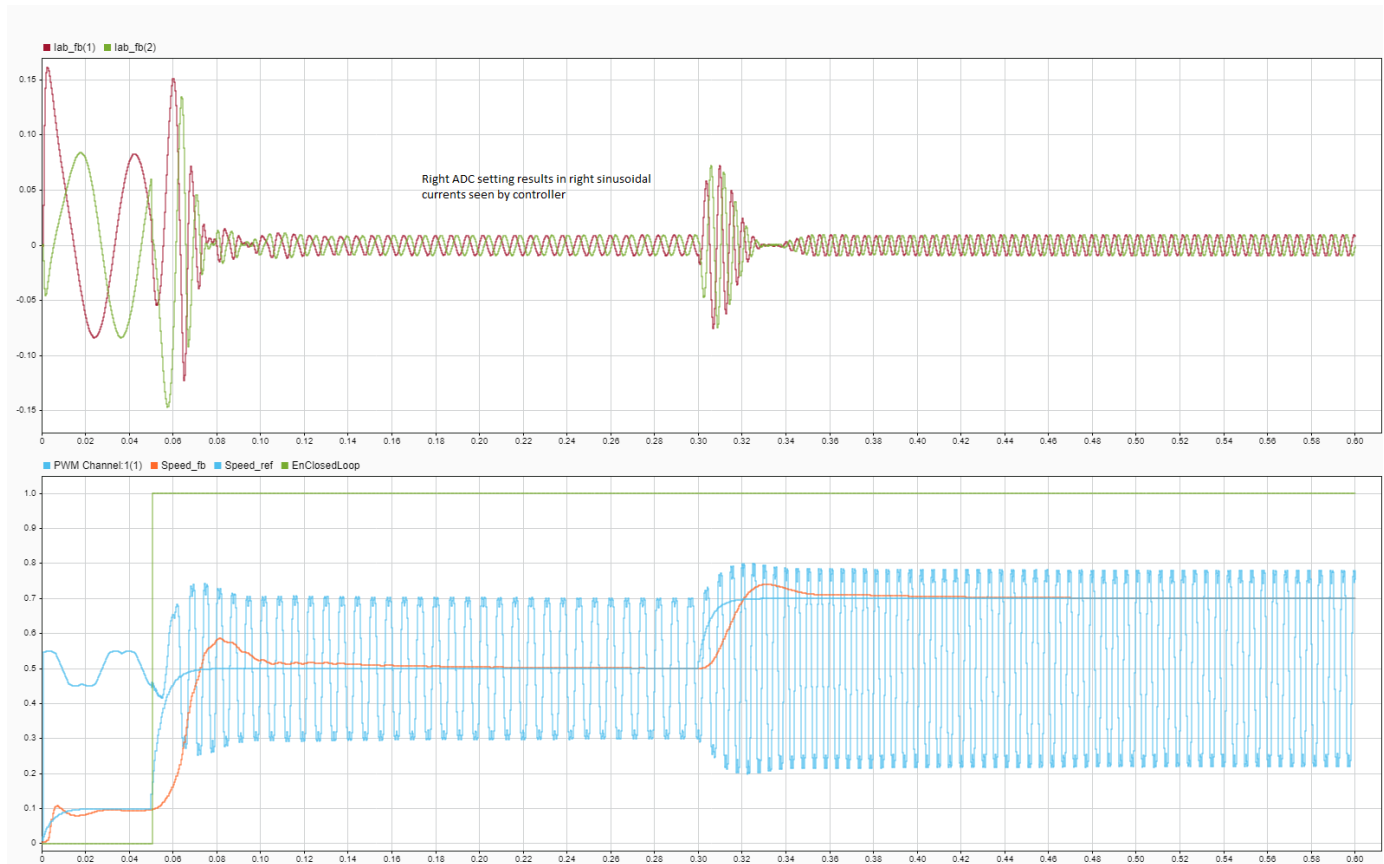
ADC hardware contains a sample and hold circuit to sense the analog inputs. To ensure complete ADC measurement, the minimum acquisition time must be selected to account for the combined effects of input circuit and the capacitor in the sample and hold circuit.

Open ADC Interface block and change the default acquisition time to 100ns. Run the simulation and view the results in Simulation Data Inspector and observe there is a distortion in current waveforms. The low acquisition time resulted in ADC measurements not reaching their true value. As a result, the controller reacts by generating a relative duty cycle causing variations in current drawn by the motor. These figures show the reaction to the incorrect ADC measurement and overdraw in the phase A current channel, with phase A current in blue and phase B current in orange. The simulated speed feedback shows significant oscillations during open loop to closed loop transition, which in real world will halt the motor.



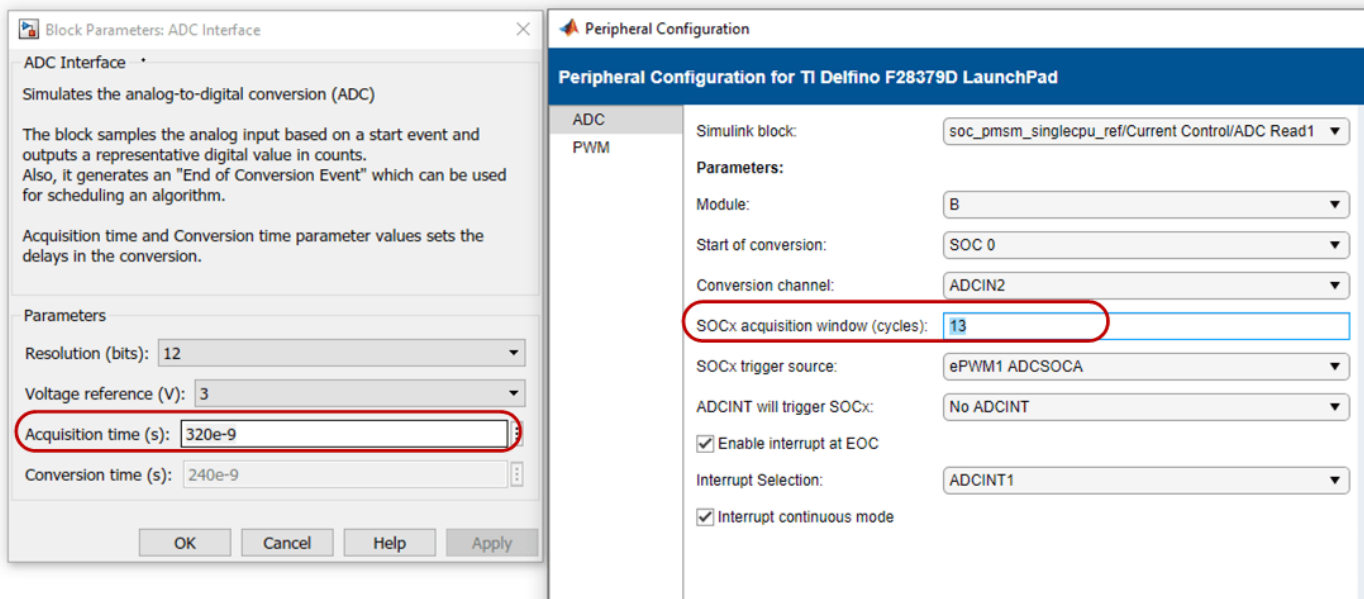
To fix this issue, open ADC Interface blocks change and change acquisition time to a larger value, 320ns. This value is the minimum ADC acquisition time recommended in Table 5-42 of the TI Delfino F28379D LaunchPad data sheet. Run the simulation and view the results in Simulation Data

Inspector. This figure shows the accurately sampled ADC values and the controller tracking the reference value as expected.

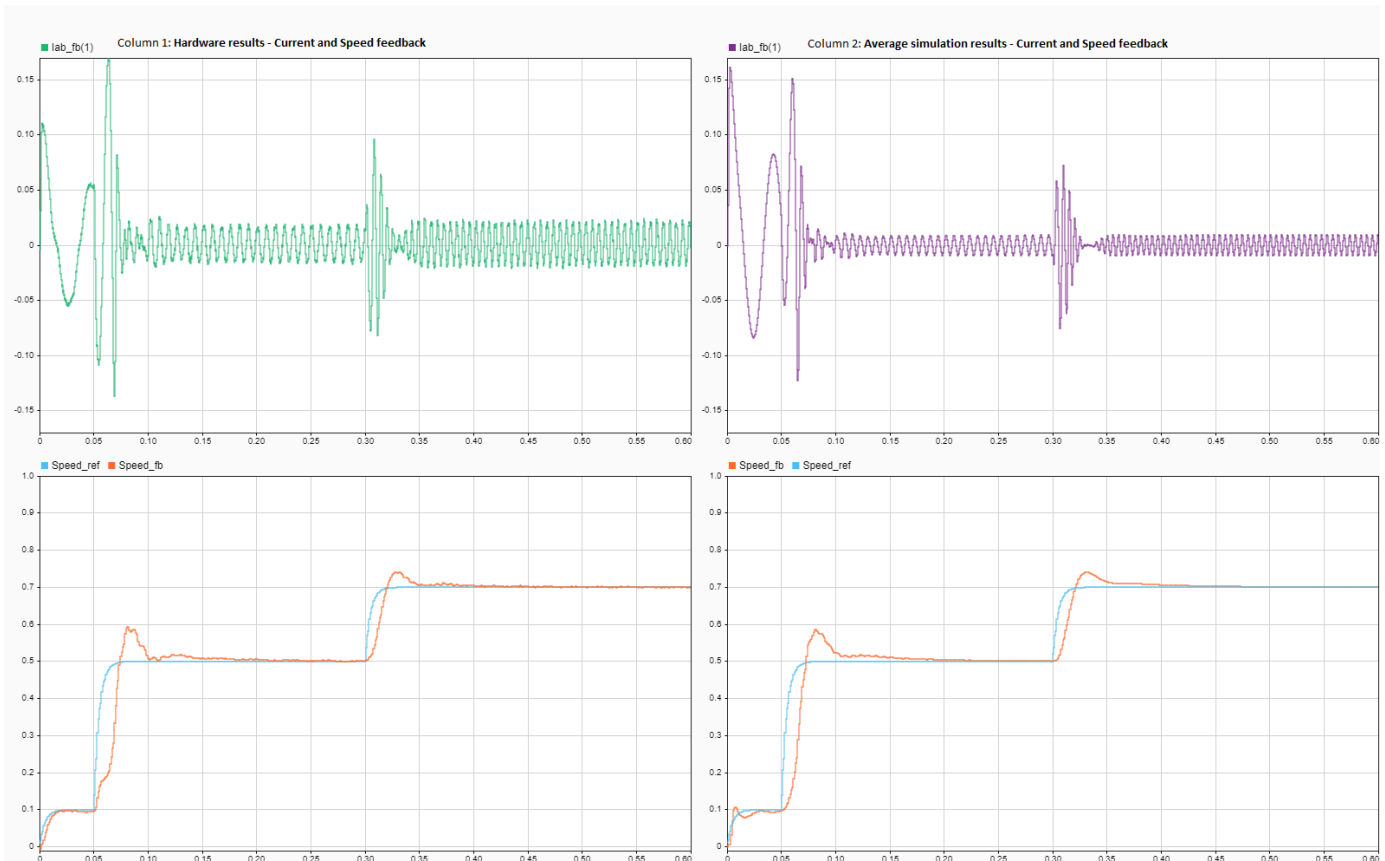


Verify simulation results against hardware by deploying the model to the TI Delfino F28379D LaunchPad. On the **System on Chip** tab, click **Configure, Build, & Deploy** to open the SoC Builder (SoC Blockset) tool.

In the SoC Builder tool, on **Peripheral Configuration** tool, set **ADC > SOCx acquisition window cycles** parameter to 13 ADC clock ticks for the ADC B and C modules. The ADC acquisition clock ticks parameter must be set to the simulation time value, set in the ADC Interface block, multiplied by the ADC clock frequency. You can get the ADC clock frequency from the model hardware settings. Open the soc_pmsm_singlecpu_ref model. On the **System on Chip** tab, click **Hardware Settings** to open the **Configuration Parameters** window. In the **Hardware Implementation > Target hardware resources > ADC_x** section, you can see the ADC clock frequency in MHz parameter value. This figure shows the ADC Interface block setting for simulation and peripheral app setting for deployment. Use same setting in simulation and codegen to ensure expected behavior.

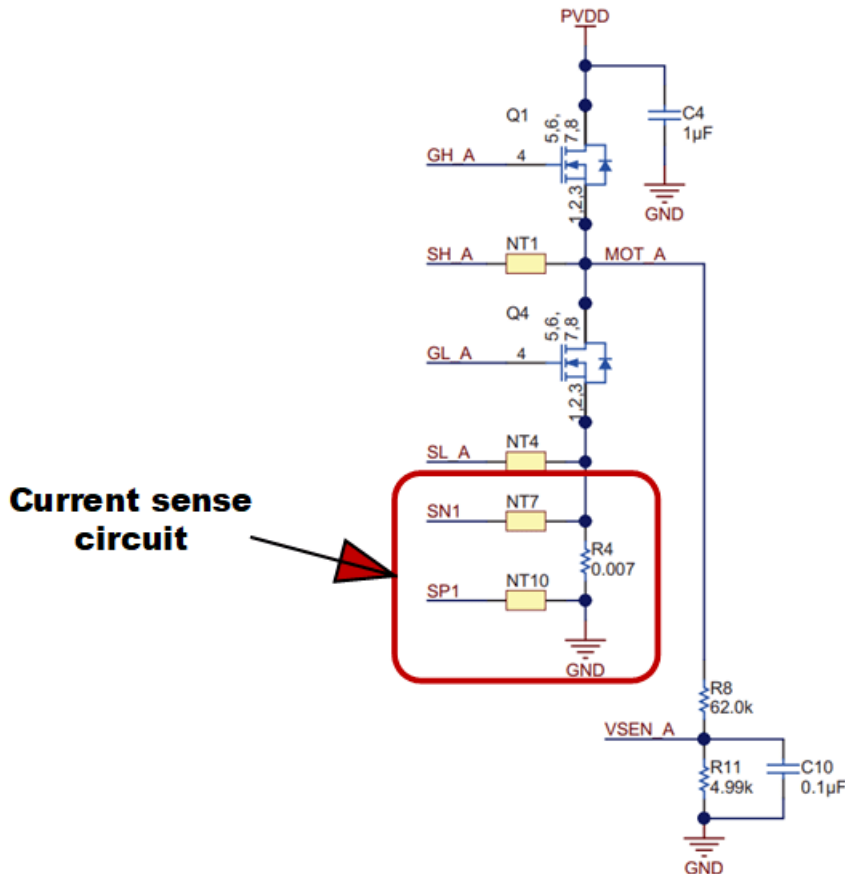


On **Select Build Action** page, to monitor data from hardware select **Build** and load for **External** mode. This figure shows the data from hardware with accurately sampled ADC values and the controller tracking the reference value as expected.



ADC-PWM Synchronization

The BOOSTXL-DRV8305EVM motor driver has a 3-phase inverter built using 6 power MOSFETS. This motor driver board uses a low-side shunt resistor to sense motor currents. The Current sense circuit amplifies the voltage drop across the shunt. This setup ensures low power dissipation, since the current only flows through the shunt when the bottom switches are on and away from PWM commutation noise. This figure shows the low-side shunt resistor circuit in BOOSTXL-DRV8305EVM motor drive.



For correct operation, current sensing must occur during the mid point of the PWM period when ADCs trigger. Specifically, the PWM counter must be at the maximum value when the bottom switches are active in the Up-Down counter mode. Current sampling at a different instance results in a measured currents of zero.

To analyze this case, switch the model to **high fidelity inverter simulation** mode. Change the plant variant to use detailed MOSFET based 3-phase inverter to replicate BOOSTXL-DRV8305EVM.

```
set_param('soc_pmsm_singlecpu_foc/Inverter and Motor/Average or Switching', ...
'LabelModeActivechoice', 'SwitchingInverter');
```

Change the Output mode parameter of PWM Interface (SoC Blockset) to Switching and connect 6 PWMs to the Mux block.

```
set_param('soc_pmsm_singlecpu_foc/PWM Channel/PWM Interface', 'OutSigMode', 'Switching');
set_param('soc_pmsm_singlecpu_foc/PWM Channel/PWM Interface1', 'OutSigMode', 'Switching');
set_param('soc_pmsm_singlecpu_foc/PWM Channel/PWM Interface2', 'OutSigMode', 'Switching');
```

Delete existing connection between PWM Interface block and Mux.

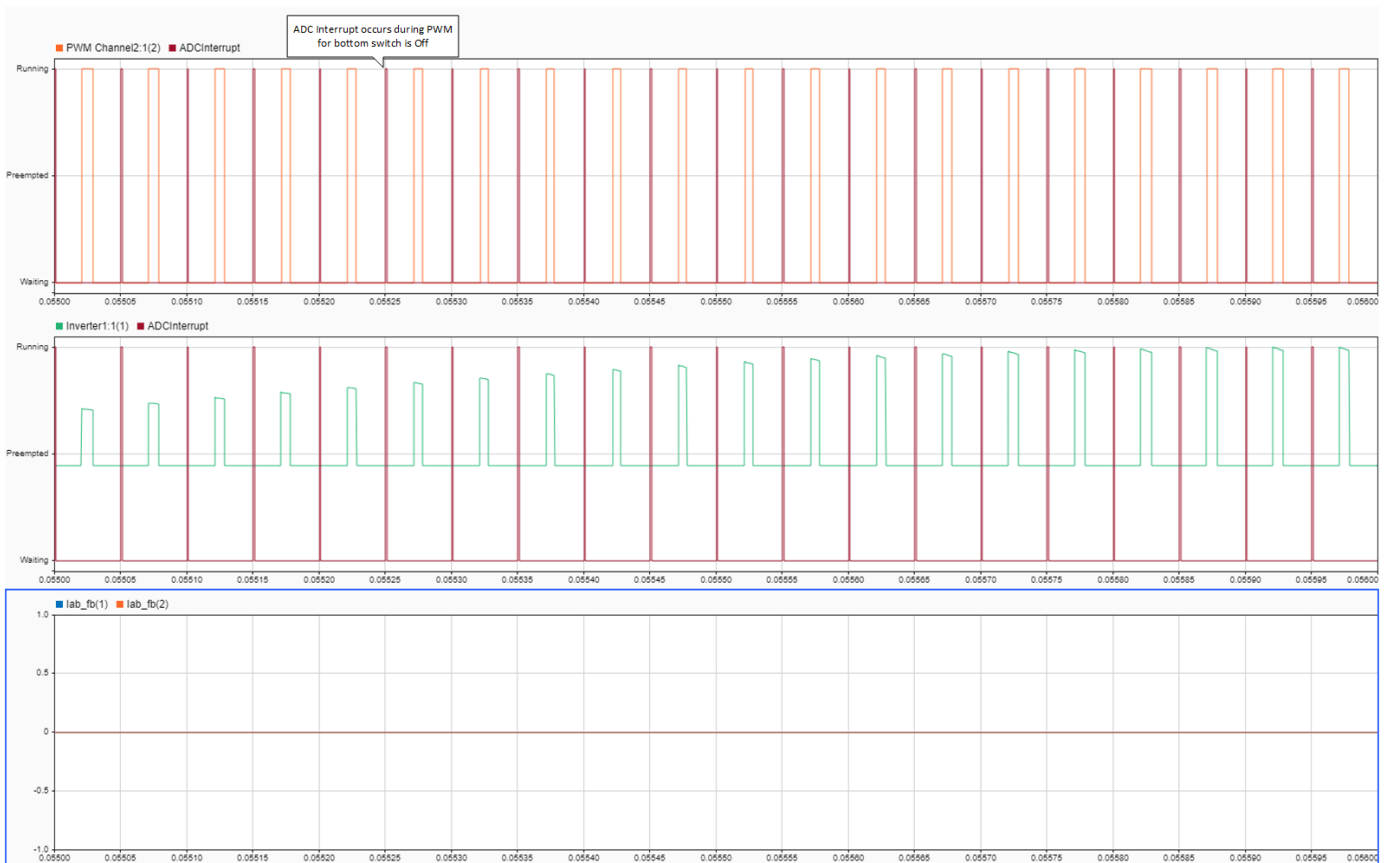
```
h = get_param('soc_pmsm_singlecpu_foc/PWM Channel/Mux', 'LineHandles');
delete_line(h.Inport);
```

As a last step, connect 6 PWM outputs to Mux.

```
set_param('soc_pmsm_singlecpu_foc/PWM Channel/Mux', 'Inputs', '6');

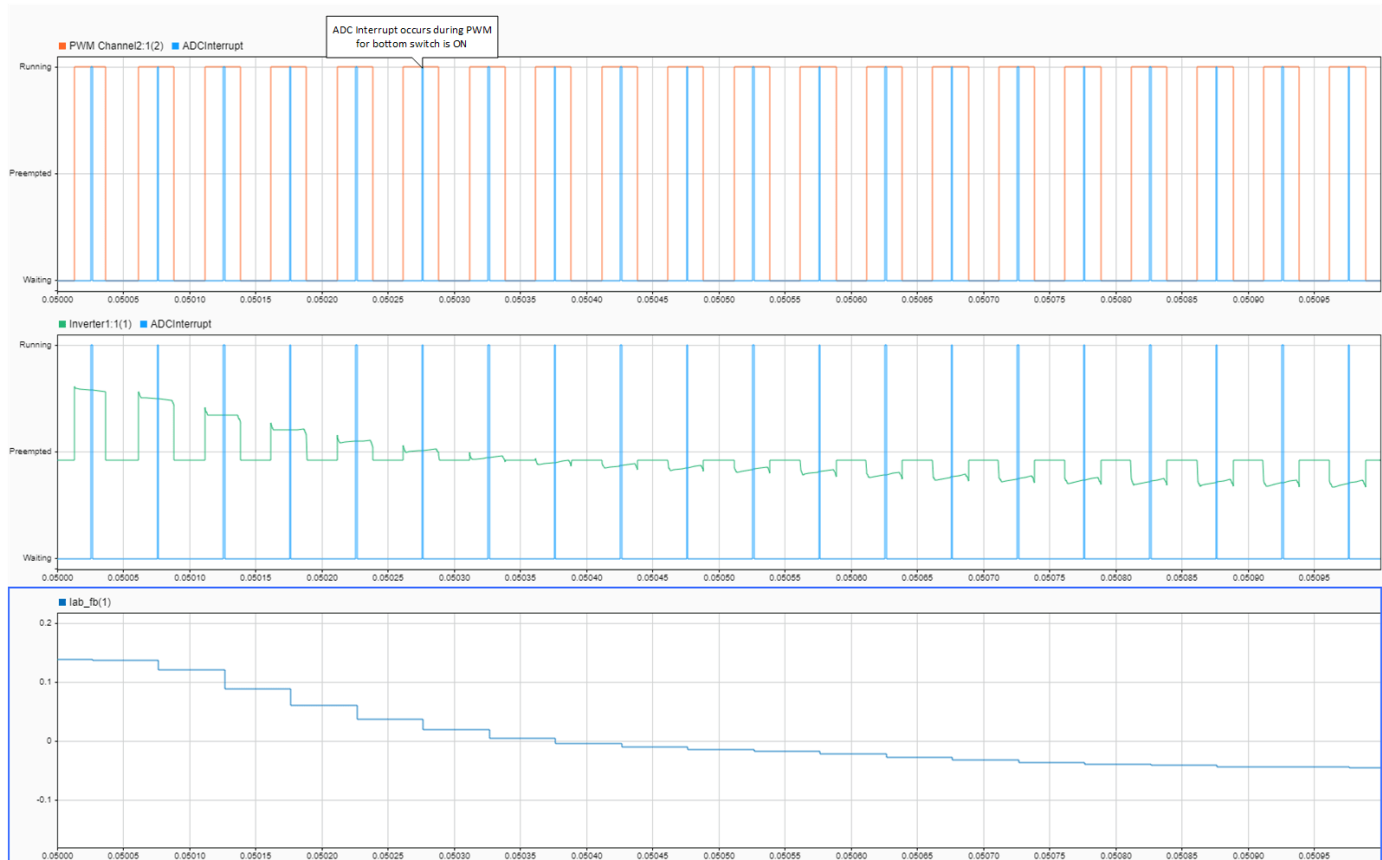
add_line('soc_pmsm_singlecpu_foc/PWM Channel', ...
{'PWM Interface/1', 'PWM Interface/2', 'PWM Interface1/1', ...
'PWM Interface1/2', 'PWM Interface2/1', 'PWM Interface2/2'}, ...
{'Mux/1', 'Mux/2', 'Mux/3', 'Mux/4', 'Mux/5', 'Mux/6'}, 'autorouting', 'smart');
```

Open the PWM Interface blocks and set **Event trigger mode** to End of PWM period. Run the simulation and view the results in Simulation Data Inspector. In the figure, phase A and phase B currents are approximately zero current. This results in a loss of feedback and no actuation in the control loop. Select **Enable task simulation** in Task Manager block to simulate and visualize tasks in Simulation Data Inspector.

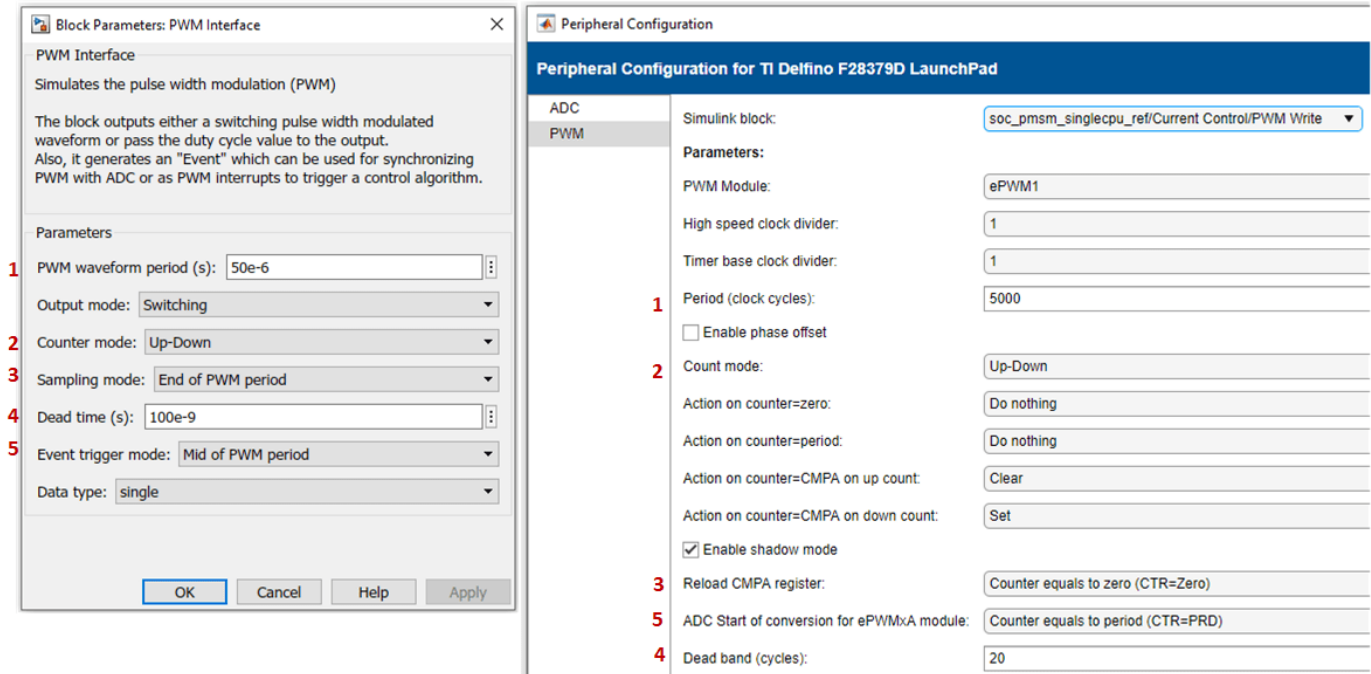


4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)

To fix this issue, change the **Event trigger mode** to Mid point of PWM period, equivalent to the PWM internal counter being at a maximum. Run the simulation and view the results in Simulation Data Inspector.

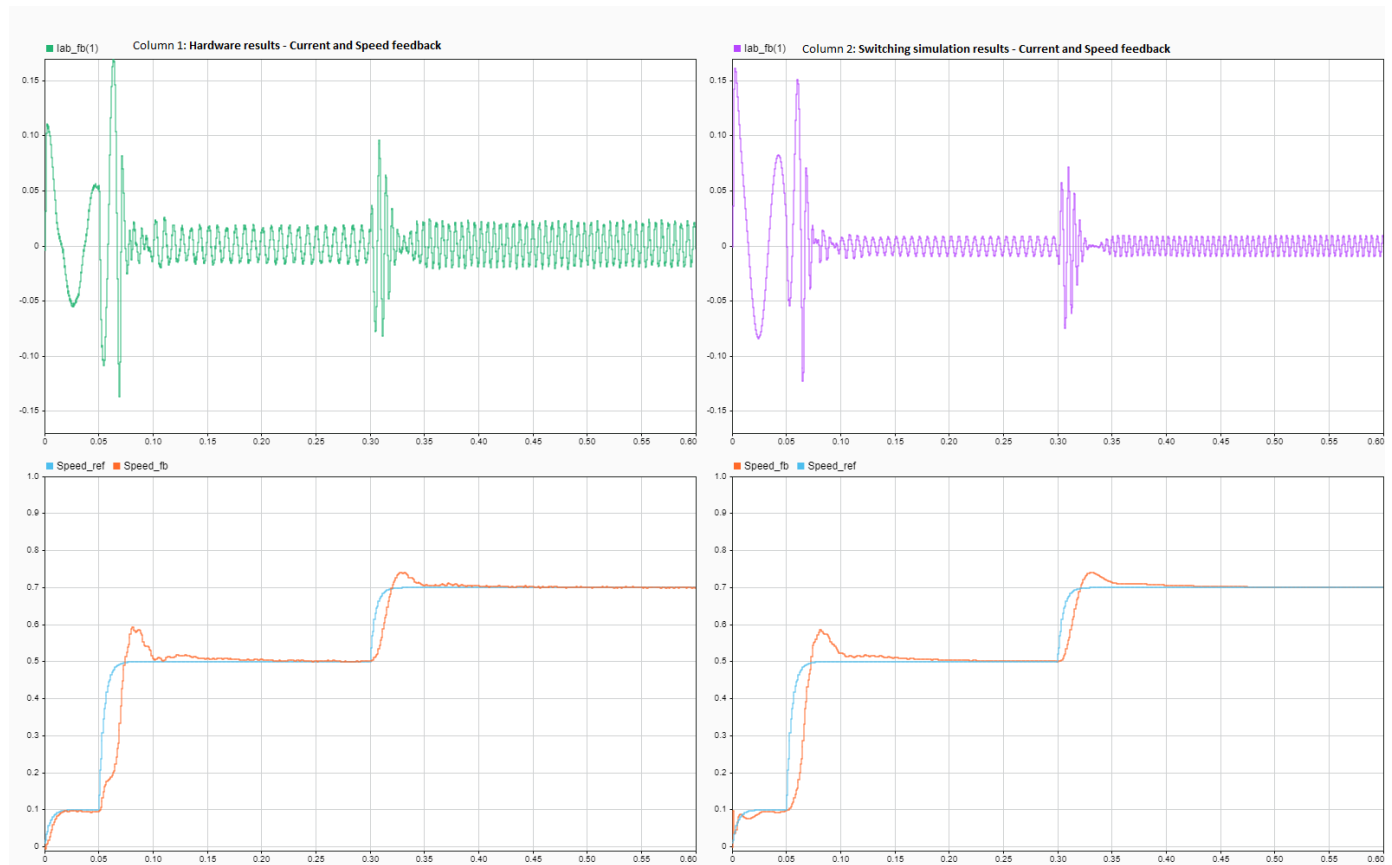


Deploy the model on to the TI Delfino F28379D LaunchPad using the SoC Builder (SoC Blockset) tool. In the SoC Builder tool, on **Peripheral configuration** tool, set **PWM event condition** to Counter equals to period. Use same setting in simulation and codegen to ensure expected behavior. This figure shows the PWM Interface block setting for simulation and the Peripheral Configuration tool setting for deployment.



This figure shows the data from simulation and hardware with correct ADC-PWM synchronization and the controller tracking the reference value as expected.

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



See Also

- “Get Started with SoC Blocks on MCUs” (SoC Blockset)
- “Partition Motor Control for Multiprocessor MCUs” on page 4-141

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Partition Motor Control for Multiprocessor MCUs

This example shows how to partition real-time motor control application on to multiple processors to achieve design modularity and improved control performance.

Many MCUs provide multiple processor cores. These additional cores can be leveraged to achieve a variety of design goals:

- Divide the application into real-time tasks, such as control laws, and non-real time tasks, such as external communication, diagnostics, or machine learning
- Partition the control algorithm to run on multiple CPUs to achieve higher loop rate
- Run the same application in multiple CPUs for safety critical applications

This example shows how to partition motor control application across two CPUs of the TI Delfino F28379D to achieve higher sampling time/PWM frequency.

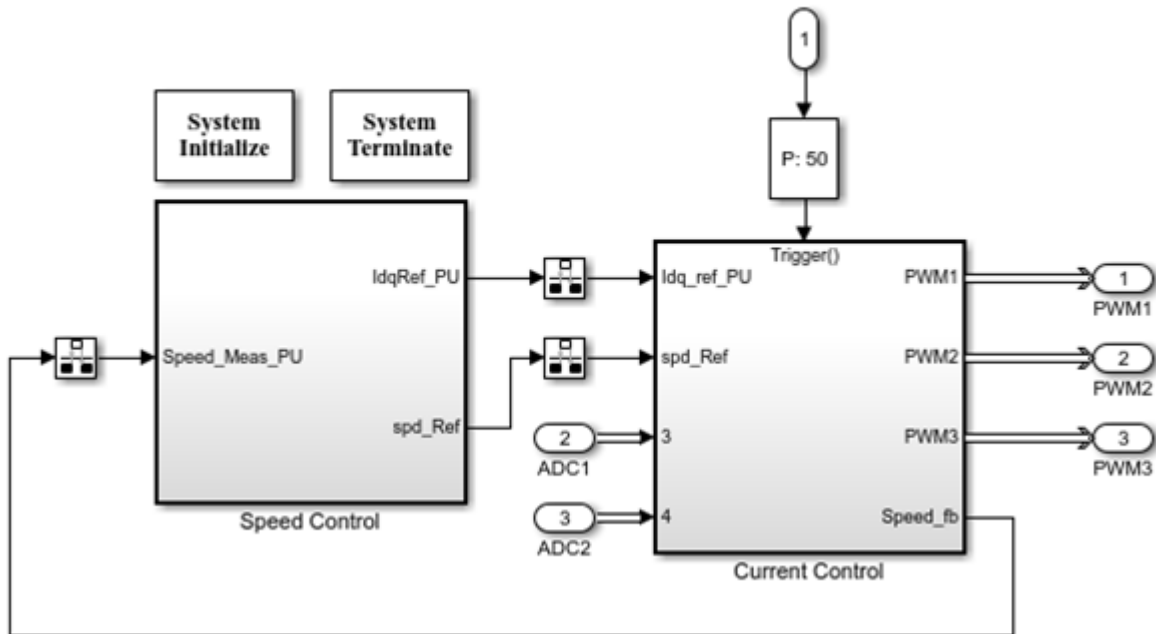
Required hardware:

- TI Delfino F28379D LaunchPad or TI Delfino F2837xD based board
- BOOSTXL-DRV8305EVM motor driver board
- Teknic M-2310P-LN-04K PMSM motor

Partition Motor Control Algorithm

Open the `soc_pmsm_singlecpu_foc` model. This model simulates a single CPU motor controller, contained in the `soc_pmsm_singlecpu_ref` model, for a permanent magnet synchronous machine (PMSM).

Permanent Magnet Synchronous Motor Field Oriented Control

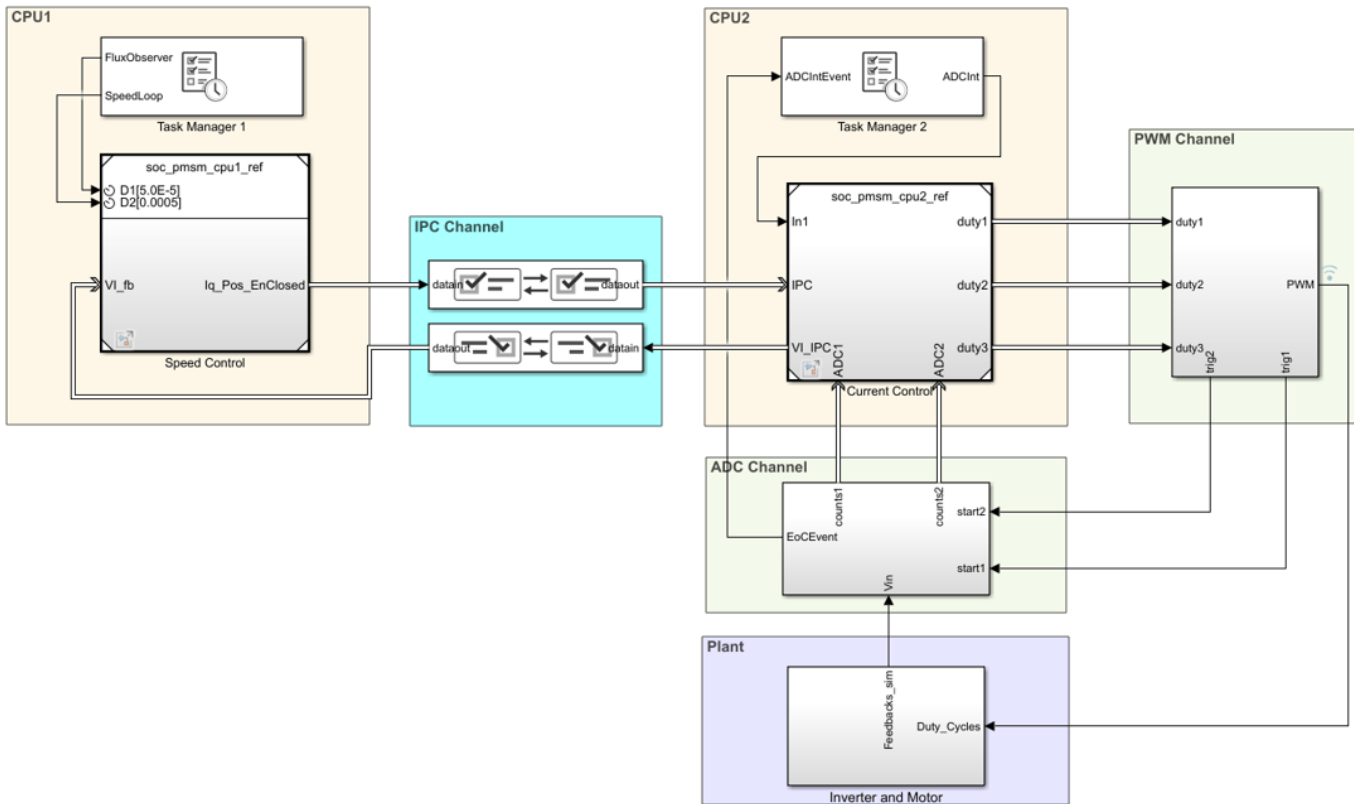


We partition the control algorithm by executing current control on CPU2, and speed control and position estimation on CPU1 respectively. Data transfer between the CPU's are handled by Interprocess Data Channel block. For more information see "Interprocess Data Communication via Dedicated Hardware Peripheral" (SoC Blockset).

Open the `soc_pmsm_dualcpu_foc` model.

```
open_system('soc_pmsm_dualcpu_foc');
```


Field-Oriented Control on Dual CPU Processor

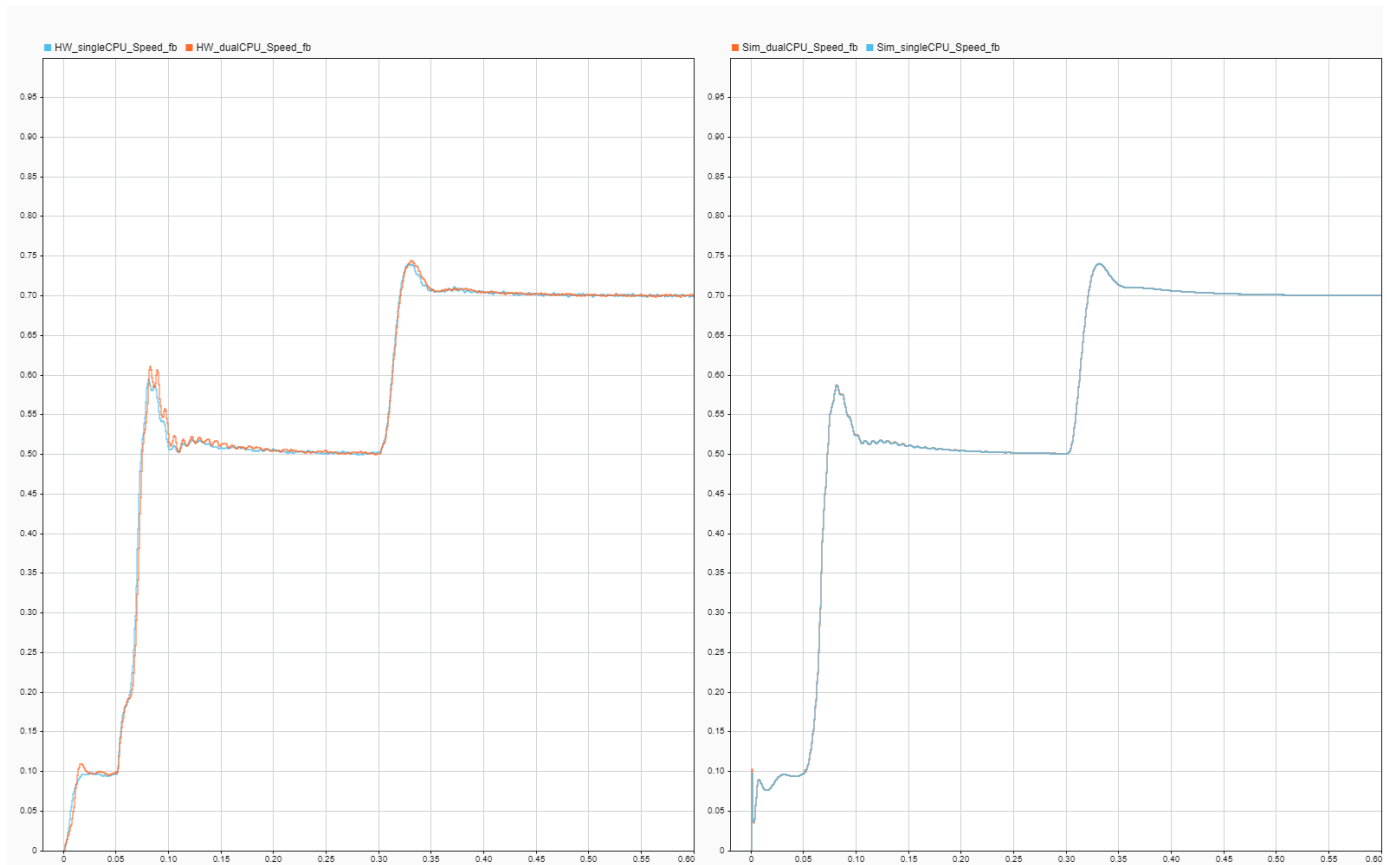


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On the **System on Chip** tab, click **Hardware Settings** to open the **Configuration Parameters** window. In the **Hardware Implementation** tab, the **Processing Unit** parameter is configured to "None" indicating it is the top-level system model.

Open the soc_pmsm_cpu1_ref model and open the soc_pmsm_cpu2_ref model to view algorithms configured for each CPU. Model references contained within the system model are configured to run on c28xCPU1 (CPU1) and c28xCPU2 (CPU2).

On the Simulation tab, click 'Run' to simulate the model. Open the Simulation Data Inspector and view signals. This figure shows results from the single and dual CPU models in simulation and deployment.



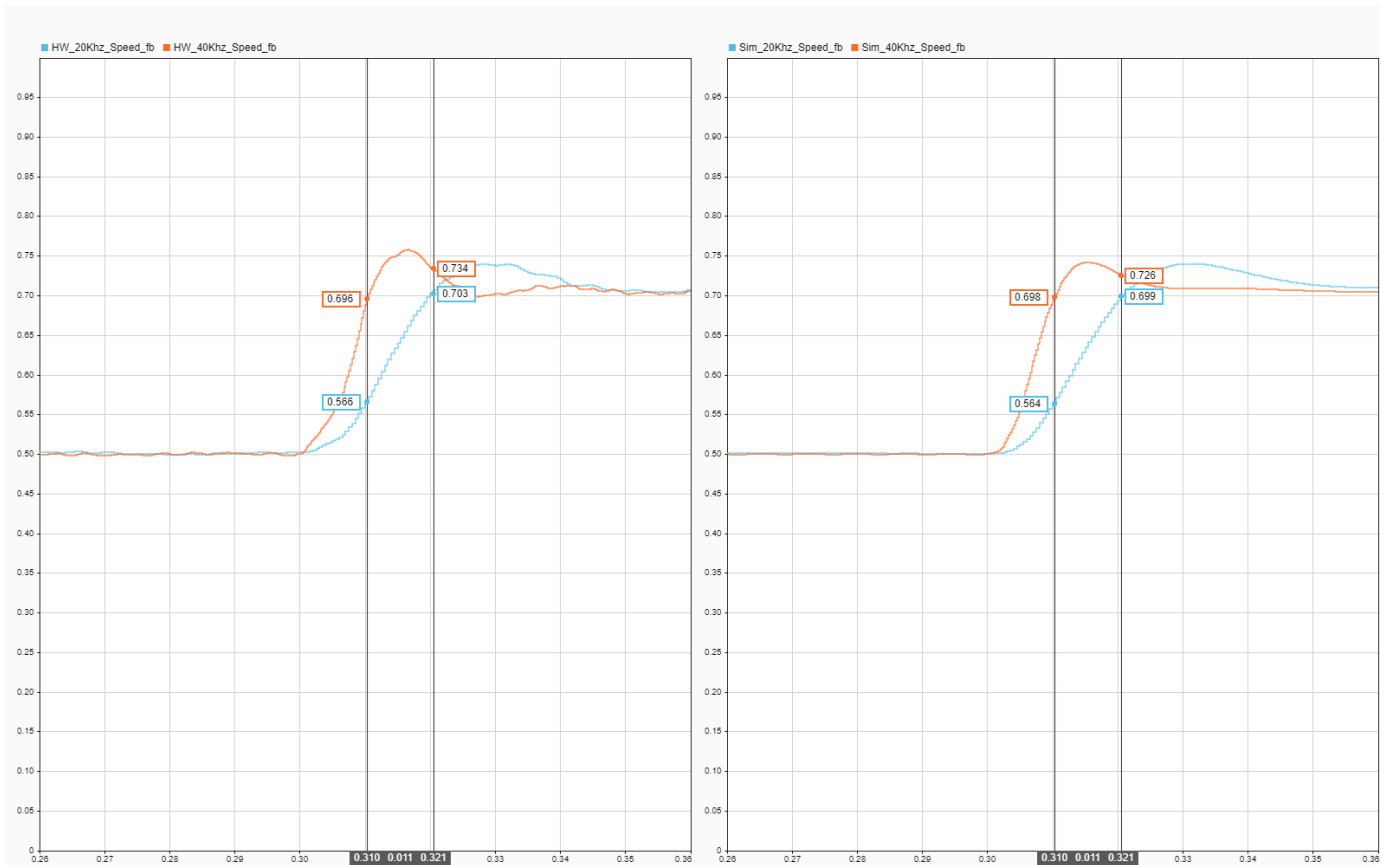
Performance Improvement with Concurrent Execution

Using both CPUs to execute control algorithms allows us to achieve higher controller bandwidth. In the original single CPU model, the control algorithm takes just over 25 μ s to execute. To provide a safety margin, single CPU model uses a PWM frequency of 20kHz, equivalent to 50 μ s period.

After partitioning, the CPU1 and CPU2 execution times reduce to less than 20 μ s. Allowing the PWM frequency to be increase to 40kHz. In the `mcb_pmsm_foc_sensorless_f28379d_data.m` script, set `PWM_frequency` to `40e3` and run the script to configure the model to the new PWM frequency. With faster sampling of currents, controller gains can then be tuned to achieve faster response times.

Deploy the model to the TI Delfino F28379D LaunchPad using the SoC Builder (SoC Blockset) tool. To open the tool, on the **System on Chip** tab, click **Configure, Build, & Deploy**, and follow the guided steps.

This figure shows the controller response from simulation and deployment at 25 μ s current loop with 40kHz PWM frequency compared with 50 μ s current loop at 20kHz frequency. As expected, the rise time in speed improves with faster current loop by approximately 50 percent.



Speed response is oscillatory because of sensorless algorithm, for more information see “Sensorless Field-Oriented Control of PMSM” on page 4-57

For higher simulation granularity, set the PWM Interface block output to Switching Mode and change the plant model variant to use the MOSFET simulation.

See Also

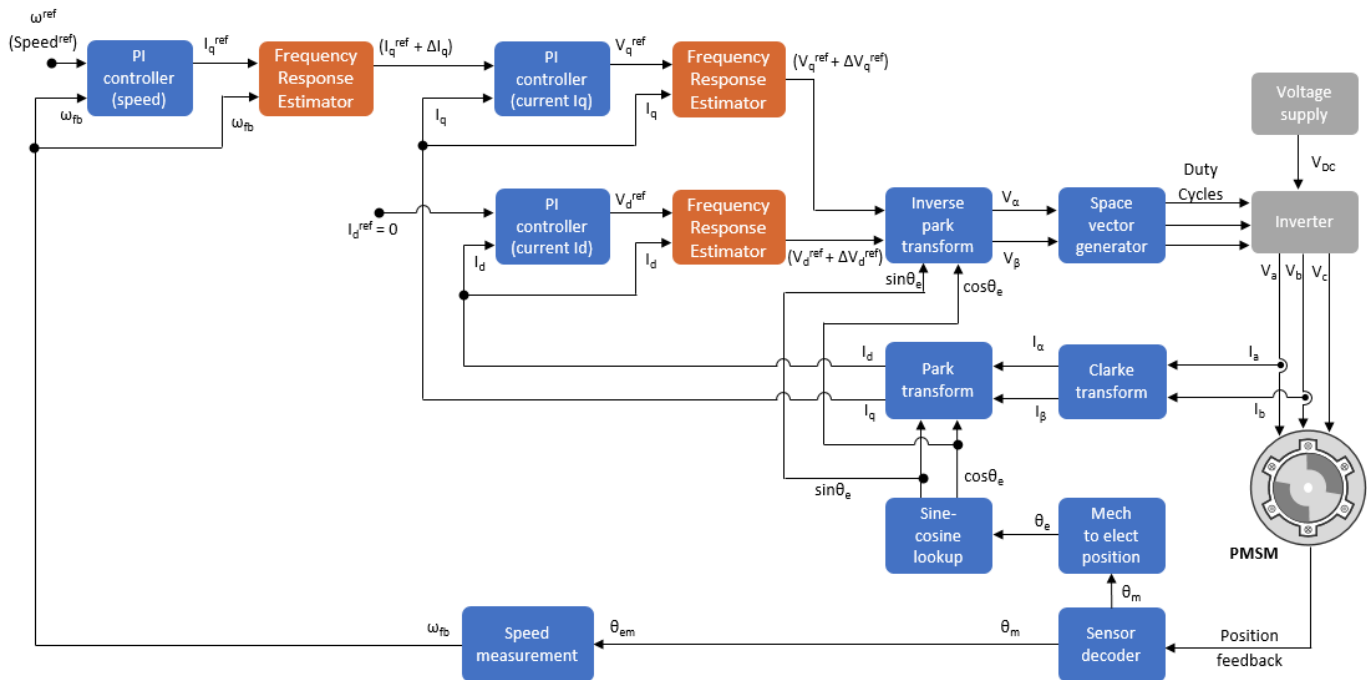
- “Get Started with SoC Blocks on MCUs” (SoC Blockset)
- “Integrate MCU Scheduling and Peripherals in Motor Control Application” on page 4-132

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Frequency Response Estimation of PMSM Using Field-Oriented Control

This example performs frequency response estimation (FRE) of a plant model running a three-phase permanent magnet synchronous motor (PMSM). When you simulate or run the model on the target hardware, the model runs tests to estimate the frequency response as seen by each PI controller (also known as raw FRE data) and plots the FRE data to provide a graphical representation of the plant model dynamics.

When the motor runs in a steady state, the online Frequency Response Estimator block that is connected to each PI control loop (I_d current, I_q current, and speed) sequentially perturbs the PI controller output and estimates the frequency response of the plant model as seen by each PI controller. You can use the frequency response of the plant to estimate the PI controller gains.



The model uses the field-oriented control (FOC) technique to control the PMSM. The FOC algorithm requires rotor position feedback, which is obtained by a quadrature encoder sensor. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

Models

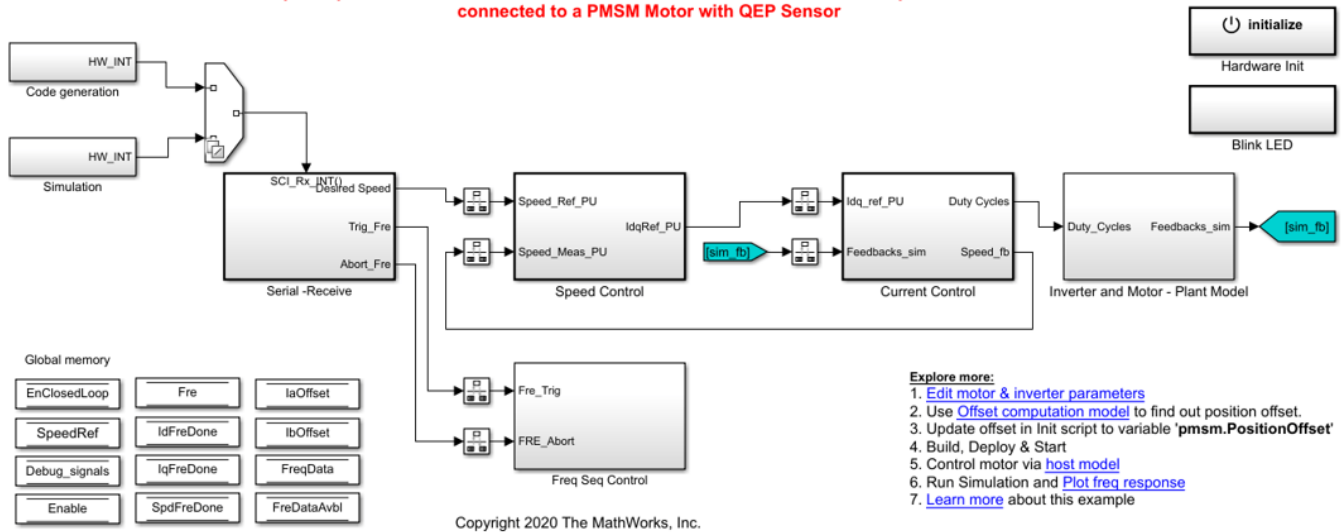
The example includes the model (target model) `mcb_pmsm_freq_est_f28379d`.

You can use this model for both simulation and code generation. You can also use the `open_system` command to open the model.

```
open_system('mcb_pmsm_freq_est_f28379d.slx');
```

Permanent Magnet Synchronous Motor Field Oriented Control

Note: This example requires a TI F28379D LaunchPad with a BOOSTXL-DRV8305 booster pack or BOOSTXL-3PhGaNIInv connected to a PMSM Motor with QEP Sensor



For details regarding the supported hardware configuration, see the Required Hardware topic in the Generate Code and Deploy Model to Target Hardware section.

Required MathWorks® Products

To simulate model:

- Motor Control Blockset™
- Simulink Control Design™

To generate code and deploy model:

1. Motor Control Blockset™
2. Embedded Coder®
3. Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
4. Simulink Control Design™

Prerequisites

1. Obtain the motor parameters. The Simulink® model uses default motor parameters that you can replace with the values from either the motor datasheet or other sources.

However, if you have the motor control hardware, you can estimate the parameters for the motor that you want to use by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the motorParam variable (in the MATLAB® workspace) with the estimated motor parameters.

2. If you obtain the motor parameters from the datasheet or other sources, update the motor parameters and inverter parameters in the model initialization script associated with the Simulink® models. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts motor parameters from the updated `motorParam` workspace variable.

Simulate Model

This example supports simulation. Follow these steps to simulate the model.

1. Open the target model included with this example.
2. Click **Run** on the **Simulation** tab to simulate the model.
3. Click **Data Inspector** on the **Simulation** tab to view and analyze the simulation results.
4. On the target model, click the **Plot freq response** hyperlink to plot the frequency response data of the plant model (`sys_sim_id`, `sys_sim_iq`, and `sys_sim_spd` variables in the workspace) that the speed control loop and the current control loops measure.

Generate Code and Deploy Model to Target Hardware

This section shows you how to generate code, run the FOC algorithm on the target hardware, start frequency response estimation, and plot the FRE data.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. The prerequisite to use the host model is to deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in a closed-loop control.

Required Hardware

This example supports this hardware configuration. You can also use the target model name to open the model from the MATLAB® command prompt.

- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter:
`mcb_pmsm_freq_est_f28379d`

Note: When using the BOOSTXL-3PHGANINV inverter, ensure that proper insulation is available between the bottom layer of BOOSTXL-3PHGANINV and the LAUNCHXL board.

For connections related to the hardware configurations, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. The model automatically computes the ADC (or current) offset values. To disable this functionality (enabled by default), update the variable `inverter.ADCOffsetCalibEnable` to 0 in the model initialization script.

Alternatively, you can compute the ADC offset values and update it manually in the model initialization scripts. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Compute the quadrature encoder index offset value and update it in the `pmsm.PositionOffset` variable available in the model initialization script associated with the target model. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

5. Open the target model for the hardware configuration that you want to use. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

6. Load a sample program to CPU2 of LAUNCHXL-F28379D. For example, load the program that operates the CPU2 blue LED by using GPIO31 (`c28379d_cpu2_blink.slx`) to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

7. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

8. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_pmsm_freq_host_f28379d.slx');
```

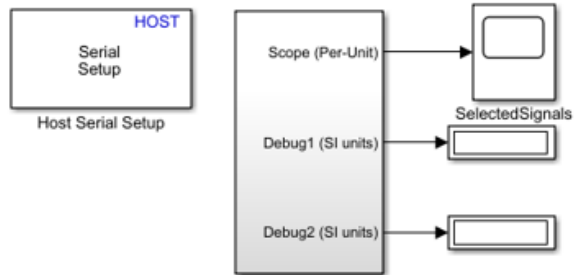
PMSM Frequency Response Estimation Control Host

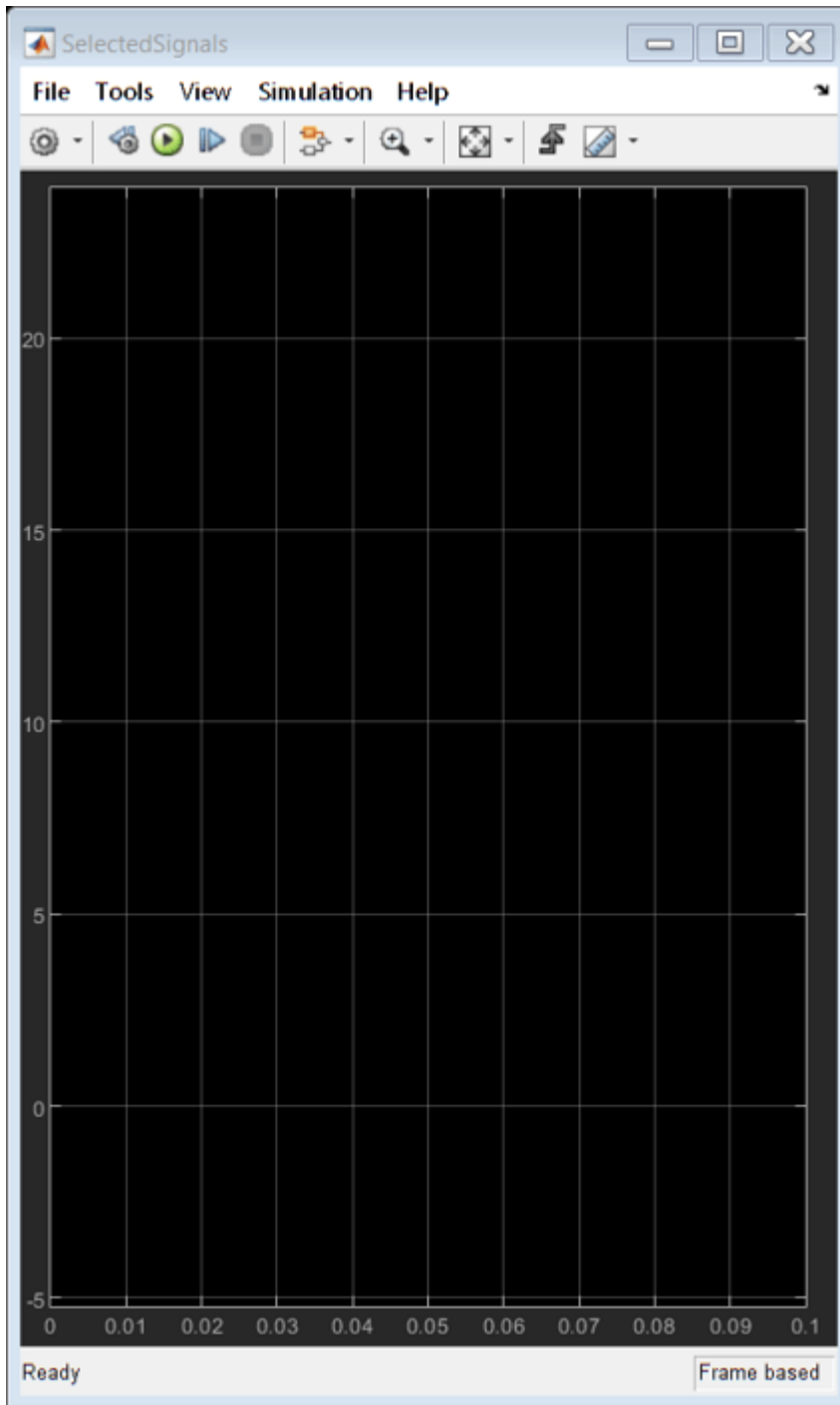
Steps:

1. Select the serial port in 'Host Serial Setup'
2. Use 'Motor Start / Stop' switch to control motor.
3. Enter the requested speed in 'Reference Speed' block.
4. Observe the debug signals in scope.
5. Start the Motor and click FRE Trigger to start frequency estimation in the target hardware.
6. Select the Debug signals "Raw FRE data" to receive the raw FRE data.
7. Wait until the "FRE Status" LED turns green, which indicates that the FRE data is received.
8. Click FRE Plot to plot the plant frequency data for the Speed control loop, Id Current control loop and Iq Current control loop.
9. [Simulate the target model](#) and [compare](#) simulation FRE results with the hardware test results.
10. [Learn more](#) about this example

Note:

Click 'FRE Plot' when FRE Status* LED turns green.





For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

9. In the Host Serial Setup block mask of the host model, select a **Port name**.
10. Change the position of the Start / Stop Motor switch to On to start running the motor.
11. Update the Reference Speed value in the host model.

12. Select the debug signal that you want to monitor in the **Debug signals** section of the host model. Observe these signals in the SelectedSignals time scope window.

13. Click the **FRE Trigger** button to start the FRE process on the target hardware.

14. Select **Position & Raw FRE data** in the **Debug signals** section of the host model to start receiving the raw FRE data from the target hardware. The **FRE Status** LED turns amber to indicate that the host model is receiving raw FRE data from the target hardware.

Note: The LED shows the correct status only when you select **Position & Raw FRE data** in the **Debug signals** section. Otherwise, the LED remains grey.

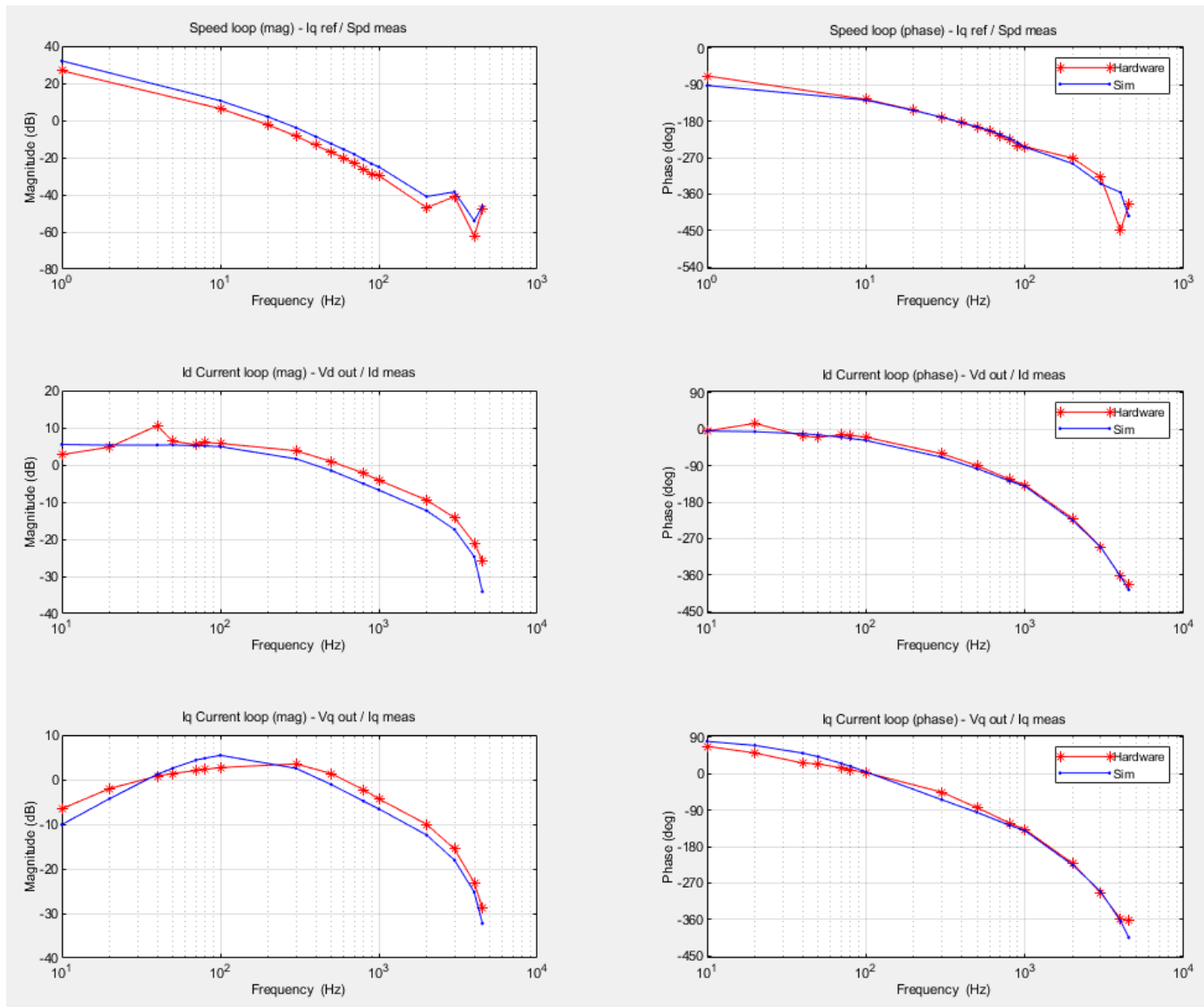
15. Check the status of the **FRE Status** LED on the host model. The LED turns green after the host model receives all the raw FRE data from the target hardware.

16. Click the **FRE Plot** button to plot the raw FRE data received from the target hardware.

17. On the host model, click **Stop** on the **Simulation** tab to stop the simulation.

18. Click the **compare** hyperlink in the host model to plot the raw FRE data generated during simulation and hardware run and compare them.

For an accurate comparison, use the same reference speed during simulation and when running the example on the target hardware.



NOTE:

- To stop the FRE process any time, click the **FRE Abort** button.
- To stop the motor immediately, turn the Start / Stop Motor switch Off.

Configure Frequency Response Estimator Block

Configure these parameters in the Frequency Response Estimator block (from Simulink Control Design™ toolbox) mask:

- Sample time (Ts) - Enter a block sample time that is identical to that of the PI controller.
- Frequencies - Enter an array of frequencies at which the block perturbs the PI controller output to estimate the frequency response of the plant. This field uses the (single data type) workspace variable `fre.i_freq` to store the array of perturbation signal frequencies.

Note: By default, the model uses an array size of 15. However, you can configure the array size.

The **start/stop** signal value of 1 that started the FRE experiment should change to 0 only after the perturbations and tests for all the frequencies are complete and the FRE experiment ends.

- **Amplitudes** - Enter the amplitude of the perturbation signals that the block applies to the PI controller output to estimate the frequency response of the plant. This field uses the (single data type) workspace variable `fre.i_amp` to store the common amplitude value of the perturbation signals.

A high amplitude produces disturbances when the motor runs. An amplitude that is too low results in an inaccurate FRE.

For more details about the Frequency Response Estimator block, see Frequency Response Estimator (Simulink Control Design).

Frequency Response Estimator Block Output

The Frequency Response Estimator block (connected to each PI controller) performs an FRE experiment by perturbing the PI controller output using the sequence of frequencies stored in `fre.i_freq`.

For each perturbation signal (represented by a frequency) the block estimates the plant frequency response in the form of a complex number. Therefore, the block uses the array of frequencies to generate an array of complex numbers (raw FRE data). The sequence of complex numbers contains the information related to gain and phase delay.

Controlling FRE Experiments

The State Machine Control subsystem algorithm enables the three Frequency Response Estimator blocks one at a time (and runs the three FRE experiments) in this order by using the **start/stop** input port of the Frequency Response Estimator block:

1. FRE block connected to Id control loop
2. FRE block connected to Iq control loop
3. FRE block connected to speed control loop

The state machine control ensures that the time interval between the start and stop signals is greater than or equal to the FRE experiment length (as displayed by the Frequency Response Estimator block dialog box). If you change the perturbation signal frequencies, ensure that the state machine control sends the stop signal only after the FRE experiment ends.

For more details about the Frequency Response Estimator block, see Frequency Response Estimator (Simulink Control Design).

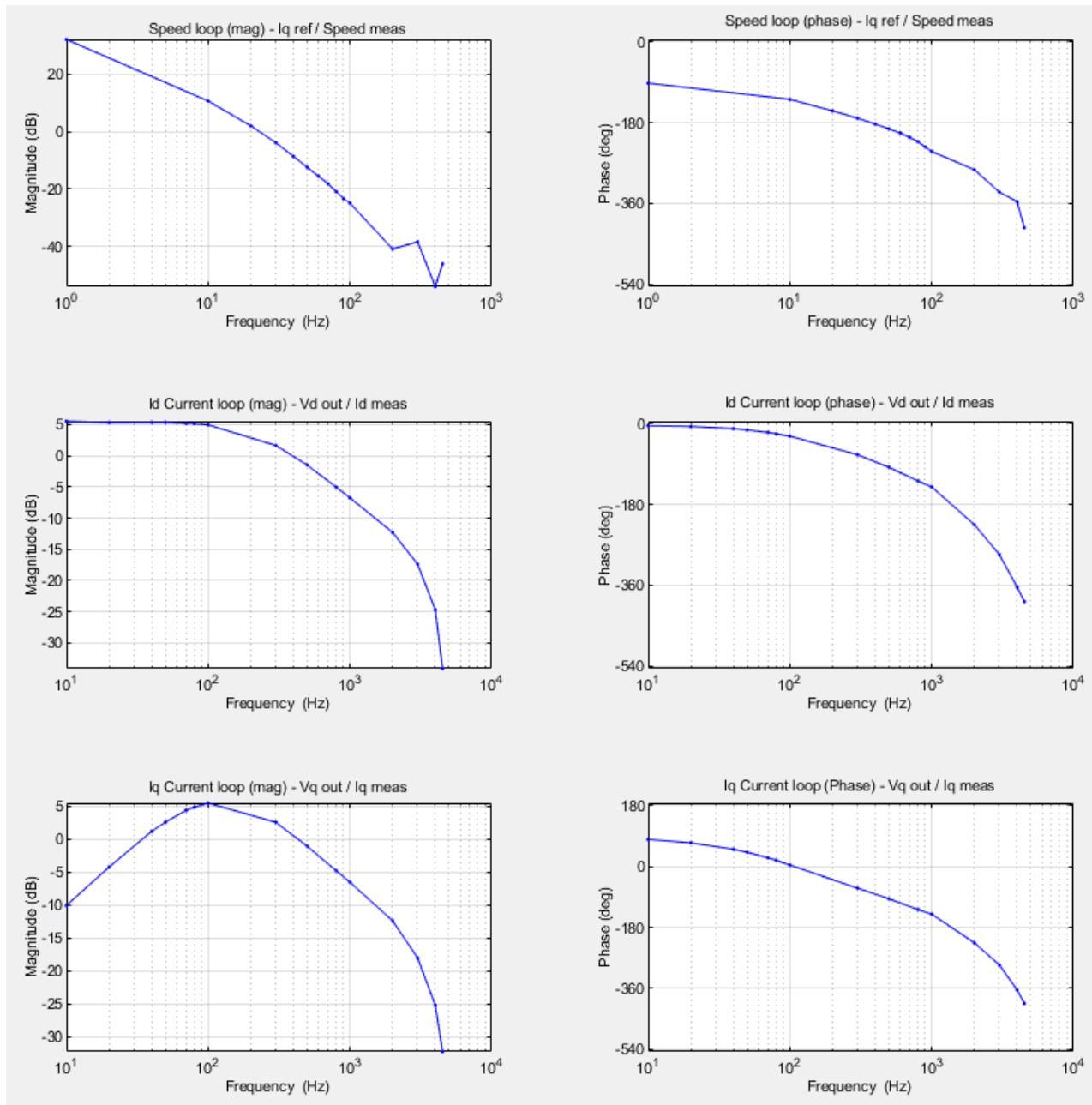
Plot Frequency Response After Simulation

After the simulation ends, the target model stores the frequency response (or the raw FRE data) in these workspace variables:

- `out.Idfreqdata` - Raw FRE data for the Id current PI controller.
- `out.Iqfreqdata` - Raw FRE data for the Iq current PI controller.

- `out.Spdfreqdata` - Raw FRE data for the speed PI controller.

When you click the **Plot freq response** hyperlink in the target model, the model plots the frequency response for the three PI controllers.



The target model uses these commands to plot the frequency responses as seen by the three PI controllers.

Frequency response of Id current PI controller:

```
sys_sim_id = frd(out.Idfreqdata, fre.i_freq*2*pi);
```

```
bode(sys_sim_id);
```

Frequency response of Iq current PI controller:

```
sys_sim_iq = frd(out.Iqfreqdata, fre.i_freq*2*pi);
```

```
bode(sys_sim_iq);
```

Frequency response of speed PI controller:

```
sys_sim_spd = frd(out.Spdfreqdata, fre.spd_freq*2*pi);
```

```
bodeplot(sys_sim_spd);
```

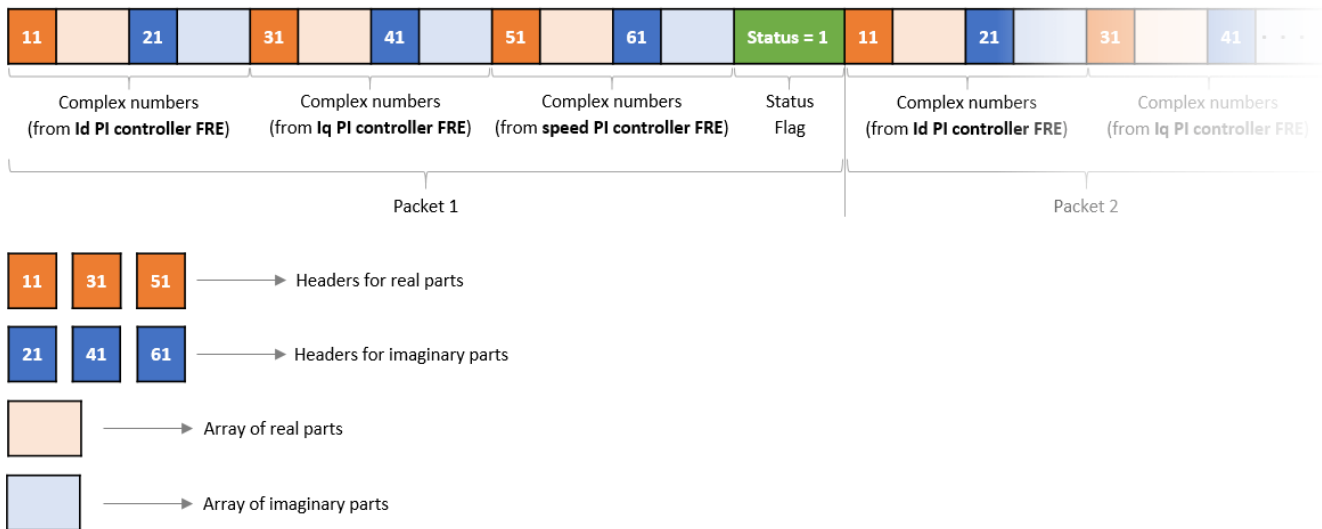
For more information about these commands, see these files:

- mcb_pmsm_freq_est_plot.m
- mcb_pmsm_freq_host_est_plot.m

Send Raw FRE Data to Host Model

When running the target model on the hardware, the target model transfers the raw FRE data continuously to the host model.

The target model splits the entire sequence of complex numbers (or raw FRE data) from each FRE block into real and imaginary arrays and adds headers to separate them. It uses this format to send the raw FRE data from each FRE block to the host model using serial communication.



Plot Frequency Response When Using Target Hardware

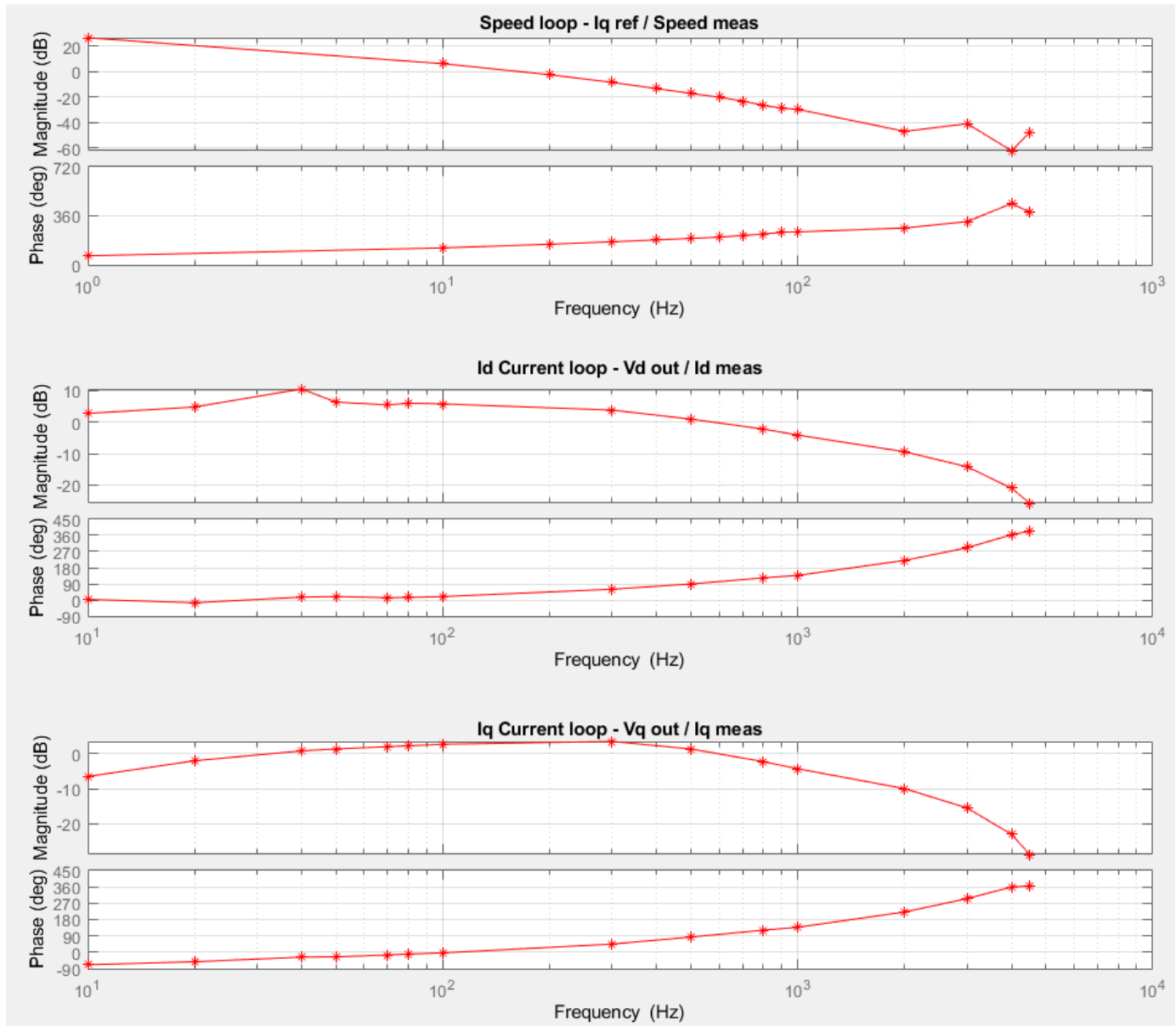
After receiving the message from the target hardware, the host model decrypts the message and stores the array of complex numbers (raw FRE data) in these workspace variables:

- IdfreqData - Raw FRE data for the Id current PI controller.

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)

- IqfreData - Raw FRE data for the Iq current PI controller.
- SpdfreqData - Raw FRE data for the speed PI controller.

When you click the **FRE Plot** button, the host model plots the frequency response for the three PI controllers.



The host model uses these commands to plot the frequency responses observed for the three PI controllers.

Frequency response of Id current PI controller:

```
sys_hw_id=frd(IdFreqData.signals.values, fre.i_freq*2*pi);  
bode(sys_hw_id);
```

Frequency response of Iq current PI controller:

```
sys_hw_iq=frd(IqFreqData.signals.values, fre.i_freq*2*pi);
bode(sys_hw_iq);
```

Frequency response of speed PI controller:

```
sys_hw_spd=frd(SpdFreqData.signals.values, fre.spd_freq*2*pi);
bode(sys_hw_spd);
```

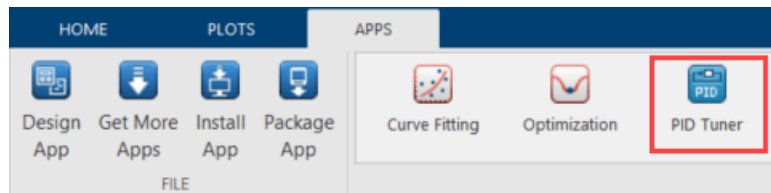
For more information about these commands, see these files:

- mcb_pmsm_freq_est_plot.m
- mcb_pmsm_freq_host_est_plot.m

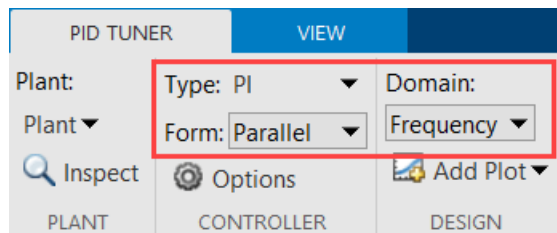
Tuning PI Controller Gains

These steps show you how to tune and determine the gains for the Id and Iq currents and the speed of the PI controllers:

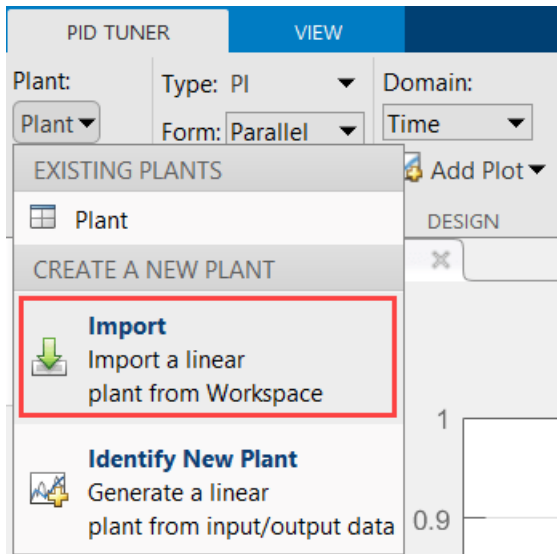
1. Navigate to the **Apps** tab on the Simulink toolstrip and open the **PID Tuner** app.



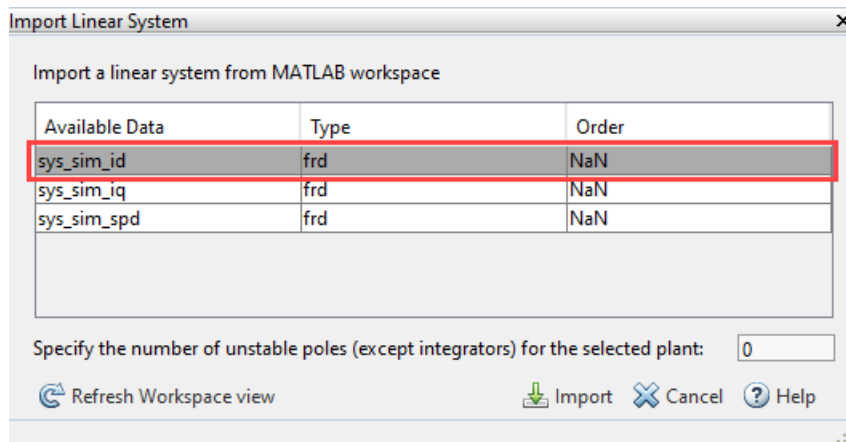
2. In the **PID Tuner** tab, select **PI** for **Type**, **Parallel** for **Form**, and **Frequency** for **Domain**.



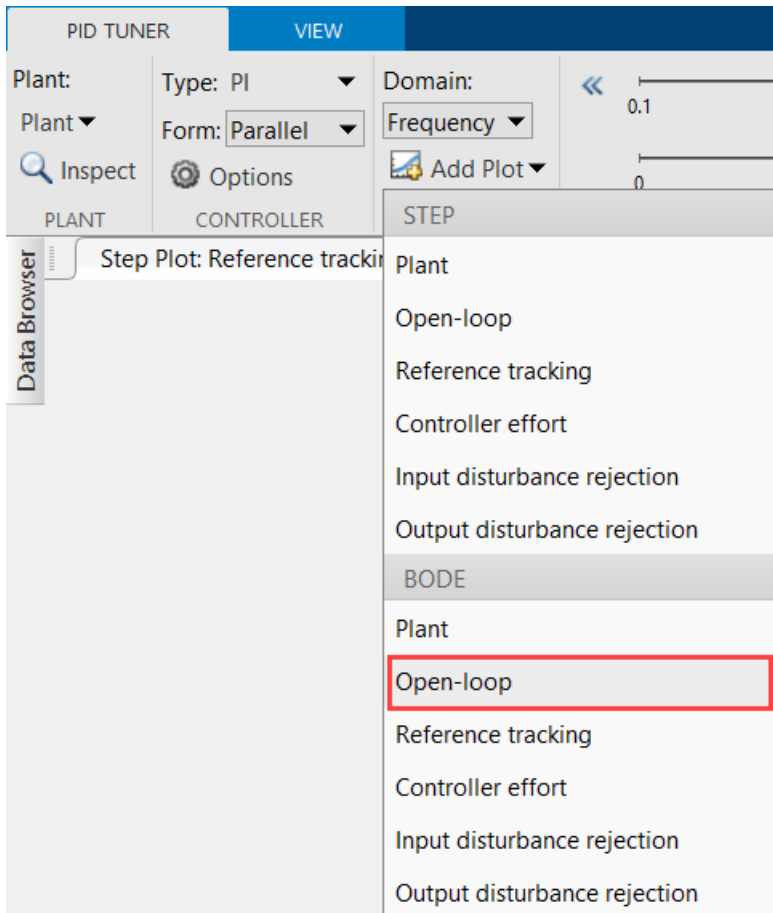
3. Under **Plant**, select **Import** to open the **Import Linear System** window.



4. In the **Import Linear System** window, select `sys_sim_id` and click **Import** to import the FRE data for the Id PI controller.

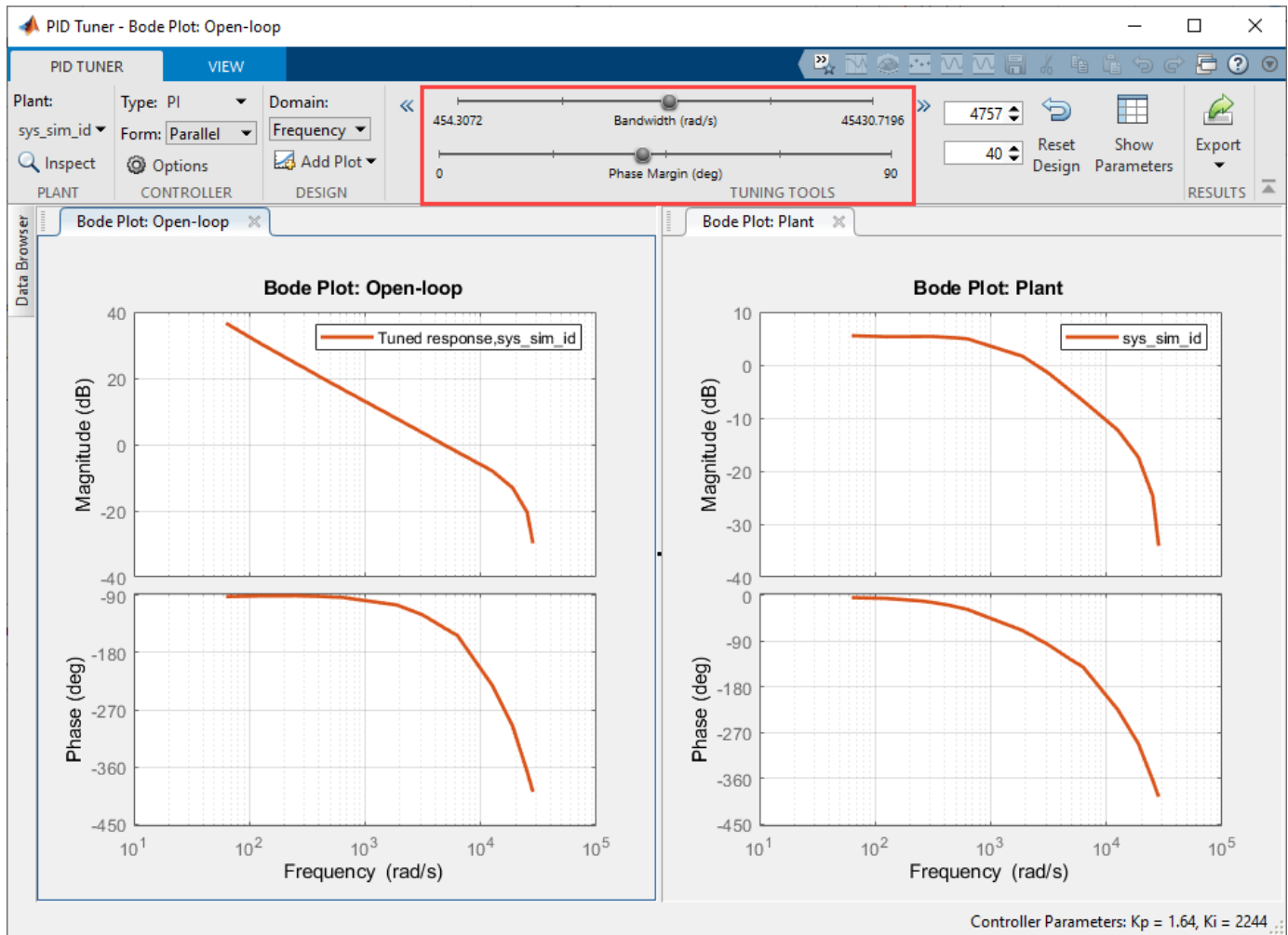


5. Select **Add Plot > Bode > Open-loop** to open the open-loop bode plot for the Id PI controller.



6. Use the **Tuning Tools** section in the **PID Tuner** tab to tune the bandwidth and phase margin and observe the results in the open-loop and plant bode plots.

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)



7. After you finish tuning, click **Show Parameters** to display the tuned controller parameters K_p and K_i for the I_d current PI controller.

Controller Parameters	
	Tuned
Kp	1.6405
Ki	2243.8215
Kd	n/a
Tf	n/a
Performance and Robustness	
	Tuned
Rise time	NaN seconds
Settling time	NaN seconds
Overshoot	NaN %
Peak	NaN
Gain margin	4.21 dB @ 7.96e+03 rad/s
Phase margin	39.5 deg @ 4.77e+03 rad/s
Closed-loop stability	Stable

8. Repeat steps 3 to 7 by selecting **sys_sim_iq** in the **Import Linear System** window to obtain the tuned parameters K_p and K_i for the I_q PI controller.

9. Update the K_p and K_i gain values for both I_d and I_q current PI controllers in the initialization script of the example model `mcb_pmsm_freq_est_f28379d.slx`. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

10. Perform the frequency response estimation again using the updated PI controller gains by either simulating the example or running it on the target hardware.

11. Perform steps 3 to 7 by selecting **sys_sim_spd** in the **Import Linear System** window to obtain the tuned parameters K_p and K_i for the speed PI controller.

See Also

- “PID Controller Tuning in Simulink” (Simulink Control Design)

Other Things to Try

You can try estimating the transfer functions and state-space models from the FRE data by using these functions from the System Identification Toolbox™:

- `ssest`
- `tfest`

MATLAB Project for FOC of PMSM with Quadrature Encoder

This MATLAB® project provides a motor control example model that uses field-oriented control (FOC) to run a three-phase permanent magnet synchronous motor (PMSM) in different modes of operation. Implementing the FOC algorithm needs real-time rotor position feedback. This example uses a quadrature encoder sensor to measure the rotor position. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

The example can run a motor in these modes:

- **StandBy** - In this mode, the motor stops running because the inverter outputs zero volts.
- **Calibration** - In this mode, the example calibrates the ADC (or current) offset and the quadrature encoder offset (offset between the d-axis of the rotor and the encoder index pulse position as detected by the quadrature encoder sensor).
- **Open Loop Speed Control** - In this mode, the example controls the rotor speed by running the motor in the open-loop control.
- **Closed Loop Torque Control** - In this mode, the example controls the torque output of the motor by running it in the closed-loop control.
- **Closed Loop Speed Control** - In this mode, the example controls the rotor speed by running the motor in the closed-loop control.

Note: When running the example model on the hardware, we recommend that you stop the motor (by switching to the StandBy mode) before transitioning from one operating mode to another.

Open MATLAB Project

Use one of these methods to open the MATLAB project to follow this workflow:

1. Click **Open Example**.
2. Run the command `mcb_QEPWorkflowDemoStart` at the command prompt.

Model

The MATLAB project includes the model `mcb_qep_workflow`.

This model (also called target model) automatically opens when you open the MATLAB project. You can also use the Project window to open this model available in the `model` folder.

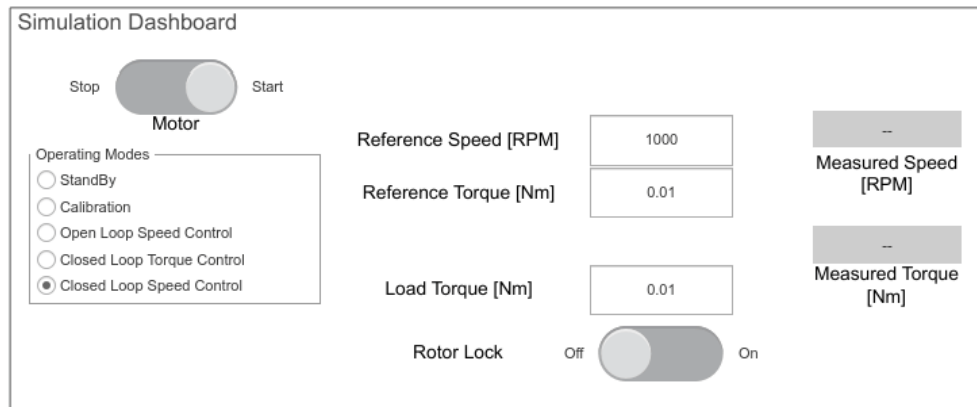
Workflow for FOC of PMSM with QEP sensor

HW Prerequisites

1. TI F28379D LaunchPad
2. BOOSTXL-DRV8305 Booster pack or BOOSTXL-3PhGaNInv
3. PMSM motor with QEP sensor

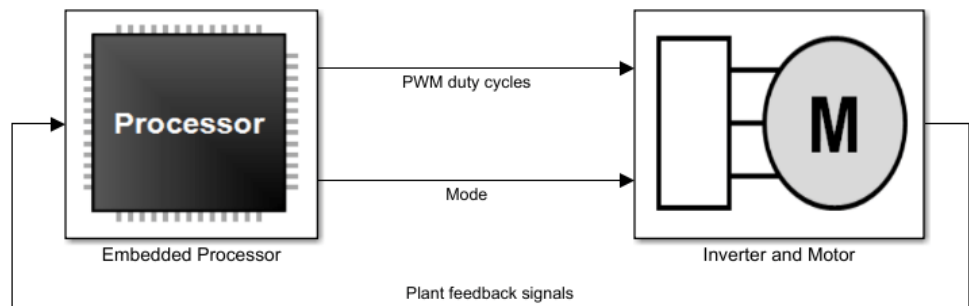
Steps:

1. [Edit motor & inverter parameters](#) and run the script to update the Simulink Data Dictionary file.
2. Simulate the model to see motor operation in different modes
3. Click **Build, Deploy & Start** in Hardware tab
4. Control motor via [host model](#)
5. [Learn more](#) about this example



Note:

Reference Speed [RPM] input is active in both Open Loop Speed Control and Closed Loop Speed Control modes.
Reference Torque [Nm] input is active only in Closed Loop Torque Control mode.



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Required MathWorks® Products

To simulate model:

- Motor Control Blockset™
- Stateflow®

To generate code and deploy model:

1. Motor Control Blockset™
2. Embedded Coder®
3. Embedded Coder® Support Package for Texas Instruments™ C2000™ Processors
4. Fixed-Point Designer™ (only needed for optimized code generation)
5. Stateflow®

Prerequisites

1. Obtain the motor and inverter parameters. The MATLAB project uses default motor and inverter parameters that you can replace with values from either the motor and inverter datasheets or from other sources.

- You can estimate the parameters for the motor that you want to use with the motor control hardware, by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188.

The parameter estimation tool updates the `motorParam` variable (in the MATLAB® workspace) with the estimated motor parameters.

2. Update the motor and inverter parameters in the `mcb_qep_data.m` parameter script associated with the MATLAB project. This script automatically opens when you open the MATLAB project. You can also use the Project window to open this script from the `utils` folder.
3. Click **Run** on the **Editor** tab to run the parameter script and update the script parameters in the data dictionary. The data dictionary file (`pmsm_qep_data.sldd`) is available inside the `data` folder in the Project window.

Note: When you simulate the target model or run it on the hardware, if you change any parameter value in the parameter script, you must run the parameter script to update the data dictionary.

Simulate Model

Follow these steps to simulate the target model.

1. Open the target model included in the MATLAB project.
2. Turn the **Stop-Start** slider switch available in the **Simulation Dashboard** area to the **Start** position to allow the model to simulate and run the motor.

During simulation, you can turn the switch to the **Stop** position anytime to immediately stop the motor.

3. Click **Run** on the **Simulation** tab to simulate the model.

Open Loop Speed Control mode

1. Select **Open Loop Speed Control** in the **Simulation Dashboard > Operating Modes** area of the target model.
2. Enter the values in the **Reference Speed [RPM]** and **Load Torque [Nm]** fields.

Note: In the open-loop mode, the motor runs only if the load torque value is either zero or a very small value. If you use a high load torque value, the motor can stop.

Closed Loop Torque Control mode

1. Select **Closed Loop Torque Control** in the **Simulation Dashboard > Operating Modes** area of the target model.
2. Enter the reference torque value in the **Reference Torque [Nm]** field.
3. You can simulate the locked rotor situation by moving the **Rotor Lock** slider switch to **On** position.

When you move the switch to **Off** position, the rotor rotates freely within a maximum speed limit that is defined by the variable `data.pmsm.wLimit_TorqueMode` in the `mcb_qep_data.m` parameter script.

Note: The **Rotor Lock** slider switch is applicable only when performing simulation in this operating mode. It has no effect during the other modes.

Closed Loop Speed Control mode

1. Select **Closed Loop Speed Control** in the **Simulation Dashboard > Operating Modes** area of the target model.
2. Enter the values in the **Reference Speed [RPM]** and **Load Torque [Nm]** fields.

NOTE:

- In the closed-loop mode, the motor runs only if the load torque value is less than or equal to the rated torque of the motor. If you use a higher load torque, the motor starts running in the opposite direction.
- When you simulate the target model, the calibration operating mode produces an invalid simulation output because this mode is designed to calibrate the hardware setup.

When simulating this example, you can observe the measured speed and torque values in the **Measured Torque [Nm]** and **Measured Speed [RPM]** fields in the **Simulation Dashboard** area.

Generate Code and Deploy Model to Target Hardware

This section shows you how to generate code and run the FOC algorithm on the target hardware.

In addition to the target model, the MATLAB project uses a host model. The host model, which is a user interface to the controller hardware board, runs on the host computer. To use the host model, first deploy the target model to the controller hardware board. The host model uses serial communication to command the model, run (and control) the motor in the selected operating mode, and collect and display the calibration output, and debug signals from the controller.

Required Hardware

The example supports this hardware configuration.

- LAUNCHXL-F28379D controller + (BOOSTXL-DRV8305 or BOOSTXL-3PHGANINV) inverter

You can select one of these inverters by setting the `mcb_SetInverterParameters` argument in the parameter script file (`mcb_qep_data.m`) to one of these values:

- BoostXL-DRV8305
- BOOSTXL-3PhGaNInv

For connections related to this hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.
2. Complete the hardware connections.
3. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

4. To ensure that CPU2 is not configured to use the board peripherals intended for CPU1, load a sample program to CPU2 of LAUNCHXL-F28379D, for example, program that operates the CPU2 blue LED by using GPIO31 (c28379D_cpu2_blink.slx).

5. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

6. Click the **host model** hyperlink in the target model to open the associated host model.

PMSM FOC Speed Control Host

Prerequisites:

1. Deploy the target model to the hardware [mcb_qep_workflow](#)

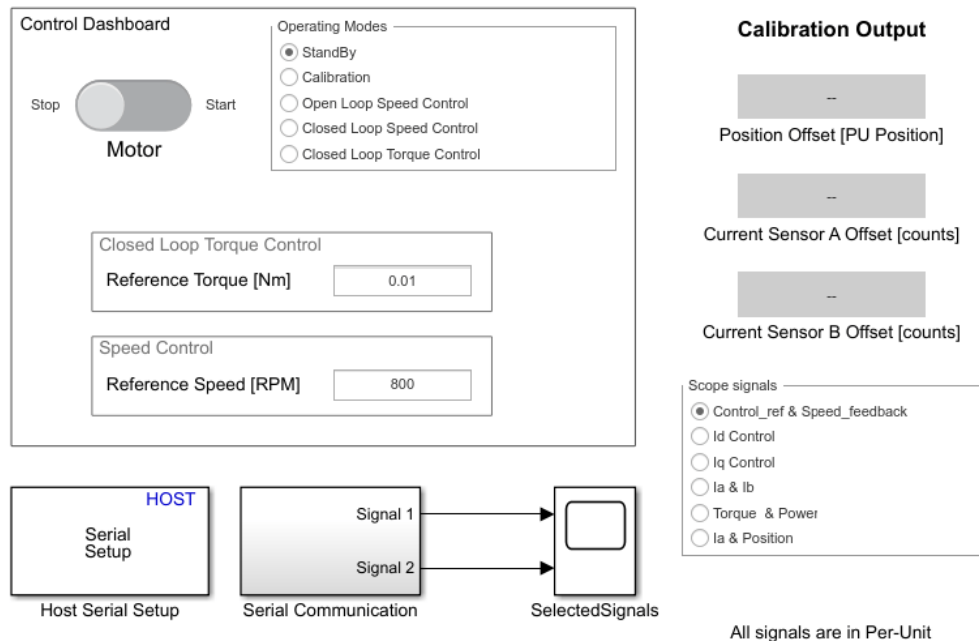
Steps:

1. Select the port name in **Serial 1** tab of **Host Serial Setup**.
2. Simulate this model
3. Use **Start / Stop Motor** switch to control the motor.
3. Use open loop mode to validate hardware setup.
4. Use Calibration mode to calibrate current offset and position offset.
5. Update these values in [parameter file](#) and run parameter file.
6. Proceed to Closed Loop Speed Control mode or torque control mode (works best with loaded motor shaft)

Note:

Reference Speed [RPM] input is active in both Open Loop Speed Control and Closed Loop Speed Control modes. Reference Torque [Nm] input is active only in Closed Loop Torque Control mode.

'Control_ref' scope signal plots Reference speed during speed control modes and Reference torque during torque control mode.



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7. Turn the **Stop-Start** slider switch in the **Control Dashboard** area to the **Start** position to allow the model to run the motor.

When running the motor using the target hardware, turn the switch to the **Stop** position anytime to immediately stop the motor.

8. In the Host Serial Setup block mask of the host model, select a **Port name**.

9. Click **Run** on the **Simulation** tab to run the host model.

Note: Always stop the motor (by using the StandBy mode) before changing the operating mode.

Instructions for Calibration mode

1. Select **StandBy** in the **Control Dashboard > Operating Modes** area of the host model to stop the motor.

2. Select **Calibration** in the **Control Dashboard > Operating Modes** area of the host model.

The controller runs the motor and performs ADC (or current) offset and quadrature encoder offset calibration and updates these offset parameters in the data dictionary file (pmsm_qep_data.sldd):

- `pmsm.PositionOffset`
- `inverter.CtSensAOffset`
- `inverter.CtSensBOffset`

The host model also displays the offset values in these fields available in the **Calibration Output** area:

- **Position Offset**
- **Current Sensor Offset A**
- **Current Offset B**

3. Update these offset parameters in the parameter script file (`mcb_qep_data.m`) before you run the parameter script:

- `data.pmsm.PositionOffset`
- `data.inverter.CtSensAOffset`
- `data.inverter.CtSensBOffset`

Note: Update the parameter script immediately to avoid losing these offset values. MATLAB project rewrites the data dictionary (with the existing parameter script values) every time you run the parameter script.

For details about these parameters, see “Estimate Control Gains from Motor Parameters” on page 3-2.

4. After the calibration completes, the offset parameters are erased if you reset the target hardware. Click **Build, Deploy & Start** on the **Hardware** tab to program the target hardware with the calibrated offset parameters.

Instructions for Open Loop Speed Control mode

1. Select **StandBy** in the **Control Dashboard > Operating Modes** area of the host model to stop the motor.

2. Select **Open Loop Speed Control** in the **Control Dashboard > Operating Modes** area of the host model.

The controller runs the motor in the open-loop control.

3. You can change the default reference speed value by using the **Reference Speed [RPM]** in the **Control Dashboard > Speed Control** area of the host model.

Note:

- Be cautious when providing a reference speed. The motor may not run optimally at all speeds. We recommend that you use a low speed initially and increase it gradually.
- In the open-loop mode, the motor runs only if the load is either zero or negligible. If you use a higher load, the motor stops running.

- You do not need to calibrate the ADC (or current) and quadrature encoder sensor when you run the motor in open-loop control.

Instructions for Closed Loop Speed Control mode

1. Run the motor in the open-loop configuration to validate the hardware setup. Follow the steps described in the Instructions for Open Loop Speed Control mode section.
2. Perform ADC (or current) offset and quadrature encoder offset calibration. Follow the steps described in the Instructions for Calibration mode section.
3. Select **StandBy** in the **Control Dashboard > Operating Modes** area of the host model to stop the motor.
4. Select **Closed Loop Speed Control** in the **Control Dashboard > Operating Modes** area of the host model.

The controller runs the motor in the closed-loop control and controls the rotor speed.

5. You can change the default reference speed value by using the **Reference Speed [RPM]** in the **Control Dashboard > Speed Control** area of the host model.

Note: In the closed-loop mode, the motor runs only if the load torque is less than or equal to the rated load of the motor. If you use a higher load torque, the motor stops running.

Instructions for Closed Loop Torque Control mode

1. Run the motor in the open-loop configuration to validate the hardware setup. Follow the steps described in the Instructions for Open Loop Speed Control mode section.
2. Perform the ADC (or current) offset and quadrature encoder offset calibration if you have not done so earlier. Follow the steps described in the Instructions for Calibration mode section.
3. Select **StandBy** in the **Control Dashboard > Operating Modes** area of the host model to stop the motor.
4. Select **Closed Loop Torque Control** in the **Control Dashboard > Operating Modes** area of the host model.

The controller runs the motor in the closed-loop configuration and controls the torque of the motor.

5. You can change the default reference torque value by using the **Reference Torque [Nm]** in the **Control Dashboard > Speed Control** area of the host model.

You can configure the maximum speed limit of the motor in the closed loop torque control mode using the variable `data.pmsm.wLimit_TorqueMode` in the `mcb_qep_data.m` parameter script.

When running the motor using the target hardware in these operating modes, you can select the debug signals (in the **Scope signals** area) that you want to monitor in the **SelectedSignals** time scope.

Estimate Initial Rotor Position Using Pulsating High-Frequency and Dual-Pulse Methods

This example determines the initial rotor position (in electrical radians) of a stationary interior PMSM. The example uses the pulsating high-frequency (PHF) method, which works when the motor has a high saliency ratio ($L_q > L_d$). The estimated rotor position ranges from θ to 2π electrical radians. Due to a limitation in the PHF method, the estimated position may show ambiguity of π (pi). The dual-pulse (DP) method uses polarity detection to resolve the ambiguity of π and applies π compensation if there is an error.

Part A: Pulsating High-Frequency Method

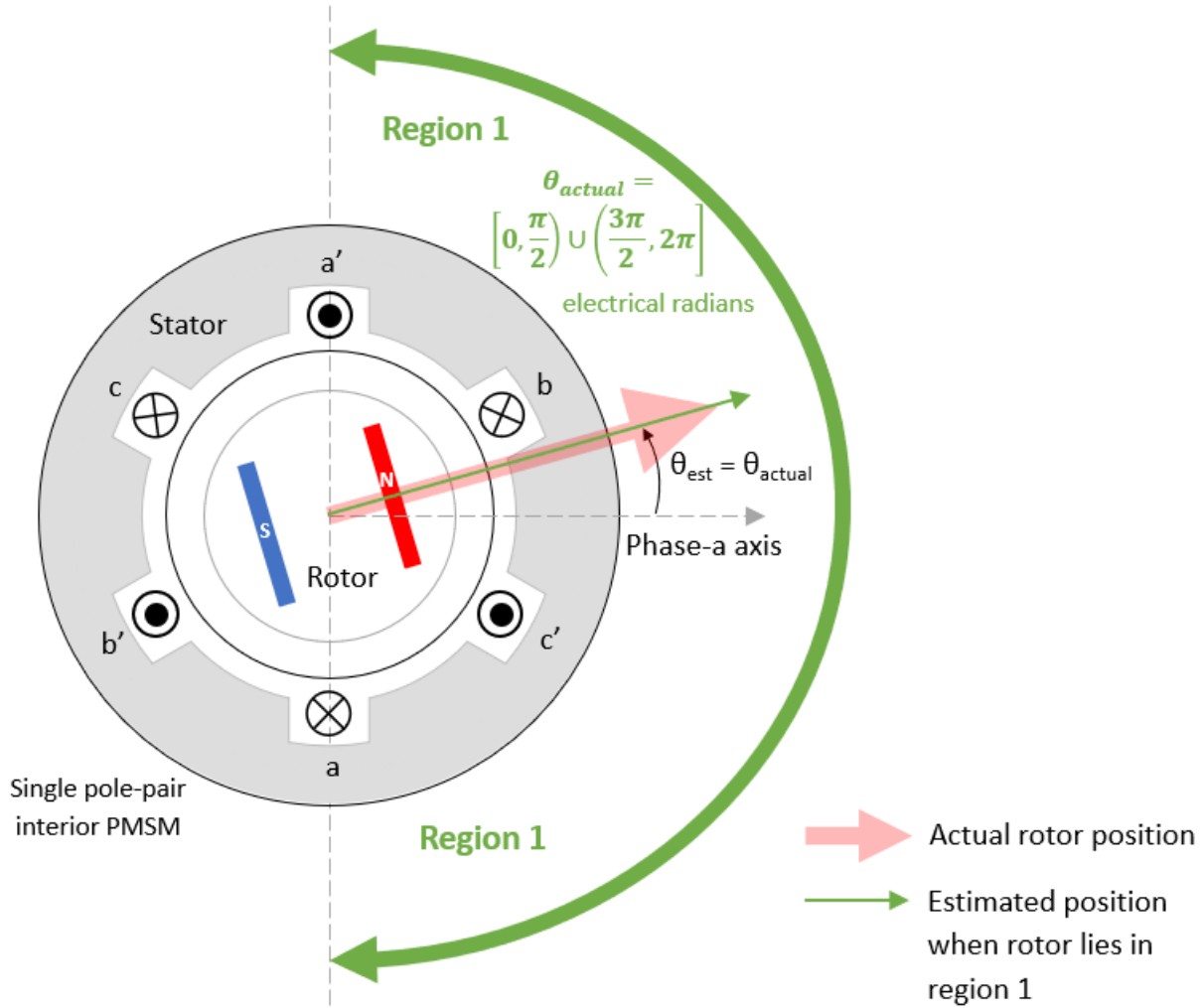
Motor control techniques like “Field-Oriented Control (FOC)” on page 4-2 need real-time position feedback from the running motor to track the rotor angle accurately. An FOC algorithm uses the real-time rotor position along with the current feedback to compute the reference voltages and duty cycles that drive the motor. Therefore, it is essential to accurately track the rotor position to compute the right reference voltages to run the motor at a specific speed using an efficient torque value. Sensors like quadrature encoders and Hall effect sensors can provide real-time rotor position data to implement position tracking in FOC applications. However, these sensors might have mechanical constraints (for example, a complex sensor installation process) and can be expensive. In addition, when using some of these sensors, it is difficult to determine the initial position of the rotor.

Whereas, sensorless techniques are cost effective and can provide more accurate position tracking without any mechanical constraint. This example uses the PHF method to determine the initial rotor position. The example algorithm injects a sinusoidal high-frequency voltage along the d-axis (resulting in unbalanced three-phase voltage in the motor) and reads the current response from the motor. The algorithm performs numerical analysis of the resulting stator current response to compute the initial position of the stationary rotor (in electrical radians).

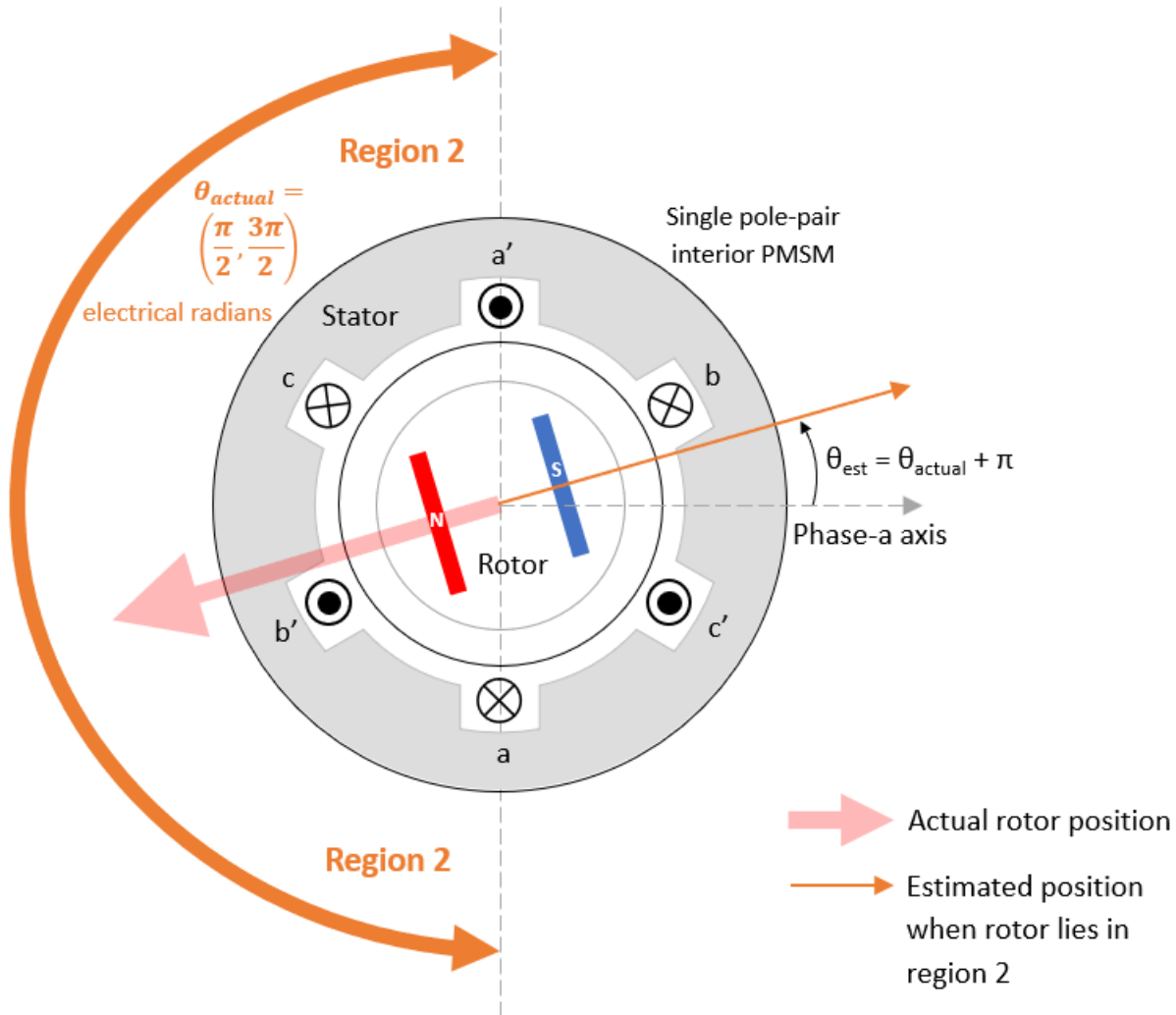
The example algorithm performs iterative tests on the motor. Therefore, when you start simulation, the estimated position shows as zero but rises steadily to saturate at the estimated rotor-angle (with respect to a-axis).

The PHF method has a limitation due to which it might compute rotor position with an ambiguity of π .

If the rotor lies in the range $\theta_{actual} = [0, \frac{\pi}{2}) \cup (\frac{3\pi}{2}, 2\pi]$ electrical radians (region 1), the estimated position is accurate (π compensation is not required).



If the rotor lies in the range $\theta_{actual} = \left(\frac{\pi}{2}, \frac{3\pi}{2}\right)$ electrical radians (region 2), the estimated position shows an ambiguity of π (π compensation is required).



Therefore, the example uses the dual-pulse method to determine if the estimated position needs π compensation.

Note: You can use these variables in the model initialization script `mcb_ipmsm_pos_est_f28379d_data.m` to customize the PHF signal:

- `PHF.Frequency` — Frequency of PHF signal
- `PHF.Amplitude` — Amplitude (in per-unit) of PHF signal
- `PHF.PHF_Duration` — Execution time of the PHF algorithm

Part B: Dual-Pulse Method

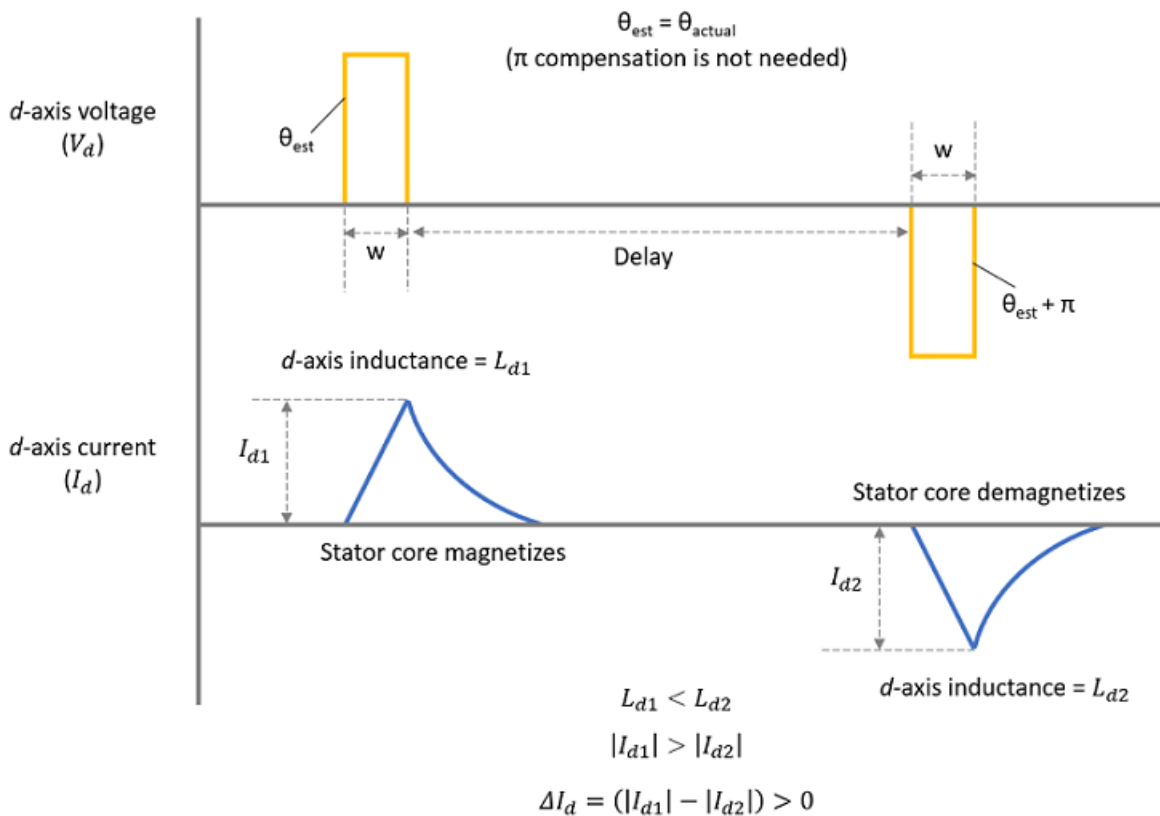
The example algorithm injects two very short duration voltage pulses (with the same width and magnitude) into the d-axis of the rotor with respect to the magnetic north of the rotor:

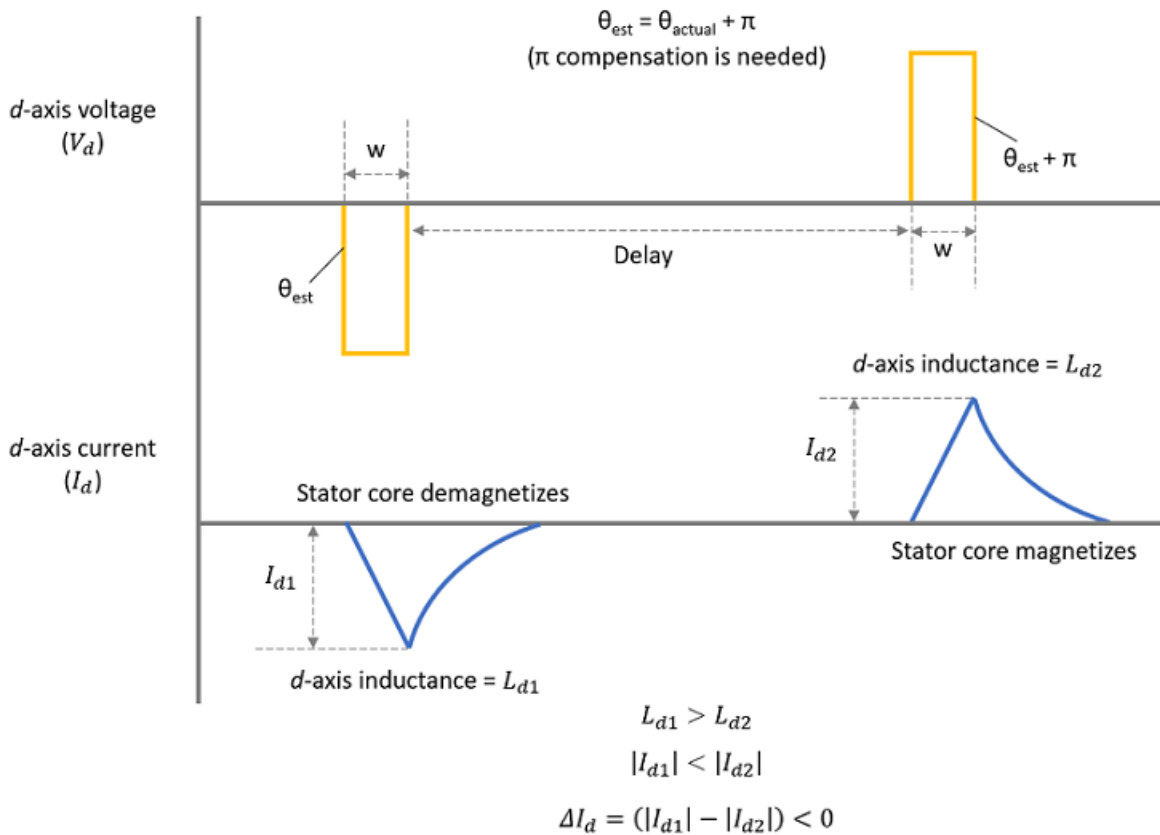
- Pulse-1 that uses the rotor position estimated in Part A

- Pulse-2 that uses the rotor position estimated in Part A + π

Because pulse width is very short, the motor does not run and the rotor remains stationary after pulse injection. The interaction between the resulting stator magnetic flux and the rotor permanent magnets result in two current impulses along the d-axis of the rotor that rise and fall quickly.

Because the stator core is saturated, it shows a nonlinear behavior. A small L_d results in higher current I_d , and a high L_d results in smaller current I_d . Therefore the I_d current impulses generated by Pulse-1 and Pulse-2 show different peak values.





The example algorithm computes the difference between the peak values of the two current impulses ΔI_d to determine if the position estimated in Part A needs π compensation.

$$\Delta I_d = |I_{d1}| - |I_{d2}|$$

Note:

- This example does not support position estimation when θ_{actual} is approximately equal to $\frac{\pi}{2}$ or $\frac{3\pi}{2}$ (the boundary points between region 1 and region 2).
- You can use these variables in the model initialization script `mcb_ipmsm_pos_est_f28379d_data.m` to customize the DP signals:
- `DP.PulseAmp` — Amplitude (in per-unit) of the pulses
- `DP.Duration_width` — Width of the pulses
- `DP.Duration_delay` — Delay between the two pulses

Model

The example includes the target model `mcb_ipmsm_pos_est_f28379d`.

You can simulate this model or run it on the hardware. Use the `open_system` command to open the model.

```
open_system('mcb_ipmsm_pos_est_f28379d.slx');
```

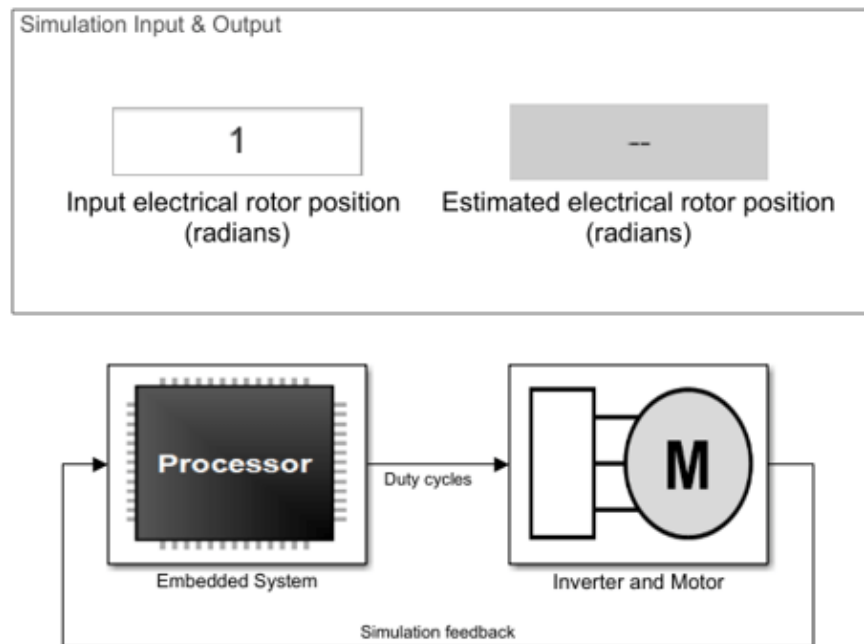
Estimation of Initial Rotor Angle (zero speed) Interior Permanent Magnet Synchronous Motor

HW Prerequisites

1. TI F8379D LaunchPad
2. BOOSTXL-DRV8305 Booster pack
3. IPMSM motor

Steps:

1. [Edit motor & inverter parameters](#)
2. Input the rotor electrical angle (radians) in the edit box "Input electrical rotor position"
3. Simulate the model and observe the estimated rotor angle in display box "Estimated electrical rotor position"
4. Click **Build, Deploy & Start** in the Hardware tab.
5. Start or stop algorithm via [host model](#)
6. [Learn more](#) about this example



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Required MathWorks® Products

- Motor Control Blockset™
- Embedded Coder®
- Embedded Coder Support Package for Texas Instruments C2000™ Processors
- Simscape™ Electrical™ (only for simulation)

Prerequisites

1. Determine the motor parameters. The target model uses default parameters that you can replace with values from either the motor datasheet or other sources.

However, if you have motor control hardware, you can estimate the parameters for your motor by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188. The parameter estimation tool updates the `motorParam` variable (in the MATLAB® workspace) with the estimated motor parameters.

2. Update the motor and inverter parameters in the model initialization script associated with the target model. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

Simulate Model

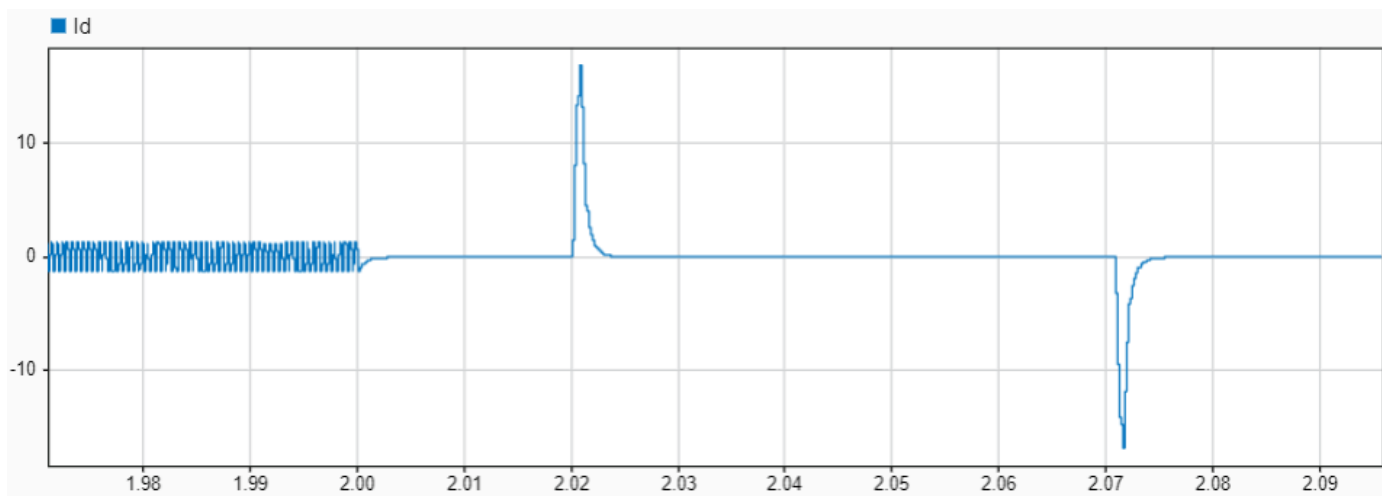
Follow the instructions in the Simulate Nonlinear Stator Core Behavior section to introduce high saliency in the motor block. Then follow these steps to simulate the target model.

1. Open the target model included in this example.
2. Enter the initial rotor position value (that the Interior PMSM block should use for simulation) in the **Input electrical rotor position (radians)** field available in the **Simulation Input & Output** area of the target model.
3. Click **Run** on the **Simulation** tab to simulate the target model. The model estimates the rotor position using the PHF method. Then it uses the DP method to determine if the estimated rotor position needs π compensation. The target model applies π compensation if needed.

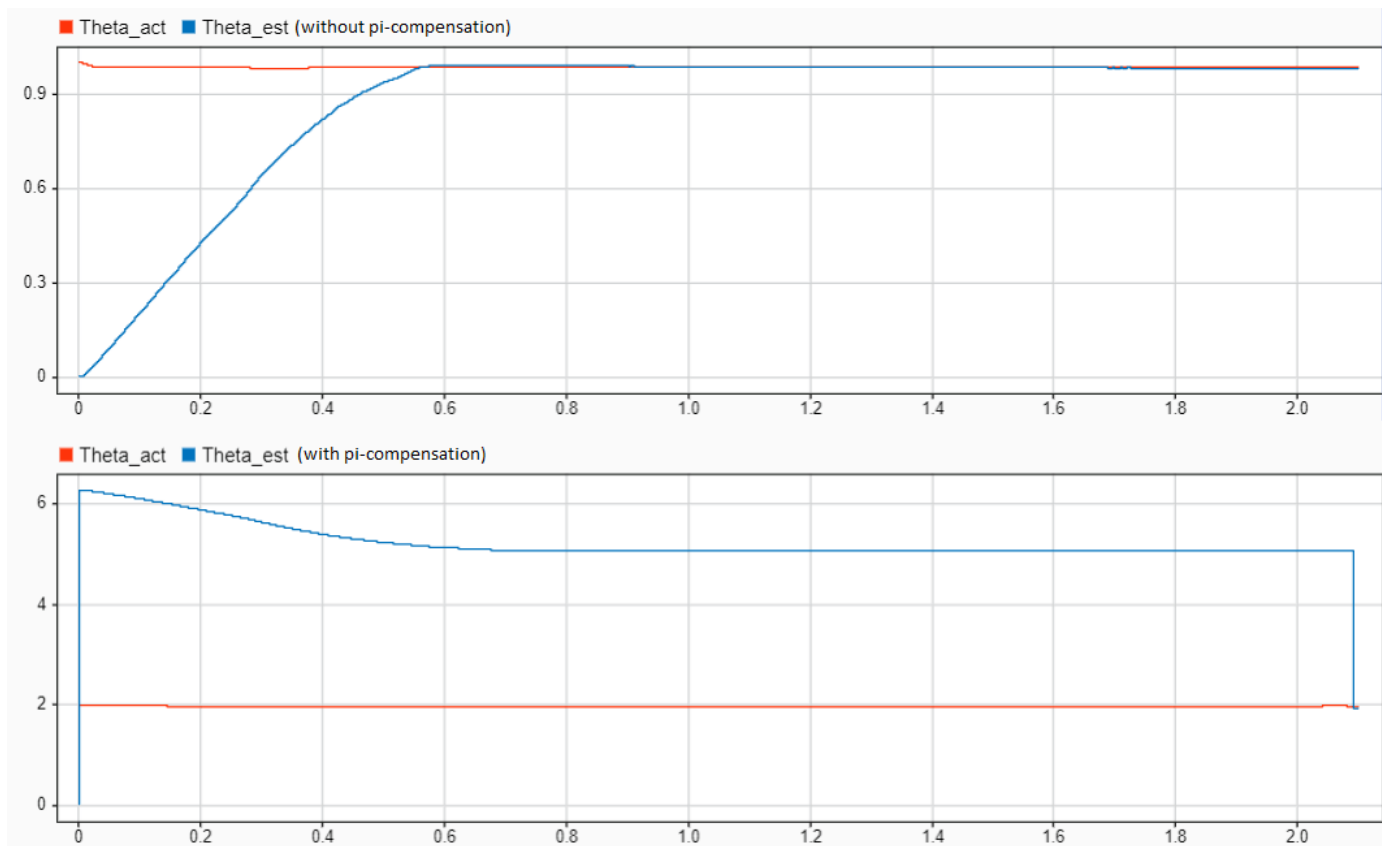
It then displays the estimated rotor position in the **Estimated electrical rotor position (radians)** field.

4. Observe the logged signals in the Simulation Data Inspector.

This plot shows the current along the d-axis (I_d) during simulation.



This plot shows the estimated rotor position when the target model does not apply π compensation ($\theta_{init} = \theta_{est}$) and when the target model applies π compensation ($\theta_{init} = \theta_{est} + \pi$).



5. The **Estimated Rotor Position (Electrical Radians)** display block in the **Output** area of the target model shows the initial rotor position estimated by the target model.

Generate Code and Deploy Model to Target Hardware

Follow the instructions in this section to generate code and run the example on the target hardware.

This example uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you can run the host model on the host computer, deploy the target model to the controller hardware board. The host model uses serial communication to command the target Simulink® model and run the motor in closed-loop control.

Required Hardware

The example supports this hardware configuration. You can also use the target model name to open the model from the MATLAB® command prompt.

LAUNCHXL-F28379D controller + BOOSTXL-DRV8305 inverter + iPMSM (such as AdLee BM-180):
mcb_ipmsm_pos_est_f28379d

For connections related to this hardware configuration, see “LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations” on page 7-5.

Generate Code and Run Model on Target Hardware

1. Simulate the target model and observe the simulation results.

2. Complete the hardware connections.

3. By default, the model computes the ADC offset values for phase current measurement. To disable this functionality, update the value of the `inverter.ADCOffsetCalibEnable` variable in the model initialization script to 0.

Alternatively, you can compute the ADC offset values and update them manually in the model initialization script. For instructions, see “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6.

4. Open the target model. If you want to change the default hardware configuration settings for the model, see “Model Configuration Parameters” on page 2-2.

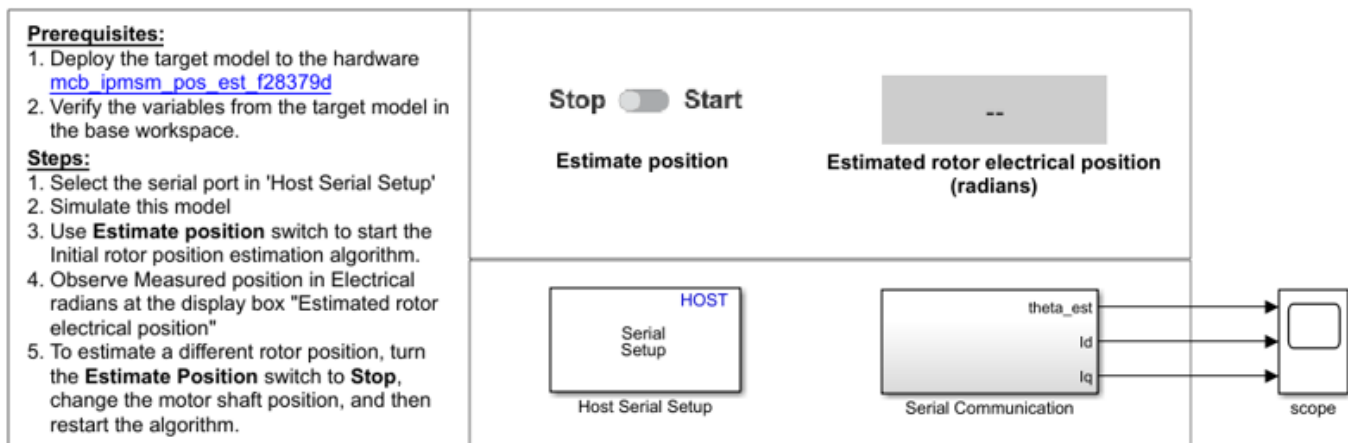
5. Load a sample program to CPU2 of the LAUNCHXL-F28379D board. For example, load the program that operates the CPU2 blue LED by using GPIO31 (`c28379D_cpu2_blink.slx`). This ensures that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

6. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware. Verify the variables that the target model adds to the workspace.

7. Click the **host model** hyperlink in the target model to open the associated host model. You can also use the `open_system` command to open the host model.

```
open_system('mcb_ipmsm_pos_est_f28379d_host_model.slx');
```

Estimation of Initial Rotor Angle (zero speed) Control Host Interior Permanent Magnet Synchronous Motor



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For details on serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

8. In the dialog box of the Host Serial Setup block in the host model, select a port name in the **Port name** parameter.

9. Click **Run** on the **Simulation** tab to run the host model.

10 Change the position of the **Estimate Position** switch to **Start** to start running the example algorithm. The target model estimates the rotor position using PHF method. Then it uses the DP method to determine if the estimated rotor position needs π compensation. The target model applies π compensation if needed.

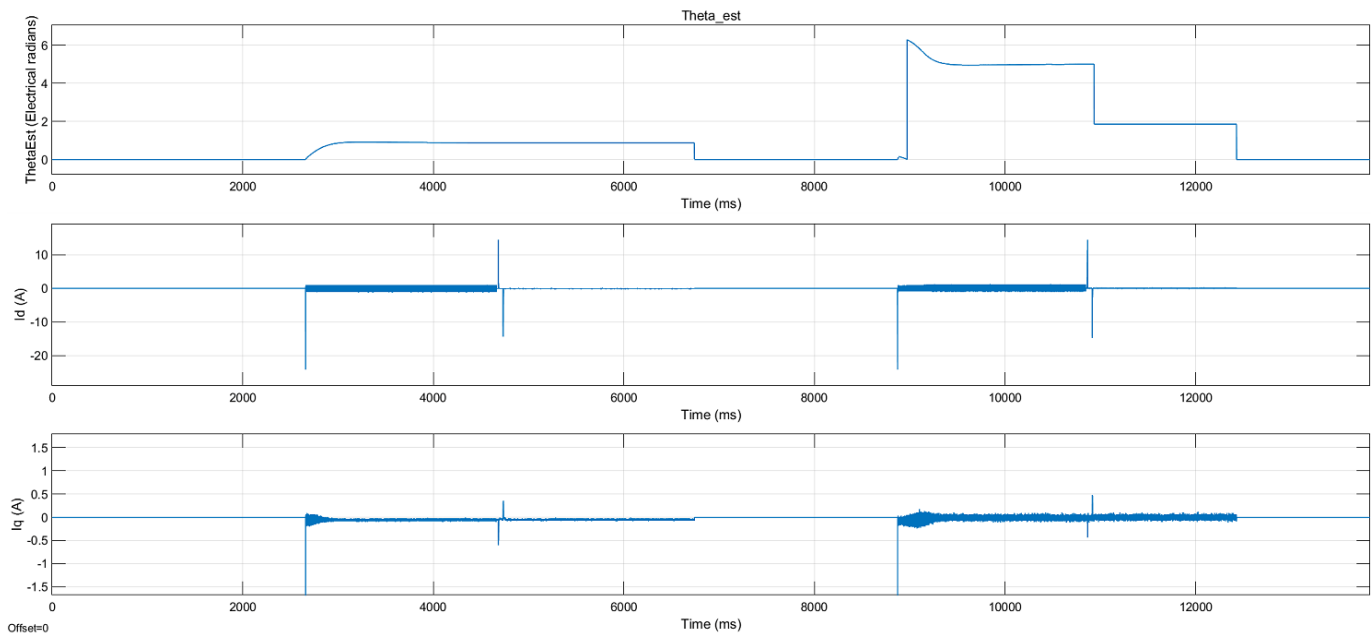
The host model obtains the estimated rotor position from the target hardware and displays it in the **Estimated rotor electrical position (radians)** field.

11 To estimate a different rotor position, change the position of the **Estimate Position** switch to **Stop**. The **Estimated rotor electrical position (radians)** field displays the value θ .

Turn the motor shaft to a new position. Then change the position of the **Estimate Position** switch to **Start** to run the example algorithm again and estimate the new position.

12 Observe the estimated position, Id, and Iq signals in the time scope available in the host model.

This plot shows the estimated rotor electrical position (θ_{init}) and the stator currents (Id) and (Iq).



Simulate Nonlinear Stator Core Behavior

The DP method algorithm works only when the stator core saturates and shows a nonlinear behavior. To generate this behavior in simulation, the target model uses the PMSM (Simscape Electrical) block from Simscape™ Electrical™. Follow this procedure to experimentally determine the tabulated L_d , L_q , and I_d data for the actual motor and use this data to make the motor block nonlinear for simulation purposes.

Determine L_d Data

1. Create a target model to run a PMSM using open-loop control. Modify the algorithm so that it injects the voltages $V_d = V_{ac} \sin(\omega t) + V_{dc}$ and $V_q = 0$ into the actual motor. This generates the current $I_d = I_{ac} \sin(\omega t + \phi) + I_{dc}$ in the motor where:

V_d is the voltage that the algorithm computes and injects along the rotor's d-axis

$V_{ac} \sin(\omega t)$ is the AC component of V_d (such that V_{ac} and ω are constants that the algorithm should assume)

V_{dc} is the DC component of V_d that you provide as an input

I_d is the current along the d-axis of the rotor that the algorithm computes from the measured I_a and I_b phase currents

$I_{ac} \sin(\omega t + \phi)$ is the AC component of I_d (ϕ is the phase difference between V_d and I_d that the algorithm should measure)

I_{dc} is the DC component of I_d , which is fixed for a V_{dc} input (the algorithm should compute this value by using V_{dc} and the motor resistance)

Note: Because $V_q = I_q = 0$, the rotor remains stationary.

a. Add an algorithm to read the I_a and I_b phase currents that the motor draws.

b. Add an algorithm to convert the I_a and I_b phase current values into the equivalent I_d value by using Clarke and Park transforms.

c. Add an algorithm to compute ϕ and I_{dc} .

d. Add an algorithm to compute I_{ac} .

$$I_{ac} = \left(\frac{I_d - I_{dc}}{\sin(\omega t + \phi)} \right)$$

e. Add an algorithm to compute L_d .

$$L_d = \frac{\sqrt{V_{ac}^2 - I_{ac}^2 R^2}}{\omega I_{ac}} \quad (\text{for a fixed } I_{dc})$$

For details about designing a control algorithm and configuring it for deployment to the target hardware, see “Control Algorithm Design” and “Deployment and Validation”.

2. Create a model initialization script (.m file) to initialize the parameters and perform other calculations. Use the **Model Properties > Callbacks** to integrate this script with the target model. For details about how Motor Control Blockset™ uses this script, see “Estimate Control Gains from Motor Parameters” on page 3-2.

3. Configure the target model to run on the target hardware. For instructions, see “Model Configuration Parameters” on page 2-2.

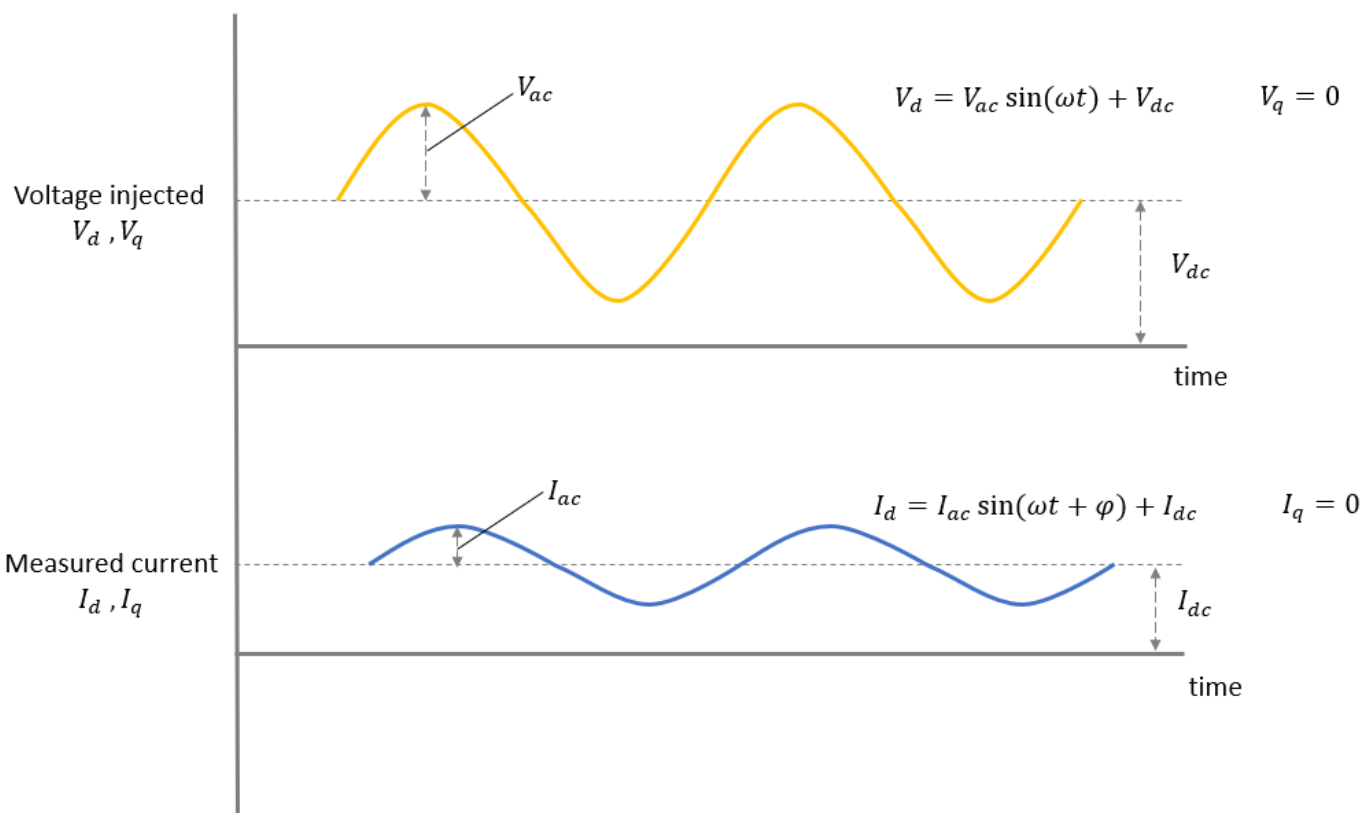
4. Create a separate host model to control and communicate with the target model running on the motor-control hardware in real-time. You can add an **Edit** box on the host model and use it to send V_{dc} input to the target hardware. Use **Display** boxes to obtain the computed L_d and I_{dc} values from the target hardware.

For details about the host-target communication interface, see “Host-Target Communication” on page 6-2.

5. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

6. Simulate the host model. Send a V_{dc} input to the target hardware and record the L_d and I_{dc} values that you obtain.

7. Change V_{dc} manually across a range between a negative and positive voltage and record the resulting L_d and I_{dc} values for each operating point.



Determine L_q Value

Perform these steps to determine a L_q value that is higher than the sequence of L_d values obtained from the Determine L_d section. This is necessary to maintain a high saliency ratio ($L_q > L_d$) for the simulated motor block.

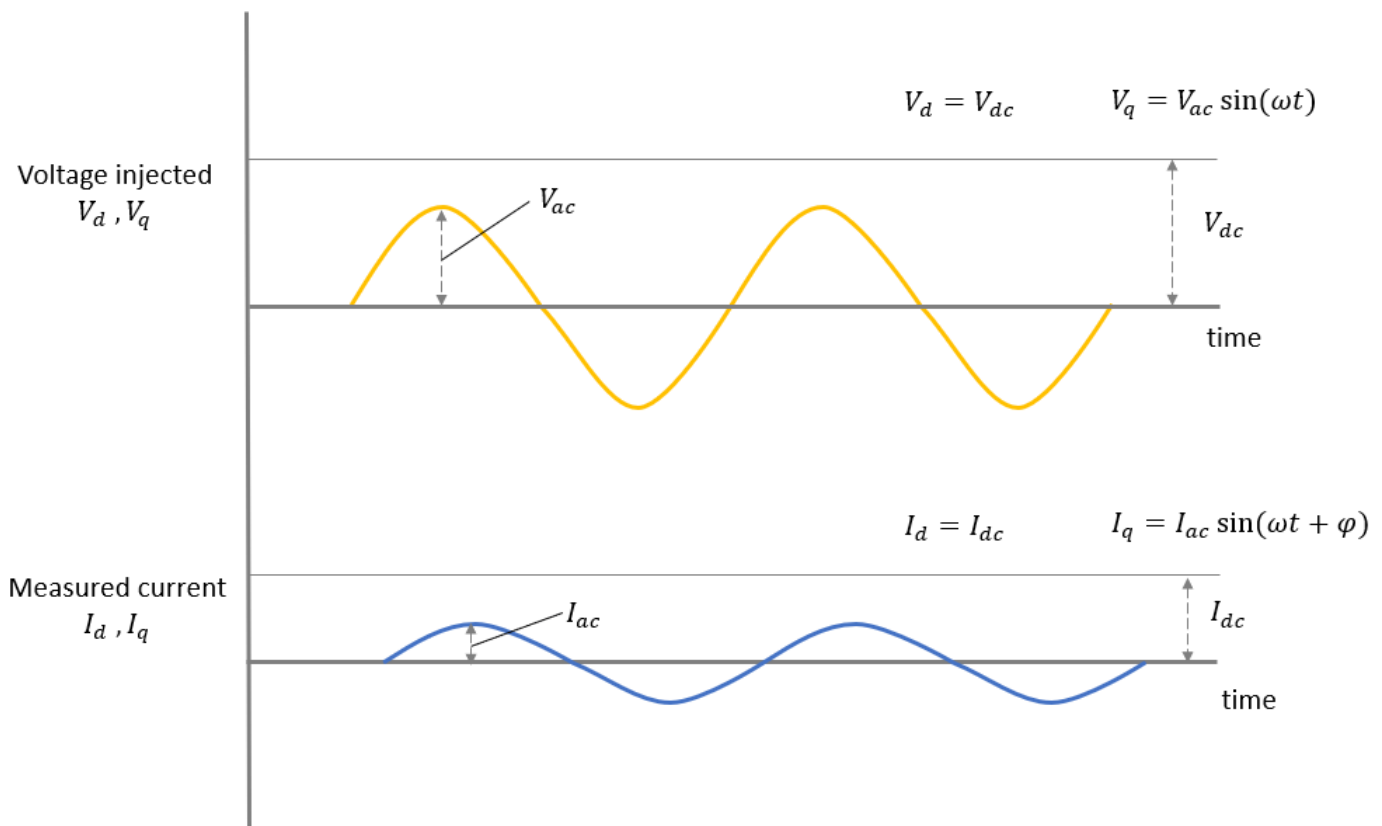
1. Modify the target model that you used in the Determine L_d section so that it injects the voltages $V_d = V_{dc}$ and $V_q = V_{ac} \sin(\omega t)$ into the actual motor. This generates a current $I_q = I_{ac} \sin(\omega t + \phi)$ in the motor where:

$V_d = V_{dc}$ is the DC voltage (corresponding to $I_d = I_{dc} = 0$) that the algorithm injects along the d axis of the rotor

$V_q = V_{ac} \sin(\omega t)$ is the AC voltage that the algorithm computes and injects along the q-axis of the rotor. (such that V_{ac} and ω are constants that the algorithm assumed in the Determine L_d section)

$I_q = I_{ac} \sin(\omega t + \phi)$ is the AC current along the q-axis of the rotor that the algorithm computes from the measured I_a and I_b phase currents (ϕ is the phase difference between V_q and I_q that the algorithm should measure)

Note: Because $I_d = 0$, the rotor remains stationary.



a. Update the existing algorithm to convert the I_a and I_b phase current values into the equivalent I_q value by using Clarke and Park transforms.

b. Update the existing algorithm to compute ϕ .

c. Update the existing algorithm to compute I_{ac} .

$$I_{ac} = \left(\frac{I_q}{\sin(\omega t + \phi)} \right)$$

d. Add an algorithm to compute L_q .

$$L_q = \frac{\sqrt{V_{ac}^2 - I_{ac}^2 R^2}}{\omega I_{ac}} \quad (\text{for } I_d = I_{dc} = 0)$$

2. Update the model initialization script to perform the preceding modified calculations.

3. Update the host model to obtain and display the L_q value computed by the target hardware.

4. Click **Build, Deploy & Start** on the **Hardware** tab to deploy the target model to the hardware.

5. Simulate the host model. Send a V_{dc} input (corresponding to $I_d = I_{dc} = 0$) to the target hardware and record the L_q value that you obtain.

Design High Saliency Motor Block

Sections Determine Ld Data and Determine Lq Value provide the following data:

- Sequence of L_d values
- Sequence of I_{dc} (I_d for a DC current) values
- Constant L_q value

In addition, we can assume a set of I_q values that we can use to add high saliency to the motor block.

Use the variables `pmsm.nonlin.idVec`, `pmsm.nonlin.Ld_data`, `pmsm.nonlin.iqVec`, and `pmsm.nonlin.Lq_data` to store this data in the model initialization script `mcb_ipmsm_pos_est_f28379d_data.m` associated with the example target model `mcb_ipmsm_pos_est_f28379d.slx`.

Note: This script is different from the model initialization script used in sections Determine Ld Data and Determine Lq Value.

In addition, define the variables `pmsm.nonlin.LdMatrix`, `pmsm.nonlin.LqMatrix`, and `pmsm.nonlin.PmMatrix`.


```
% Ld vs Id data computed through experiment mention in documentation
% Stator current in d-axis
pmsm.nonlin.idVec = [-16.385 -12.69 -10.105 -6.305 -3.755 -1.475 1.57 3.925 6.505 10.44 13.04 14.3325]; %A
% Stator d-axis inductance
pmsm.nonlin.Ld_data = [1.77E-04 1.76E-04 1.76E-04 1.75E-04 1.76E-04 2.63E-04 2.59E-04 1.76E-04 1.73E-04 1.72E-04 1.70E-04 1.69E-04]; %H

% Stator current in q-axis
pmsm.nonlin.iqVec = linspace(-13,13,20); %A
% Q-axis inductance value at low currents
pmsm.nonlin.Lq_data = 2.88E-04; %H

% Here Ld has been considered to be dependent only Id
pmsm.nonlin.LdMatrix = pmsm.nonlin.Ld_data'*ones(1,20); %H

% Here Lq has been considered to be independent of Id, Iq
% Here low current Lq value has been chosen because Ld<Lq has to be
% satisfied for all Id, Iq
pmsm.nonlin.LqMatrix = pmsm.nonlin.Lq_data*ones(12,20); %H

% Here PM flux has been considered to be independent of Id, Iq
pmsm.nonlin.PmMatrix = pmsm.FluxPM * ones(12,20);
```

In the PMSM (Simscape Electrical) block parameter dialog box, set the **Modeling fidelity** parameter to **Tabulated Ld, Lq and PM** and add these variables as shown in the following figure.

Block Parameters: PMSM

Permanent Magnet Synchronous Machine

This block represents a permanent magnet synchronous machine with sinusoidal flux distribution.

Right-click on the block and select Simscape block choices to access variant implementations of this block.

[Select a predefined parameterization](#)

[Source code](#)

Settings

Main Iron Losses Mechanical Variables

Electrical connection: Composite three-phase ports

Winding type: Delta-wound

Modeling fidelity: Tabulated Ld, Lq, and PM

Number of pole pairs: pmsm.p

Permanent magnet flux linkage parameterization: Specify flux linkage

Stator parameterization: Specify Ld, Lq, and L0

Direct-axis current vector, i_D : pmsm.nonlin.idVec A

Quadrature-axis current vector, i_Q : pmsm.nonlin.iqVec A

Ld matrix, $L_d(i_d, i_q)$: pmsm.nonlin.LdMatrix H

Lq matrix, $L_q(i_d, i_q)$: pmsm.nonlin.LqMatrix H

Permanent magnet flux linkage, $PM(i_d, i_q)$: pmsm.nonlin.PmMatrix Wb

The variables `pmsm.nonlin.idVec`, `pmsm.nonlin.Ld_data`, `pmsm.nonlin.iqVec`, and `pmsm.nonlin.Lq_data` help saturate the stator core and introduce a nonlinear behavior during simulation. This enables the algorithm of the DP method to generate the I_d current impulses (corresponding to Pulse-1 and Pulse-2) with different peaks.

References

[1] W. Zine, L. Idkhajine, E. Monmasson, Z. Makni, P. Chauvenet, B. Condamin, and A. Bruyere, "Optimisation of HF signal injection parameters for EV applications based on sensorless IPMSM drives", IET Electric Power Applications, Volume 12, Issue 3, March 2018, p. 347 - 356 (doi:10.1049/iet-epa.2017.0228).

[2] Gaolin Wang, Guoqiang Zhang, and Dianguo Xu, "Position Sensorless Control Techniques for Permanent Magnet Synchronous Machine Drives", Springer, Singapore, 2020 p. 41 - 43 (doi: <https://doi.org/10.1007/978-981-15-0050-3>).

Algorithm-Export Workflows for Custom Hardware

This example enables you to use any custom motor-control hardware (hardware not used in the Motor Control Blockset™ examples) to run a three-phase permanent magnet synchronous motor (PMSM) using field-oriented control (FOC). Using the algorithm export workflows, which involve generating code for the control algorithm by using Simulink® and Embedded Coder® and then integrating it with either manually written or externally generated hardware driver code. This example explains the algorithm export workflows along with the intermediate steps.

The example uses the following hardware as a reference, but you can use any motor-control hardware:

- Controller: STMicroelectronics® STM32F302R8
- Inverter: STMicroelectronics® X-NUCLEO-IHM07M1
- Motor: BLY171D (includes quadrature encoder sensor)

You can use this example to customize the control algorithm and integrate it with the drivers for your motor-control hardware. In this example, we use the STM32 Cube MX software to configure and generate code for the hardware drivers. This example supports any three-phase PMSM.

Implementing the FOC algorithm needs real-time rotor position feedback. This example uses a quadrature encoder sensor to measure the rotor position. For details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

The example includes three workflows.

1. Open-loop control and ADC offset calibration — This workflow uses an algorithm that runs a PMSM using open-loop control (also known as scalar control or Volts/Hz control). You can use this workflow to check the integrity of the hardware connections and calculate the ADC offsets for the current sensors available on the hardware.

2. Quadrature encoder offset calibration — This workflow uses an algorithm that calculates the offset between the d-axis of the rotor and the index pulse position as detected by the quadrature encoder sensor. The control algorithm (available in the field-oriented control workflow) needs this offset to accurately compute the rotor position, which is necessary to implement FOC.

3. Field-oriented control — This workflow uses an algorithm that runs a PMSM using closed-loop field-oriented control (FOC). The workflow uses the ADC and quadrature sensor offsets as inputs.

Each workflow includes these steps to prepare, deploy, and run the algorithm on your hardware:

1. Generate code for the control algorithm using Embedded Coder®
2. Obtain C Code For Hardware Drivers
3. Integrate control algorithm code with the driver code
4. Deploy the integrated code to hardware
5. Control the motor using a host Simulink® model.

Open MATLAB® Project

Use one of these methods to open the MATLAB project:

- Click **Open Example**.
- Run the command `mcb_FOCAlgorithmExportDemoStart` at the command prompt.

The project contains three folders, one for each workflow required to run the final FOC algorithm. Each folder contains these contents:

- Data script containing motor, inverter, and target hardware details.
- Algorithm model for generating code for the control algorithm. The generated code will be available in the folder `[project_root]/work/code`.
- Host model for communication with the target hardware.
- C code which shows how to integrate the generated algorithm code and the hardware driver code (specific to STM32F302R8 & X-NUCLEO-IHM07M1).

In addition to the three folders, the project also includes an `.IOC` file. You can use this file with STM32 Cube MX to configure the peripherals of the target and generate code. The `.IOC` file available in the project is specific to the STM32F302R8 and X-NUCLEO-IHM07M1 hardware.

Workflows for Custom Hardware

Follow these workflows in sequence.

1. “Open-Loop Control and ADC Offset Calibration” on page 8-2
2. “Quadrature Encoder Offset Calibration” on page 8-11
3. “Field-Oriented Control” on page 8-18

Estimate PMSM Parameters Using Recommended Hardware

This example determines the parameters of a permanent magnet synchronous motor (PMSM) using the recommended Texas Instruments™ hardware. The tool determines these parameters:

- Phase resistance, R_s (Ohm)
- d and q axis inductances, L_d and L_q (Henry)
- Back-EMF constant, K_e (Vpk_LL/krpm, where Vpk_LL is the peak voltage line-to-line measurement)
- Motor inertia, J (Kg.m²)
- Friction constant, B (N.m.s)

The example accepts the minimum required inputs, runs tests on the target hardware, and displays the estimated parameters.

NOTE: This example does not support simulation. Use one of the supported hardware configurations to run this example.

Prerequisites

The parameter estimation tool needs the motor position as detected by either a quadrature encoder, a Hall sensor, or a sensorless flux observer. To detect the motor position correctly by using a position sensor, calibrate the quadrature encoder or Hall sensor attached to the motor under test.

- Ensure that the PMSM is in no-load condition.

If you are using Hall sensors:

- Ensure that the PMSM has Hall sensors.
- Calibrate the Hall sensor offset. For instructions, see “Hall Offset Calibration for PMSM Motor” on page 4-67.

If you are using a quadrature encoder sensor:

- Ensure that the PMSM has a quadrature encoder sensor.
- Calibrate the quadrature encoder offset. For instructions, see “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76.

NOTE: If you set the **Sensor Selection** field in the host model to `Sensorless`, you can skip the position sensor calibration step.

Supported Hardware

This example supports only these hardware configurations:

Texas Instruments™ F28069M control card configuration:

- F28069M control card

- DRV8312-69M-KIT inverter
- A PMSM with a Hall or a quadrature encoder sensor
- DC power supply

NOTE: The DRV8312-69M-KIT board has a known issue in the board's power supply section. Due to this limitation, the board does not support all Hall sensor types. For example, it does not support the Hall sensor of Teknic M-2310P motor.

Texas Instruments LAUNCHXL-F28379D configuration:

- LAUNCHXL-F28379D controller
- BOOSTXL-DRV8305 inverter
- A PMSM with a Hall or a quadrature encoder sensor
- DC power supply

Required MathWorks® Products

To run parameter estimation, you need these products:

- Motor Control Blockset™
- Fixed-Point Designer™
- Embedded Coder®
- Embedded Coder Support Package for Texas Instruments C2000™ Processors

Prepare Hardware

For the F28069M control card configuration:

1. Connect the F28069M control card to J1 of DRV8312-69M-KIT inverter board.
2. Connect the motor three phases to MOA, MOB, and MOC on the inverter board.
3. Connect the DC power supply to PVDDIN on the inverter board.
4. If you are using a Hall sensor, connect the Hall sensor encoder output to J10 on the inverter board.
5. If you are using a quadrature encoder sensor, connect the quadrature encoder pins (G, I, A, 5V, B) to J4 on the inverter board.

For the LAUNCHXL-F28379D configuration:

1. Attach the inverter board to the controller board such that J1, J2 of BOOSTXL aligns with J1, J2 of LAUNCHXL.
2. Connect the motor three phases to MOTA, MOTB, and MOTC on the BOOSTXL inverter board.
3. Connect the DC power supply to PVDD and GND on the BOOSTXL inverter board.
4. If you are using a Hall sensor, connect the Hall sensor output to QEP_B (configured as eCAP) on LAUNCHXL.

5. If you are using a quadrature encoder sensor, connect the quadrature encoder pins (G, I, A, 5V, B) to QEP_A on the LAUNCHXL controller board.

For more details regarding these connections, see “Hardware Connections” on page 7-2.

For more details regarding the model settings, see “Model Configuration Parameters” on page 2-2.

For LAUNCHXL-F28379D, load a sample program to CPU2, for example, program that operates the CPU2 blue LED using GPIO31 (`c28379D_cpu2_blink.slx`) to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

Parameter Estimation Tool

The parameter estimation tool includes a target model and a host model. The models communicate with each other by using a serial communication interface. For more details, see “Host-Target Communication” on page 6-2.

Enter the details about the hardware setup and the motor under test in the host model. The target model uses an algorithm to perform tests on the motor and estimate the motor parameters. The host model starts the required tests and displays the estimated parameters.

Prepare Workspace

Open the parameter estimation host model. You can also use this command to open the host model:

```
open_system('mcb_param_est_host_read.slx');
```

The screenshot displays the Parameter Estimation Tool interface, divided into three main sections:

- Select Board:** Shows the selected board as "DRV8305 and F283..." and the communication port as "Serial Setup" (HOST).
- Required Inputs:** Lists various input parameters:
 - Input DC Voltage: 24 V
 - Nominal Current: 7.1 A (peak value)
 - Nominal Speed: 4000 rpm
 - Pole pairs: 4
 - Nominal Voltage: 24 V
 - Sensor Selection: Sensor...
- Test Status:** Features a "Run" button and a "Stop" button. Below it, a table of "Estimated Motor Parameters" is shown:

Parameter	Value	Unit
Rs	--	Ohm
Ld	--	H
Lq	--	H
Bemf	--	Vpk_LL/krpm
Motor Inertia	--	Kg.m^2
Friction constant	--	N.m.s
- Fault Status:** Lists fault types: Over Current, Under Voltage, and Serial communication.
- Signal from Target:** Shows a "Speed" dropdown menu and a "SelectedSignal" box.

At the bottom, there are links for "Target Models" and "Models to calibrate Hall Offset" and "Models to calibrate QEP Offset".

Enter these details in the host model to prepare the workspace:

- **Select Board** — Select the target hardware and inverter combination.
- **Communication Port** — In the Host Serial Setup block parameter dialog box, select a serial **Port name** to which the hardware is connected. Select an available port from the list. For more details, see “Find Communication Port” on page 6-4.
- **Required Inputs** — Enter the motor specification and hardware setup data. You can obtain these values either from the motor datasheet or from the motor nameplate.
 - **Input DC Voltage** — The DC supply voltage for the inverter (Volts).
 - **Nominal Current** — The rated current of the motor (Ampere).
 - **Nominal Speed** — The rated speed of the motor (RPM).
 - **Pole Pairs** — The number of pole pairs of the motor.
 - **Nominal Voltage** — The rated voltage of the motor (Volts).
 - **Position Offset** — The position (Hall or quadrature encoder) sensor offset value (per-unit position) (see “Hall Offset Calibration for PMSM Motor” on page 4-67, “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76, and “Per-Unit System” on page 6-16).
 - **Sensor Selection** — The type of position sensor that you are using. You can select one of these values:
 - QEP — Select this option if you are using the quadrature encoder sensor attached to your motor.
 - HALL — Select this option if you are using the Hall sensors available in your motor.
 - **Sensorless** — Select this option if you want to use the Flux Observer sensorless position estimation block instead of a position sensor. For details about this block, see Flux Observer Flux Observer.
 - **Total QEP Slits** — The number of slits available in the quadrature encoder sensor. By default, this field has a value 1000.

NOTE: When updating **Required Inputs**, consider these limitations:

- The rated speed of the motor must be less than 25000 RPM.
- The tests protect the hardware from over-current faults. However, to ensure that these faults do not occur, keep the motor's rated current (entered in **Nominal Current** field) less than the maximum current supported by the inverter.
- If you have an SMPS-based DC power supply unit, set a safe current limit on the power supply for safety reasons.

Deploy Target Models

Before starting the tests by using the parameter estimation tool, you need to download the binary files (.hex/ .out) generated by the target model into the target hardware. There are two workflows to download the binary files:

Workflow 1: Build and Deploy Target Model

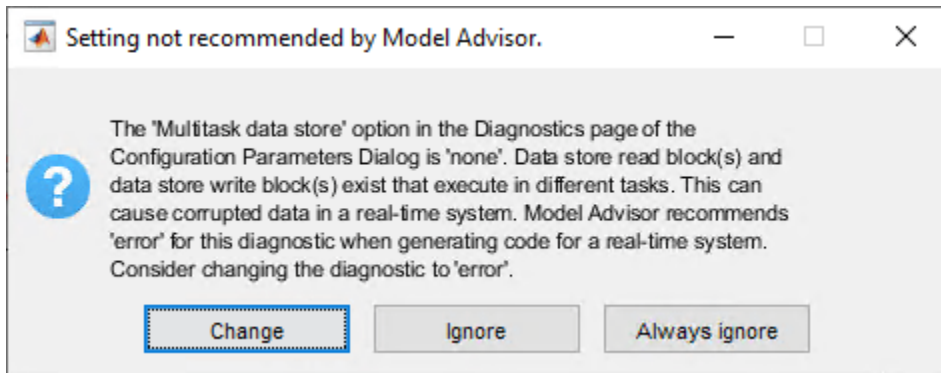
Use this workflow to generate and deploy the code for the target model. Ensure that you press **Ctrl +D** to update the workspace with the required input values from the host model.

Click one of these hyperlinks in the parameter estimation host model to open the target model (for the hardware that you are using):

- For F28069M-based controller attached to either Hall or quadrature encoder sensor:
[mcb_param_est_f28069_DRV8312](#)
- For F28069M-based controller that uses the sensorless Flux Observer block:
[mcb_param_est_sensorless_f28069_DRV8312](#)
- For F28379D-based controller attached to either Hall or quadrature encoder sensor:
[mcb_param_est_f28379D_DRV8305](#)
- For F28379D-based controller that uses the sensorless Flux Observer block:
[mcb_param_est_sensorless_f28379D_DRV8305](#)

Click **Build, Deploy & Start** in the **Hardware** tab to deploy the target model to the hardware.

NOTE: Ignore the warning message **Multitask data store option in the Diagnostics page of the Configuration Parameter Dialog is none** displayed by the model advisor, by clicking the **Always Ignore** button. This is part of the intended workflow.



Workflow 2: Manually Download Target Model

Use this workflow to deploy the binary files (.hex/ .out) of the target model manually by using a third party tool (the workflow does not need code-generation). This workflow is only valid for Teknic M-2310P motor.

- Locate the binary files (.hex/ .out) at these locations:
 - < matlabroot > \toolbox\mcb\mcbexamples\mcb_param_est_f28069_DRV8312.out
 - < matlabroot > \toolbox\mcb\mcbexamples
\mcb_param_est_sensorless_f28069_DRV8312.out
 - < matlabroot > \toolbox\mcb\mcbexamples\mcb_param_est_f28379D_DRV8305.out
 - < matlabroot > \toolbox\mcb\mcbexamples
\mcb_param_est_sensorless_f28379D_DRV8305.out

NOTE: The files `mcb_param_est_f28069_DRV8312.out` and `mcb_param_est_f28379D_DRV8305.out` use a fixed quadrature encoder slits count of 1000. Therefore, when you set the required input **Sensor Selection** to **QEP** in the host model, you can use these files only for motors connected to a quadrature encoder sensor with 1000 slits (for example, the Teknic M-2310P motor).

- Open a third-party tool to deploy the binary files (`.hex/ .out`).
- Download and run the binary files (`.hex/ .out`) on the target hardware.

Estimate Motor Parameters

Use the following steps to run the Motor Control Blockset parameter estimation tool:

1. Ensure that you deploy the binary files (`.hex/ .out`) generated from the target model, to the target hardware and update the required details in the host model.
2. In the host model, check if the **Run-Stop** slider switch position is **Run**. Then, click **Run** in the **Simulation** tab to run the parameter estimation tests.
3. The parameter estimation process takes less than a minute to perform the tests. You can ignore the beep sound produced during the tests.
4. The host model displays the estimated motor parameters after successfully completing the tests.

The tool uses the following algorithm to estimate parameters:

- Phase resistance, R_s — The tool uses Ohm's law to estimate this value.
- d axis inductance, L_d — The tool uses frequency injection method to estimate these values.
- q axis inductance, L_q — The tool uses frequency injection method to estimate these values.
- Back-EMF constant, K_e — The tool measures the currents and voltages and uses the electric motor equation to estimate this value.
- Motor inertia, J — The tool estimates this value by using retardation test.
- Friction constant, B — The tool estimates this value by using the torque equation for a motor running at a constant speed.

When the parameter estimation tests complete, the **Test Status** LED turns green.

If the tests are interrupted, the **Test Status** LED turns red. When the LED turns red, run the host model again to rerun the parameter estimation tests.

During an emergency, you can manually turn the **Run-Stop** slider switch to **Stop** position to stop the parameter estimation tests. In addition, the model interrupts the parameter estimation tests and turns these LEDs red to protect the hardware from the following faults:

1. Over-current fault (this fault occurs when actual current drawn from the power supply is more than the **Nominal Current** value mentioned in the **Required Inputs** section of the host model)
2. Under-voltage fault (this fault occurs when input DC voltage drops below 80% of the **Input DC Voltage** value mentioned in the **Required Inputs** section of the host model)

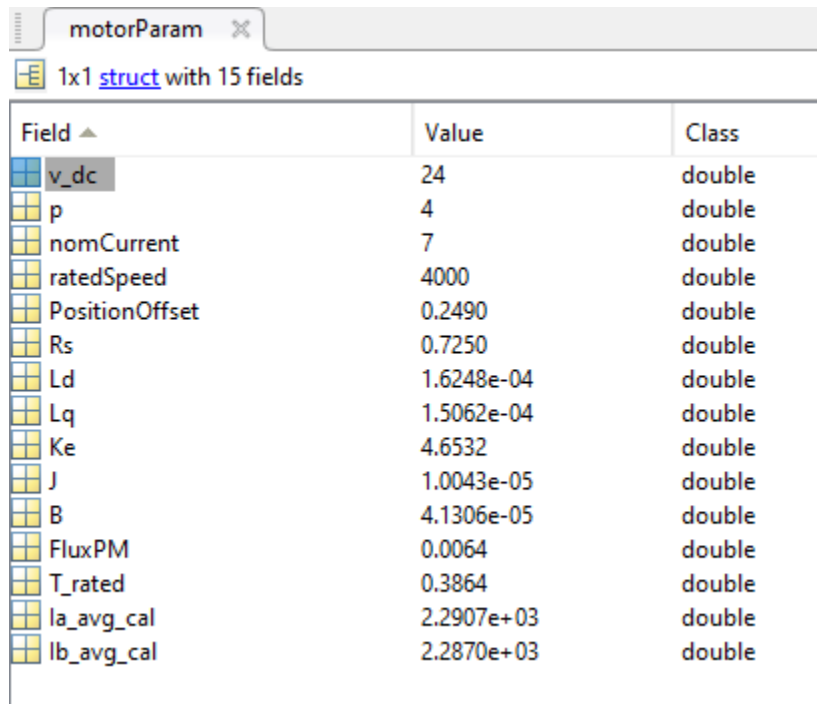
3. Serial communication fault

Save Estimated Parameters

You can export the estimated motor parameters and further use them for the simulation and control system design.

To export, click **Save Parameters** to save the estimated parameters into a MAT (.mat) file.

To view the saved parameters, load the MAT (.mat) file in the MATLAB® workspace. MATLAB saves the parameters in a structure named `motorParam` in the workspace.



The screenshot shows a MATLAB workspace window titled 'motorParam'. Below the title bar, it indicates '1x1 struct with 15 fields'. A table displays the fields and their corresponding values and classes.

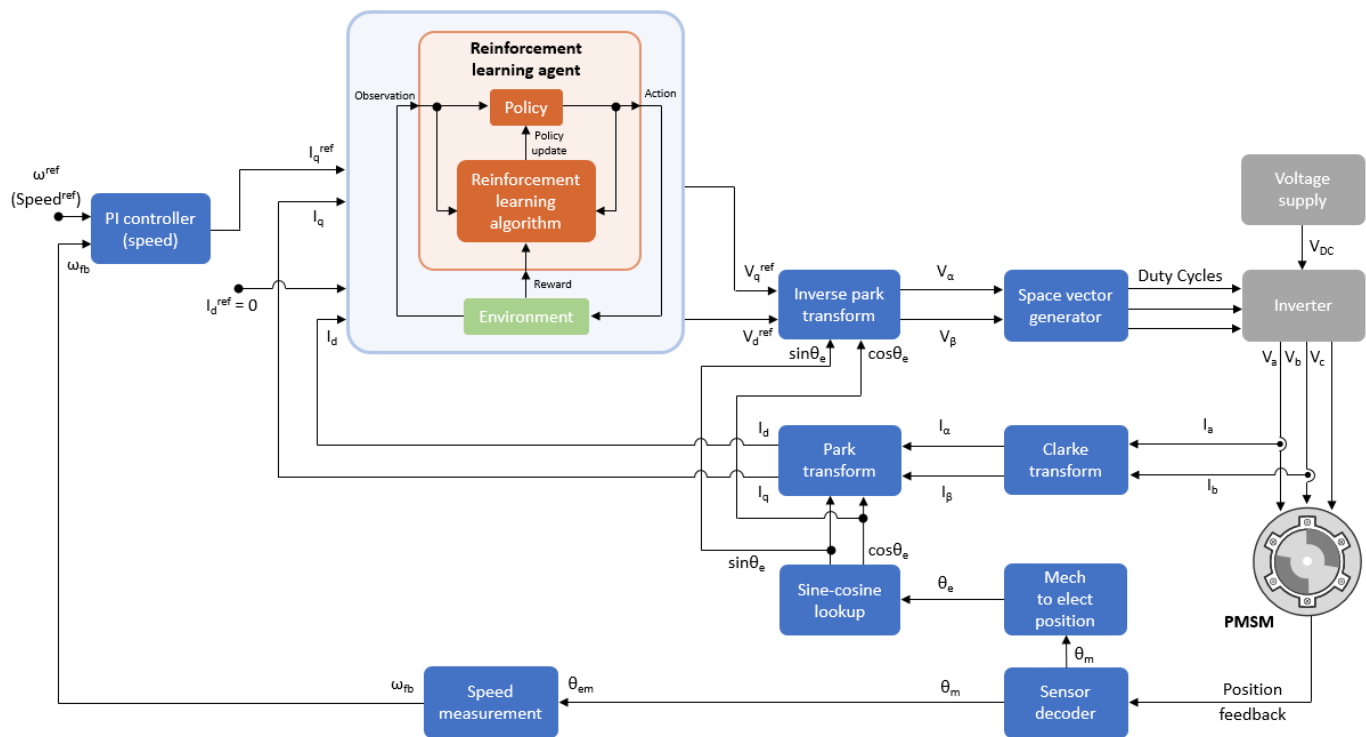
Field	Value	Class
v_dc	24	double
p	4	double
nomCurrent	7	double
ratedSpeed	4000	double
PositionOffset	0.2490	double
Rs	0.7250	double
Ld	1.6248e-04	double
Lq	1.5062e-04	double
Ke	4.6532	double
J	1.0043e-05	double
B	4.1306e-05	double
FluxPM	0.0064	double
T_rated	0.3864	double
Ia_avg_cal	2.2907e+03	double
Ib_avg_cal	2.2870e+03	double

Click **Open Model** to create a new Simulink® model with a PMSM motor block. The motor block uses the `motorParam` structure variables from the MATLAB workspace.

Field-Oriented Control of PMSM Using Reinforcement Learning

This example shows you how to use the control design method of reinforcement learning to implement field-oriented control (FOC) of a permanent magnet synchronous motor (PMSM). The example uses FOC principles. However, it uses the reinforcement learning (RL) agent instead of the PI controllers. For more details about FOC, see “Field-Oriented Control (FOC)” on page 4-2.

This figure shows the FOC architecture with the reinforcement learning agent. For more details about the reinforcement learning agents, see “Reinforcement Learning Agents” (Reinforcement Learning Toolbox).



The reinforcement learning agent regulates the d-axis and q-axis currents and generates the corresponding stator voltages that drive the motor at the required speed.

The speed-tracking performance of an FOC algorithm that uses a reinforcement learning agent is similar to that of a PI-controller-based FOC.

Model

The example includes the `mcb_pmsm_foc_sim_RL` model.

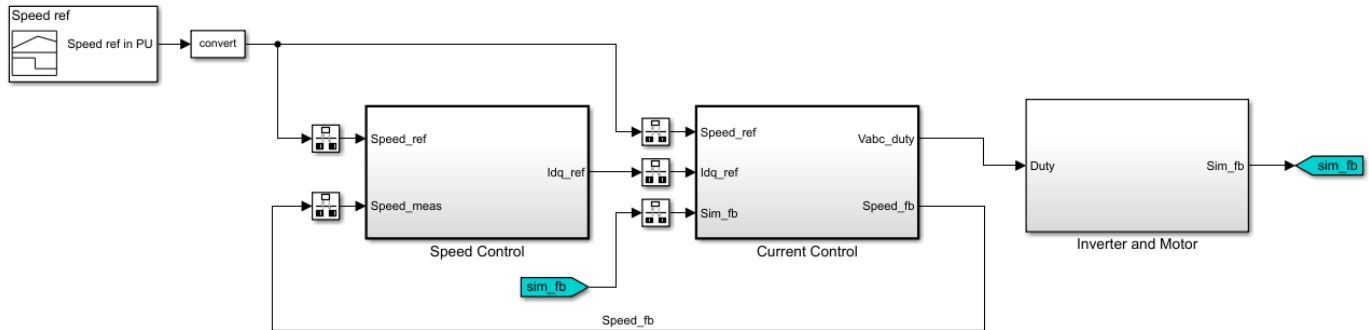
Note: You can use this model only for simulation.

This model includes the FOC architecture that uses the reinforcement learning agent. You can use the `open_system` command to open the Simulink® model.

```
mdl = 'mcb_pmsm_foc_sim_RL';
open_system(mdl);
```

Permanent Magnet Synchronous Motor - Reinforcement Learning

Note: This example demonstrates PMSM speed control with Reinforcement learning control



Steps:

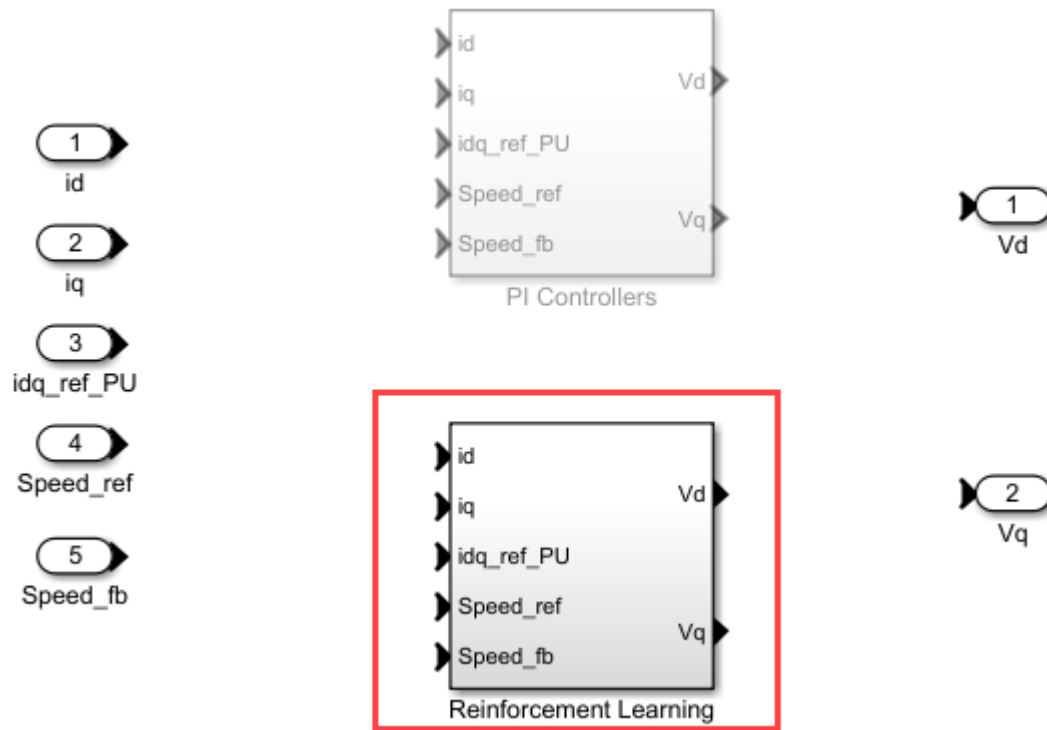
1. Use [live script](#), compare Reinforcement learning and PI
2. [Learn more](#) about this example.

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When you open the model, it loads the configured parameters including the motor parameters to the workspace for simulation. To view and update these parameters, open the `mcb_pmsm_foc_sim_RL_data.m` model initialization script file. For details about the control parameters and variables available in this script, see “Estimate Control Gains from Motor Parameters” on page 3-2.

You can access the reinforcement learning setup available inside the Current Controller Systems subsystem by running this command.

```
open_system('mcb_pmsm_foc_sim_RL/Current Control/Control_System/Closed Loop Control/Current Cont
```



For more information about setting up and training a reinforcement learning agent to control a PMSM, see “Train TD3 Agent for PMSM Control” (Reinforcement Learning Toolbox).

Note:

- Training a reinforcement learning agent is a computationally intensive process that may take several hours to complete.
- The agent in this example was trained using the PWM frequency of 5 KHz. Therefore, the model uses this frequency by default. To change this value, train the reinforcement learning agent again by using a different PWM frequency and update the `PWM_f` frequency variable in the `mcb_pmsm_foc_sim_RL_data.m` model initialization script. You can use the following command to open the model initialization script.

```
edit mcb_pmsm_foc_sim_RL_data;
```

Required Mathworks® Products

- Motor Control Blockset™
- Reinforcement Learning Toolbox™

Simulate Model

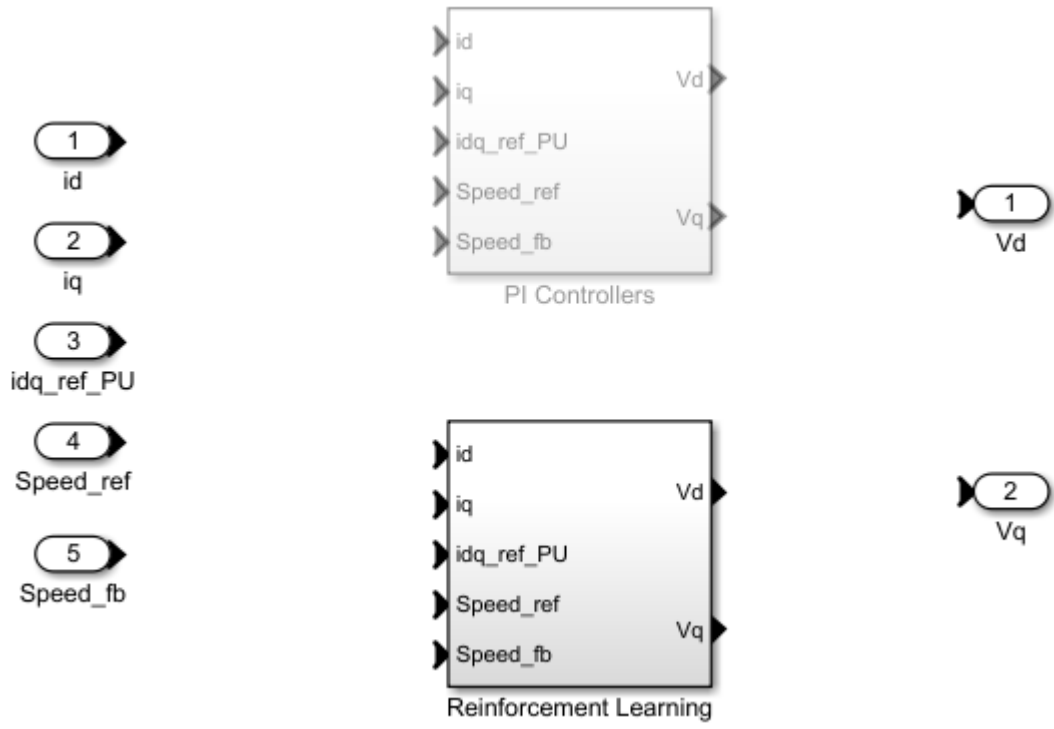
Follow these steps to simulate the model.

1. Open the model included with this example.
2. Run this command to select the Reinforcement Learning variant of the Current Controller Systems subsystem available inside the FOC architecture.

```
ControllerVariant='RL';
```

You can navigate to the Current Controller Systems subsystem to verify if the Reinforcement Learning subsystem variant is active.

```
open_system('mcb_pmsm_foc_sim_RL/Current Control/Control_System/Closed Loop Control/Current Cont
```



Note: The model selects the Reinforcement Learning subsystem variant by default.

3. Run this command to load the pre-trained reinforcement learning agent.

```
load('agent.mat');
```

Note: The reinforcement learning agent in this example was trained to use the speed references of 0.2, 0.4, 0.6, and 0.8 PU (per-unit). For information related to the per-unit system, see “Per-Unit System” on page 6-16.

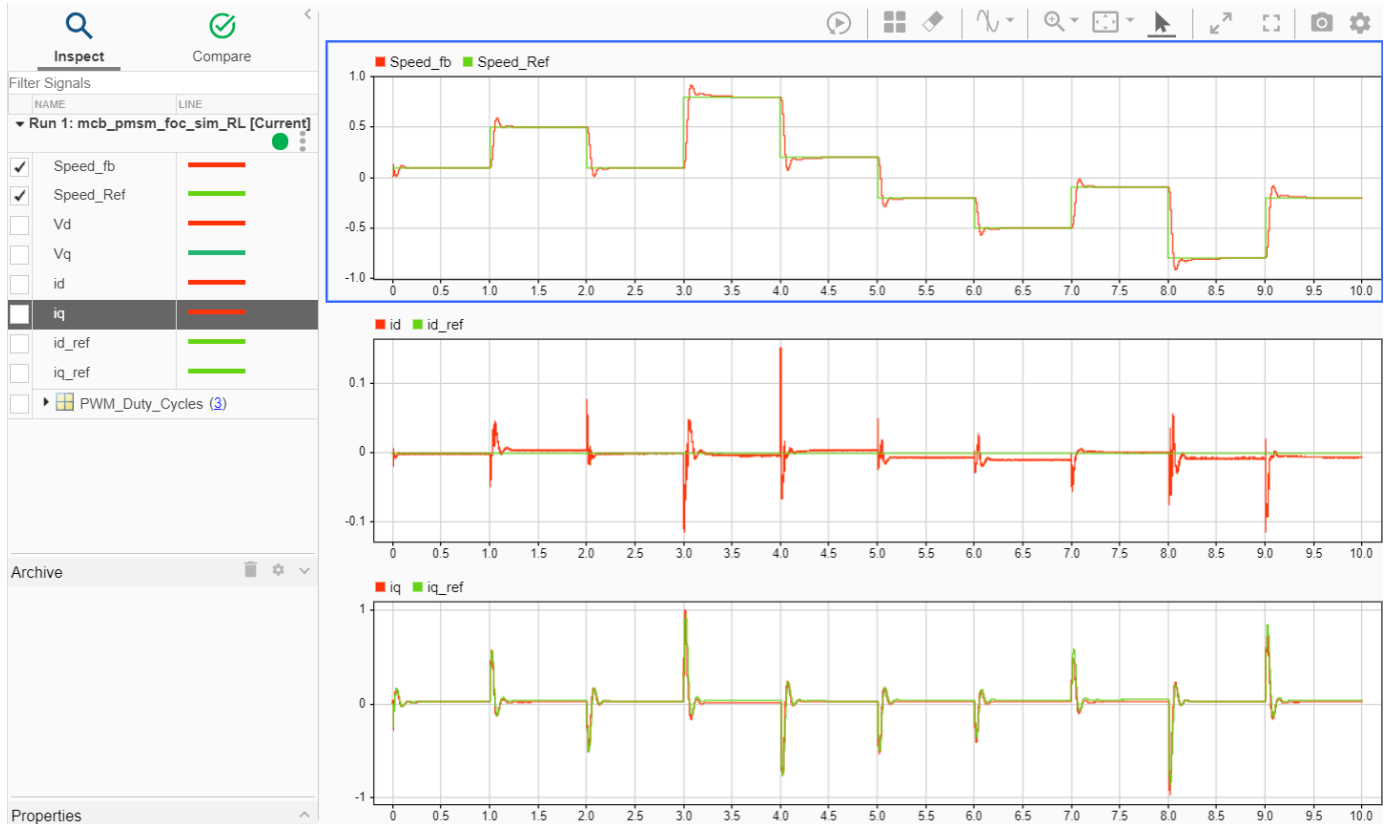
4. Click **Run** on the **Simulation** tab to simulate the model. You can also run this command to simulate the model.

```
sim mdl;
```

5. Click **Data Inspector** on the **Simulation** tab to open the Simulation Data Inspector. Select one or more of these signals to observe and analyze the simulation results related to speed tracking and controller performance.

- Speed_ref
- Speed_fb
- iq_ref

- i_q
- i_d _ref
- i_d



In the preceding example:

- The combination of PI and reinforcement learning controllers achieve the required speed by tracking the changes to the speed reference signal.
- The second and third data inspector plots show that the trained reinforcement learning agent acts as a current controller and successfully tracks both the I_d and I_q reference currents. However, a small steady state error exists between the reference and actual values of I_d and I_q currents.

Use Simulation to Compare RL Agent with PI Controllers

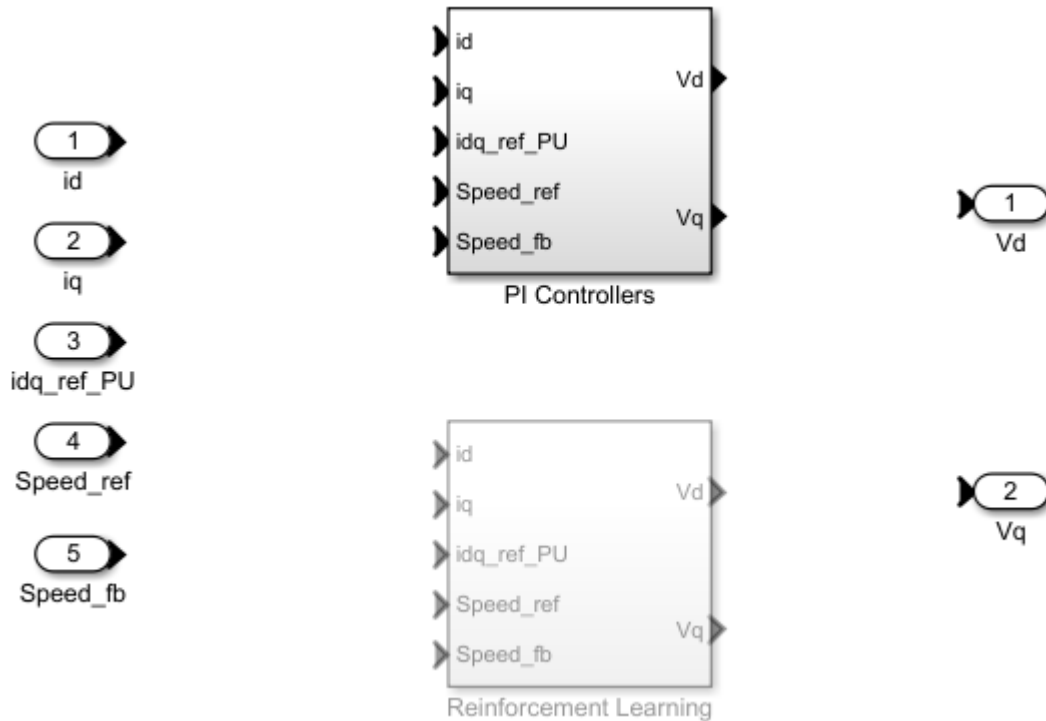
Use these steps to analyze the speed tracking and controller performance of PI controllers and compare them with that of reinforcement learning agent:

1. Open the model included with this example.
2. Run this command to select the PI Controllers variant of the Current Controller Systems subsystem available inside the FOC architecture.

```
ControllerVariant='PI';
```

You can navigate to the Current Controller Systems subsystem to verify if the PI Controllers subsystem variant is active.

```
open_system('mcb_pmsm_foc_sim_RL/Current Control/Control_System/Closed Loop Control/Current Cont
```



NOTE: The model selects the Reinforcement Learning subsystem variant by default.

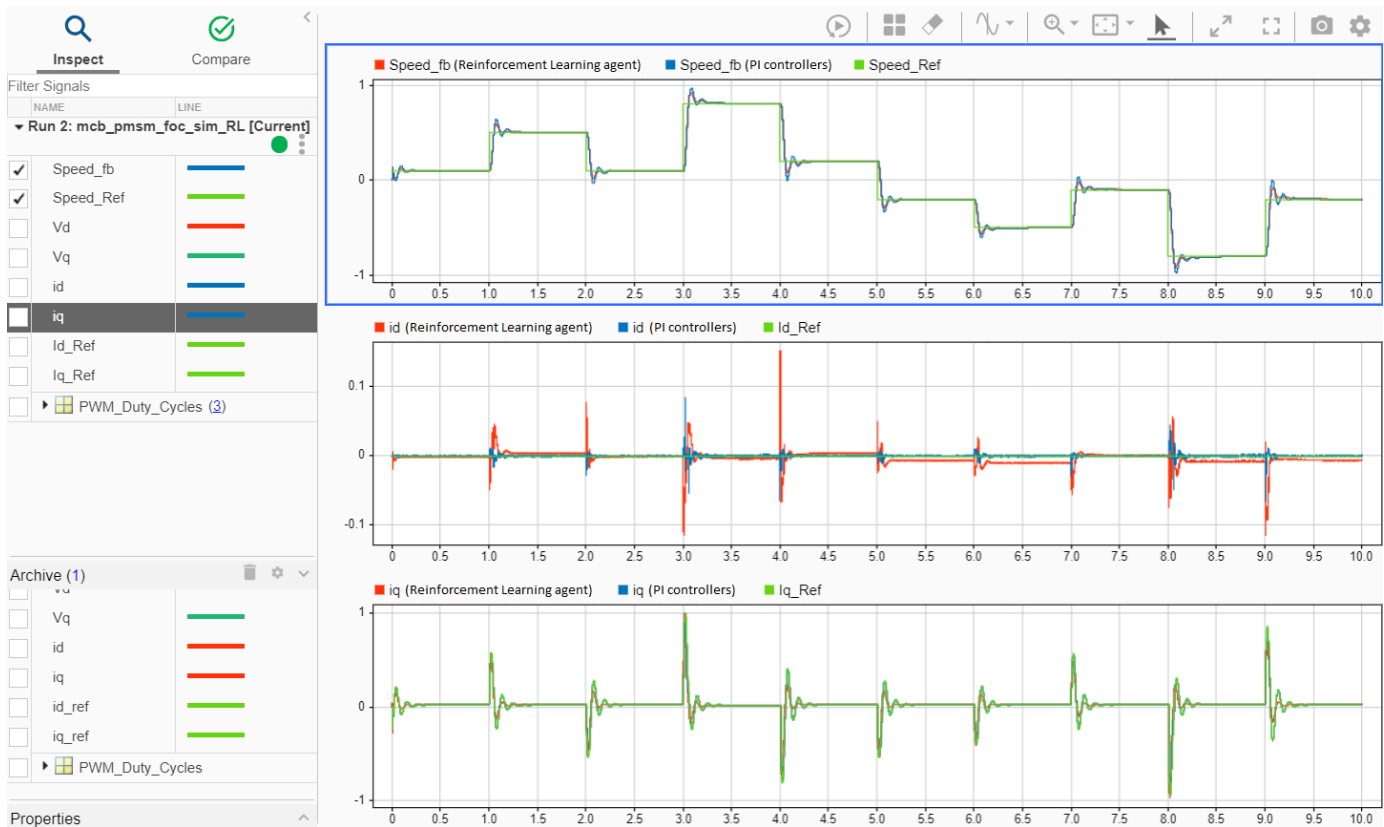
3. Click **Run** on the **Simulation** tab to simulate the model. You can also run this command to simulate the model.

```
sim mdl;
```

4. Click **Data Inspector** on the **Simulation** tab to open the Simulation Data Inspector. Select one or more of these signals to observe and analyze the simulation results related to speed tracking and controller performance.

- Speed_ref
- Speed_fb
- iq_ref
- iq
- id_ref
- id

5. Compare these results with the previous simulation run results obtained by using the RLAgent (Reinforcement Learning) subsystem variant.



In the preceding example:

- The red signals show the simulation results that you obtain using the RLAgent (Reinforcement Learning) subsystem variant.
- The blue signals show the simulation results that you obtain using the PIControllers (PI Controllers) subsystem variant.
- The plots indicate that (with an exception of Id reference current tracking) the performance of reinforcement learning agent is similar to the PI controllers. You can improve the current tracking performance of the reinforcement learning agent by further training the agent and tuning the hyperparameters.

NOTE: You can also update the reference speed to higher values and similarly compare the performances between reinforcement learning agent and PI controllers.

Estimate Induction Motor Parameters Using Recommended Hardware

This example determines the parameters of a three-phase AC induction motor (ACIM) using the recommended Texas Instruments™ hardware. The example determines these parameters:

- Stator resistance R_s (Ohm)
- Rotor resistance R_r (Ohm)
- Magnetizing inductance L_m (H)
- Stator leakage inductance L_{ls} (H)
- Rotor leakage inductance L_{lr} (H)
- Motor inertia J (Kg.m²)
- Friction constant B (N.m.s)

The example accepts the minimum required motor and hardware parameters, runs tests on the target hardware, and displays the estimated parameters.

Note: This example does not support simulation. Use the supported hardware configuration to run this example.

Prerequisites

- Ensure that the motor is in the no-load condition.
- Ensure that the motor has a quadrature encoder sensor. The parameter estimation tool needs the quadrature encoder sensor to measure the rotor speed.

Supported Hardware

This example supports only the following hardware configuration:

- LAUNCHXL-F28379D controller
- BOOSTXL-DRV8305 inverter
- A three-phase AC induction motor with a quadrature encoder sensor
- DC power supply

Required MathWorks® Product

To run parameter estimation, you need:

- Motor Control Blockset™
- Embedded Coder®

- Embedded Coder Support Package for Texas Instruments C2000™ Processors

Prepare Hardware

1. Attach the inverter board to the controller board such that J1 and J2 of BOOSTXL align with J1 and J2 of LAUNCHXL.
2. Connect the motor three phases to MOTA, MOTB, and MOTC on the BOOSTXL inverter board.
3. Connect the DC power supply to PVDD and GND on the BOOSTXL inverter board.
4. Connect the quadrature encoder pins (G, I, A, 5V, B) to QEP_A on the LAUNCHXL controller board.

For more details regarding these connections, see “Hardware Connections” on page 7-2.

For more details regarding the model settings, see “Model Configuration Parameters” on page 2-2.

For LAUNCHXL-F28379D, load a sample program to CPU2, for example, the program that operates the CPU2 blue LED using GPIO31 (`c28379D_cpu2_blink.slx`) to ensure that CPU2 is not mistakenly configured to use the board peripherals intended for CPU1.

Parameter Estimation Tool

The parameter estimation tool includes a target model and a host model. The models communicate with each other by using a serial communication interface. For more details, see “Host-Target Communication” on page 6-2.

Enter the details about the hardware setup and the motor under test in the host model. The target model uses an algorithm to perform tests on the motor and estimate the motor parameters. The host model starts the required tests and displays the estimated parameters.

Prepare Workspace

Open the parameter estimation host model. You can also use this command to open the host model:

```
open_system('mcb_acim_param_est_host_read.slx');
```

ACIM Parameter Estimation

Communication Port

Serial Setup: HOST

Required Inputs

Nominal Voltage: 16.97 V (Line-Line RMS)

Input DC Voltage: 24 V

Nominal Current: 1.8 A (phase peak value)

Nominal Magnetizing Current (Id0): 1.08 A (phase peak value)

Pole pairs: 2

Rated Frequency: 50 Hz

Total QEP Slits: 1000

Steps

1. Provide required inputs.
2. Press **Ctrl+D** to update the workspace
3. Build, Deploy & Start required target models
4. Run this model to estimate motor parameters

Note

1. It is recommended to set the power supply DC bus voltage as:
Input DC Voltage (V)
 $= \sqrt{2} * \text{Nominal Voltage of motor (Line-Line RMS V)}$
2. For some phase sequences, the parameter estimation tool may not compute the inertia and friction constant parameters. Interchange any two motor phase connections and try running the parameter estimation host model again to estimate these parameters.

Test Status

Run Stop

Estimated Motor Parameters

Parameter	Value	Unit
Rs	--	Ohm
Rr	--	Ohm
Lm	--	H
Lls	--	H
Llr	--	H
Motor Inertia	--	Kg.m ²
Friction constant	--	N.m.s

Save Parameters Open Model

Signal Conditioning and Scaling

SelectedSignal

Fault Status

- Over Current
- Under Voltage
- Serial communication

Signal from Target

Iq

SelectedSignal

Signal

Target Model (F28379D + DRV8305): [mcb_acim_param_est_f28379D_Drv8305](#)

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Enter these details in the host model to prepare the workspace.

- **Communication Port** — In the Host Serial Setup block parameter dialog box, select the serial **Port name** to which the hardware is connected. Select an available port from the list. For more details, see “Find Communication Port” on page 6-4.
- **Required Inputs** — Enter the motor specification and hardware setup data. You can obtain these values either from the motor datasheet or from the motor nameplate.
 - **Nominal Voltage** — The rated voltage (line-to-line RMS value) of the motor (Volts).
 - **Input DC Voltage** — The DC supply voltage for the inverter (Volts).
 - **Nominal Current** — The rated current (phase peak value) of the motor (Ampere).
 - **Nominal Magnetizing Current (Id0)** — The rated magnetizing current of the motor (Ampere). For detailed instructions to compute this value, see the Compute Nominal Magnetizing Current (Id0) section.
 - **Pole Pairs** — The number of pole pairs of the motor.

- **Rated Frequency** — The rated frequency of operation of the motor (Hertz).

- **Total QEP Slits** — The number of slits available in the quadrature encoder sensor. By default, this field has a value 1000.

Note: When updating **Required Inputs**, consider these limitations:

- The tests protect the hardware from over-current faults. However, to ensure that these faults do not occur, keep the rated current of the motor (entered in **Nominal Current** field) less than the maximum current supported by the inverter.
- If you have an SMPS-based DC power supply unit, set a safe current limit on the power supply for safety reasons.

Deploy Target Models

Before starting the tests by using the parameter estimation tool, you need to download the binary files (.hex/ .out) generated by the target model into the target hardware. There are two workflows to download the binary files:

Workflow 1: Build and Deploy Target Model

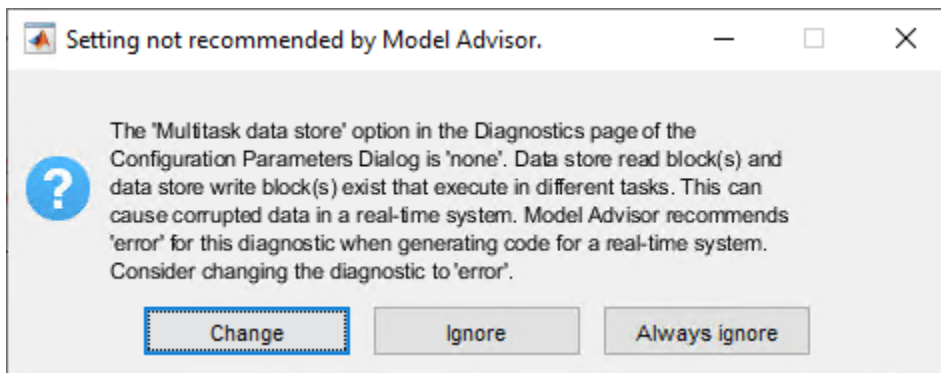
Use this workflow to generate and deploy the code for the target model. Ensure that you press **Ctrl +D** to update the workspace with the required input values from the host model.

Click this hyperlink available in the parameter estimation host model to open the target model:

- [mcb_acim_param_est_f28379D_DRV8305](#)

Click **Build, Deploy & Start** in the **Hardware** tab to deploy the target model to the hardware.

Note: Ignore the warning message Multitask data store option in the Diagnostics page of the Configuration Parameter Dialog is none displayed by the model advisor, by clicking the **Always Ignore** button. This is part of the intended workflow.



Workflow 2: Manually Download Target Model

Use this workflow to deploy the binary files (.hex/ .out) of the target model manually by using a third party tool (the workflow does not need code-generation).

- Locate the binary files (.hex/ .out) at this location:

```
- < matlabroot >\toolbox\mcb\mcbexamples  
\mcb_acim_param_est_f28379D_DRV8305.out
```

The `mcb_acim_param_est_f28379D_DRV8305.out` file uses fixed quadrature encoder slits count of 1000, therefore you can use this file only for motors connected to a quadrature encoder with 1000 slits.

- Open a third-party tool to deploy the binary files (.hex/ .out).
- Download and run the binary files (.hex/ .out) on the target hardware.

Estimate Motor Parameters

Use the following steps to run the Motor Control Blockset parameter estimation tool:

1. Ensure that you deploy the binary files (.hex/ .out) generated from the target model to the target hardware and update the required details in the host model.
2. In the host model, check if the **Run-Stop** slider switch position is **Run**. Then, click **Run** in the **Simulation** tab to run the parameter estimation tests.
3. The host model displays the estimated motor parameters after successfully completing the tests.

When the parameter estimation tests complete, the **Test Status** LED turns green.

If the tests are interrupted, the **Test Status** LED turns red. When the LED turns red, run the host model to rerun the parameter estimation tests.

During an emergency, you can manually turn the **Run-Stop** slider switch to the **Stop** position to stop the parameter estimation tests. In addition, the model interrupts the parameter estimation tests and turns these LEDs red to protect the hardware from the following faults:

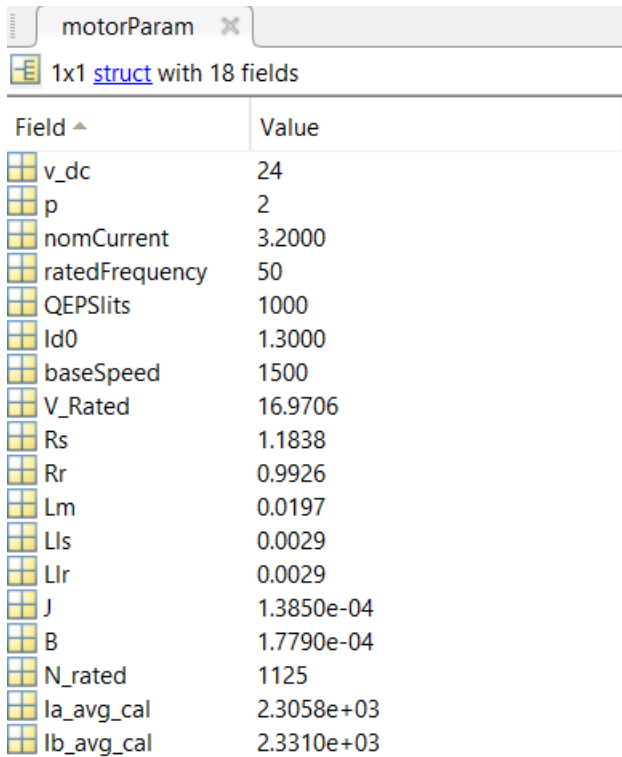
1. Over-current fault (this fault occurs when actual current drawn from the power supply is more than the **Nominal Current** value specified in the **Required Inputs** section of the host model)
2. Under-voltage fault (this fault occurs when input DC voltage drops below 80% of the **Input DC Voltage** value specified in the **Required Inputs** section of the host model)
3. Serial communication fault

Save Estimated Parameters

You can export the estimated motor parameters and then use them for the simulation and control system design.

To export, click **Save Parameters** to save the estimated parameters in a MAT (.mat) file.

To view the saved parameters, load the MAT (.mat) file in the MATLAB® workspace. MATLAB saves the parameters in a structure named `motorParam` in the workspace.



Field ^	Value
v_dc	24
p	2
nomCurrent	3.2000
ratedFrequency	50
QEPSlits	1000
Id0	1.3000
baseSpeed	1500
V_Rated	16.9706
Rs	1.1838
Rr	0.9926
Lm	0.0197
Lls	0.0029
Llr	0.0029
J	1.3850e-04
B	1.7790e-04
N Rated	1125
la_avg_cal	2.3058e+03
lb_avg_cal	2.3310e+03

Click **Open Model** to create a new Simulink® model with an Induction Motor block. The block uses the motorParam structure variables from the MATLAB workspace.

Note:

- For some phase sequences, the parameter estimation tool may not compute the **Motor Inertia** and **Friction Constant** parameters. Interchange any two motor phase connections and try running the parameter estimation host model again to estimate these parameters.
- Under the following conditions, slightly increase the **Nominal Current** required input in the host model (for example, increase by 10% of the original value) and run the parameter estimation tests again:
 - When the host model runs and executes the tests, the **Speed** debug signal (in the time scope available in the host model) does not reach a stable value of around 0.6 per-unit (PU).
 - When running the host model multiple times, the **Motor Inertia** and **Friction Constant** values vary.

Repeat this step until the **Speed** signal stabilizes (at around 0.6 PU) in the time scope. This ensures that the computed **Motor Inertia** and **Friction Constant** values are accurate.

- It is recommended to set the power supply DC bus voltage to the following value:

$$\text{Input DC Voltage (V)} = (\sqrt{2}) \times [\text{Nominal Voltage of motor (V) (line – line RMS value)}]$$

- You can determine the total leakage inductance (in Henry) using the L_{ls} and L_{lr} values computed by the parameter estimation tool:

$$L_{ls} = L_{lr} = \left(\frac{\text{Total leakage inductance}}{2} \right)$$

- The parameter estimation tool does not estimate rated slip (`slip_rated`). The tool computes the rated speed $((1 - \text{slip_rated}) \times \text{synchronous speed})$ assuming that `slip_rated = 0.25`. We recommend that you measure `slip_rated` or obtain it from the motor datasheet.

Compute Nominal Magnetizing Current (I_{d0})

You can obtain the value of the nominal magnetizing current (I_{d0}) of the motor under test either from the motor datasheet or by performing the standard no-load tests and experiments. Optionally, you can follow this alternative procedure to manually compute the I_{d0} value.

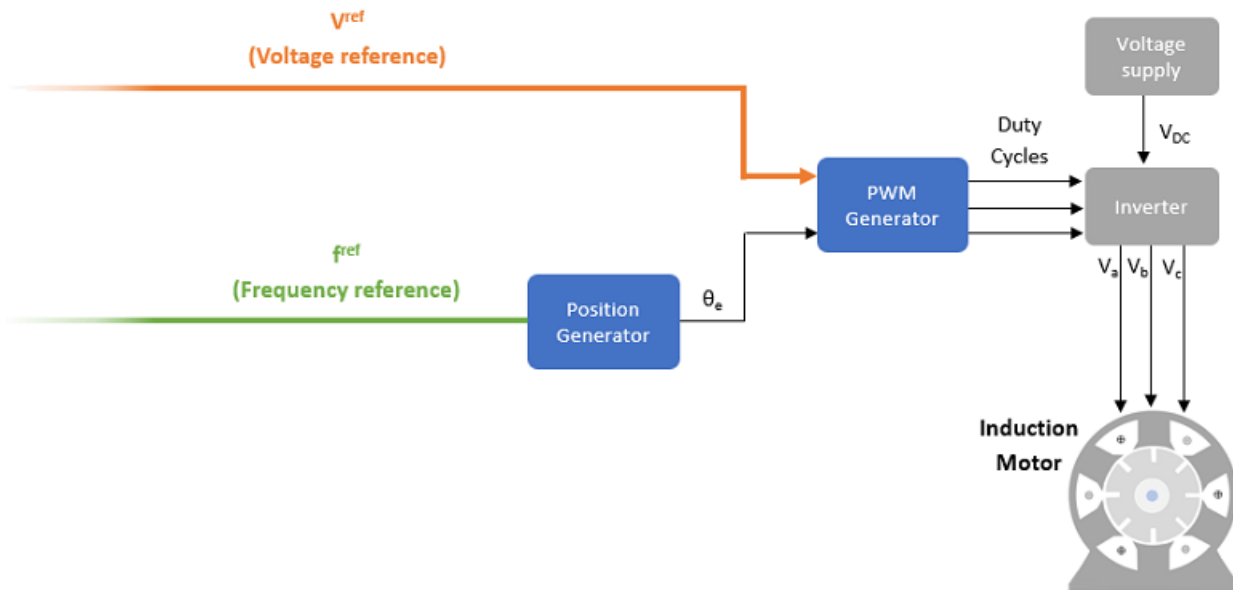
1. You can configure the target model included in the example “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6 with the parameters of the motor under test and separate out the paths for frequency reference (f^{ref}) and voltage reference (V^{ref}) processing such that these signals become independent of each other.

In addition, use the ADC driver blocks (available in the target model) to compute the real-world value of the phase current of the motor. You can measure this value directly or send this value to the host model via serial communication for monitoring.

Note: The ADC offset depends on the ADC gain value `inverter.SPI_Gain_Setting` that you configure in the model initialization script associated with the target model. Changing ADC gain also changes the ADC offset.

2. Set f^{ref} to 50% of **Rated Frequency** and V^{ref} to 50% of **Nominal Voltage**.

3. Increase f^{ref} to **Rated Frequency** and V^{ref} to a value between 90% and 95% of **Nominal Voltage**.



4. Ensure that the motor is in no-load condition and the motor phase current is magnetizing current. After you run the model and the motor, monitor the phase current.

Measure the peak value of the phase current. You can consider this value as the nominal magnetizing current (I_{d0}) of the motor under test.

Estimate PMSM Parameters Using Custom Hardware

This example includes an algorithm to determine the parameters of a permanent magnet synchronous motor (PMSM) using any custom motor-control hardware (hardware not used in the Motor Control Blockset™ examples). The algorithm determines these parameters:

- Phase resistance, R_s (Ohm)
- d axis inductance, L_d (Henry)
- q axis inductance, L_q (Henry)
- Back-EMF constant, K_e (Vpk_LL/krpm, where Vpk_LL is the peak voltage line-to-line measurement)
- Motor inertia, J (Kg.m²)
- Friction constant, B (N.m.s)

The algorithm accepts the minimum required inputs and runs tests on the target hardware to estimate the PMSM parameters.

The example needs a quadrature encoder sensor to measure the rotor position and provide real-time rotor position feedback. This workflow helps you to integrate the parameter estimation algorithm with the drivers for your motor-control hardware. It supports any three-phase PMSM.

The workflow includes these four steps to prepare, deploy, and run the PMSM parameter estimation algorithm on your hardware:

1. Generate code for the parameter estimation algorithm using Embedded Coder®
2. Obtain C code for the custom hardware drivers
3. Integrate parameter estimation algorithm code with the driver code
4. Deploy the integrated code to hardware

Note: This workflow does not support simulation. You can use any motor-control hardware to run this example.

Prerequisites

- Ensure that the PMSM has a quadrature encoder sensor and calibrate the sensor.

The parameter estimation algorithm needs the motor position as detected by a quadrature encoder position sensor. To detect the motor position correctly by using the sensor, calibrate the quadrature encoder that is attached to the motor under test. For instructions, see “Quadrature Encoder Offset Calibration” on page 8-11.

- Calibrate the offset values of the ADC (or current sensor) peripheral available in your hardware. For instructions, see “Open-Loop Control and ADC Offset Calibration” on page 8-2.
- Ensure that the PMSM is in no-load condition.

Custom Hardware Configuration

- Controller hardware
- Inverter hardware
- A PMSM with a quadrature encoder sensor
- DC power supply

Required MathWorks® Products

To build the parameter estimation algorithm included in this example, you need these products:

- Motor Control Blockset™
- Fixed-Point Designer™
- Embedded Coder®

Open MATLAB® Project and Prepare Parameter Estimation Model

Use one of these methods to open the MATLAB project:

- Click **Open Example**.
- Run the command `mcb_ParameterEstimationAlgorithmStart` at the command prompt.

The MATLAB project opens and shows the following files:

- `parameter_estimation_algorithm.slx` (model containing the parameter estimation algorithm)
- `parameter_estimation_init.m` (model initialization script for the parameter estimation algorithm)

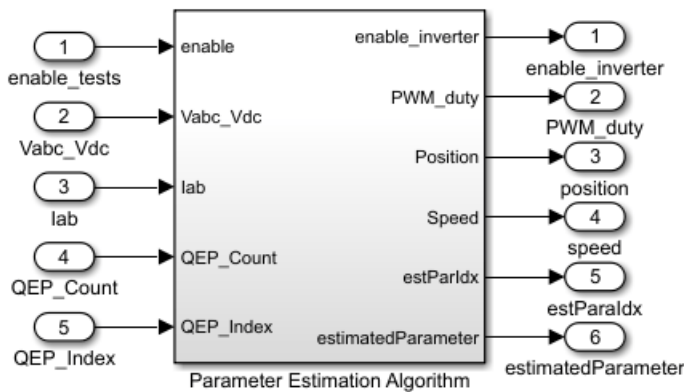
Note:

- Verify and update the motor, inverter, and other parameters related to the target hardware and parameter estimation algorithm in the model initialization script `parameter_estimation_init.m`.
- The rated speed of the motor (variable `motorParam.ratedSpeed`) must be less than 25000 RPM.
- The tests protect the hardware from over-current faults. However, to ensure that these faults do not occur, keep the rated current of the motor (variable `motorParam.nomCurrent`) less than the maximum current supported by the inverter.
- If you have an SMPS-based DC power supply unit, set a safe current limit on the power supply for safety reasons.

Generate Code For Parameter Estimation Algorithm Using Embedded Coder

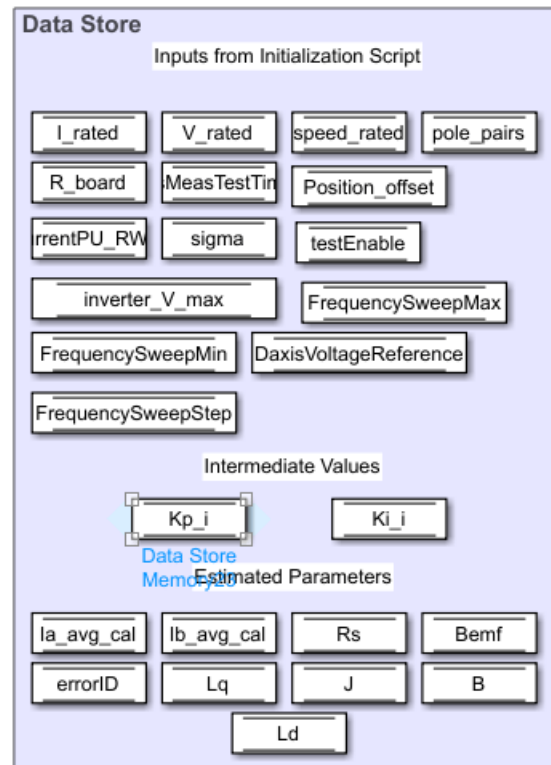
1. After you open the MATLAB project, double-click the `parameter_estimation_algorithm.slx` model.

Parameter Estimation Algorithm



Explore more:

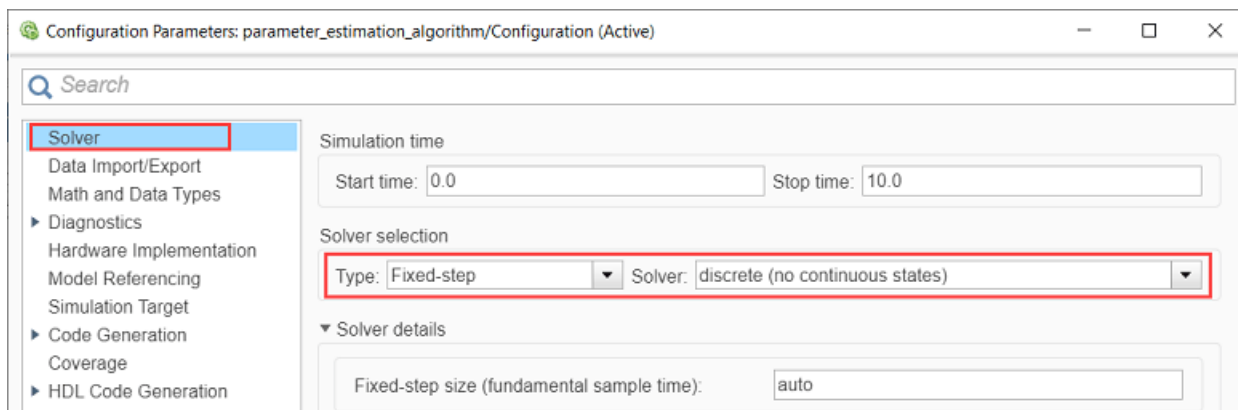
1. [Edit motor & inverter parameters](#)
2. Generate c code using the 'Embedded Coder' app
3. Integrate generated code with driver code



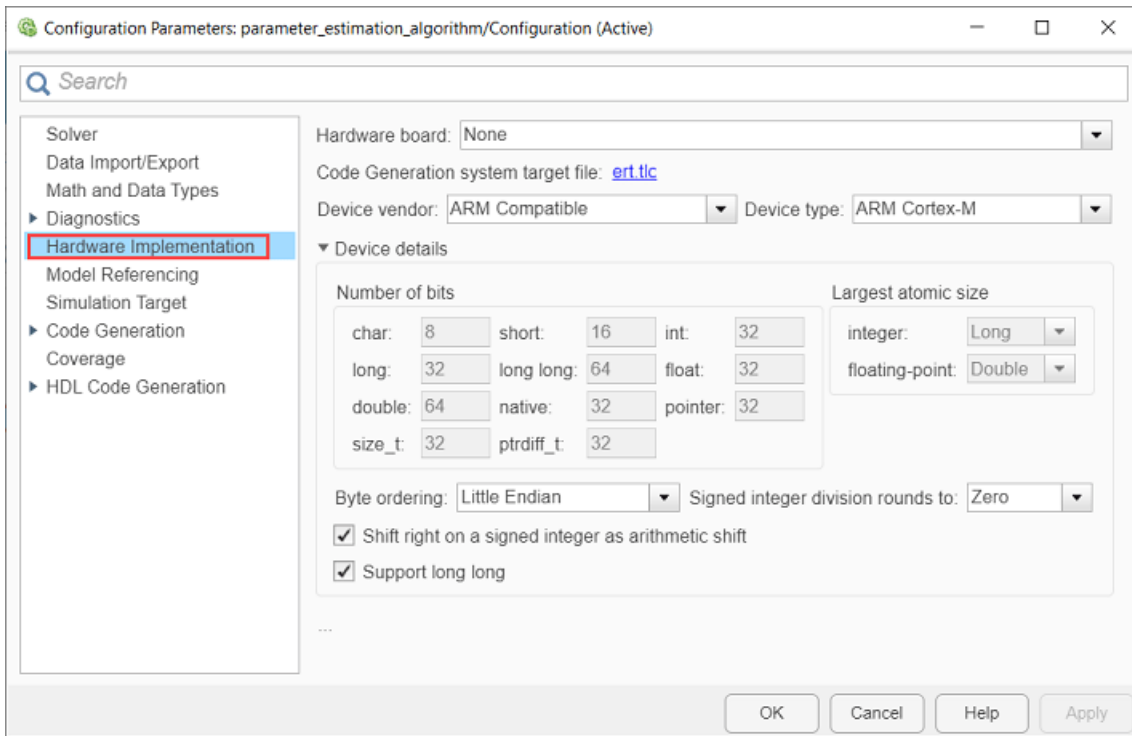
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2. Select **Modeling > Model Settings > Model Settings** to open the Configuration Parameters dialog box.

3. In the **Solver Selection** area of the **Solver** tab, update the **Type** and **Solver** fields.

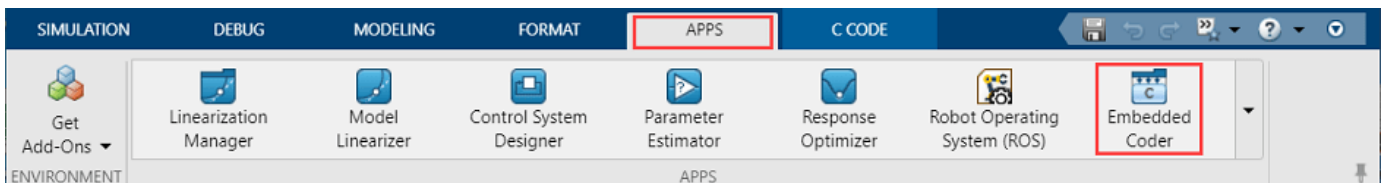


4. In the **Hardware Implementation** tab of the Configuration Parameters dialog box, configure the parameters according to your hardware.



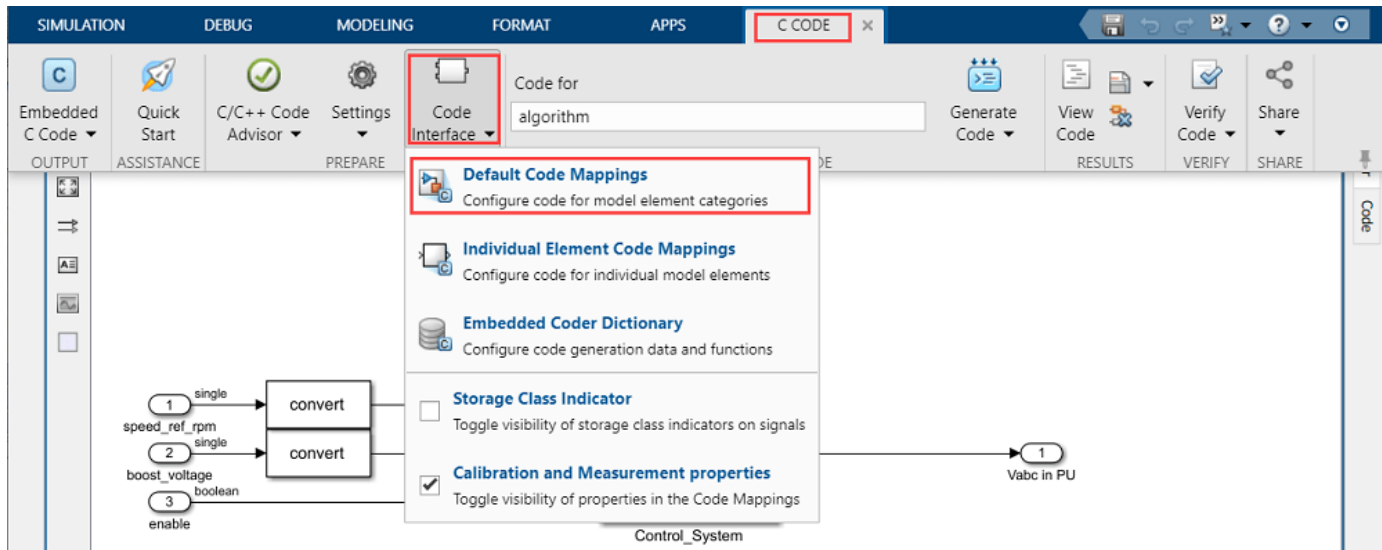
5. Update the hardware setup parameters (including the quadrature encoder and ADC offsets) in the model initialization script (parameter_estimation_init.m).

6. In the Simulink toolstrip of the model, select **Apps > Embedded Coder** to open the Embedded Coder application.



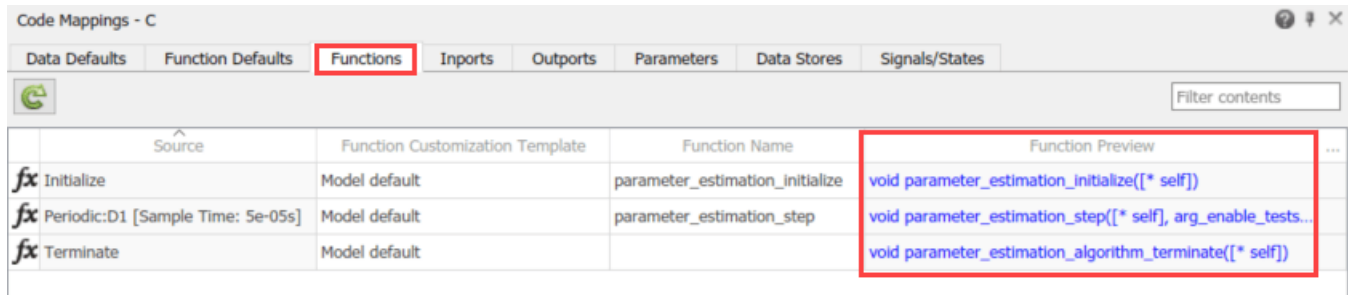
7. In the Simulink toolstrip, select **C Code > Code Interface > Default Code Mappings** to open the Code Mappings - C dialog box.

4 Implement Motor Speed Control by Using Field-Oriented Control (FOC)

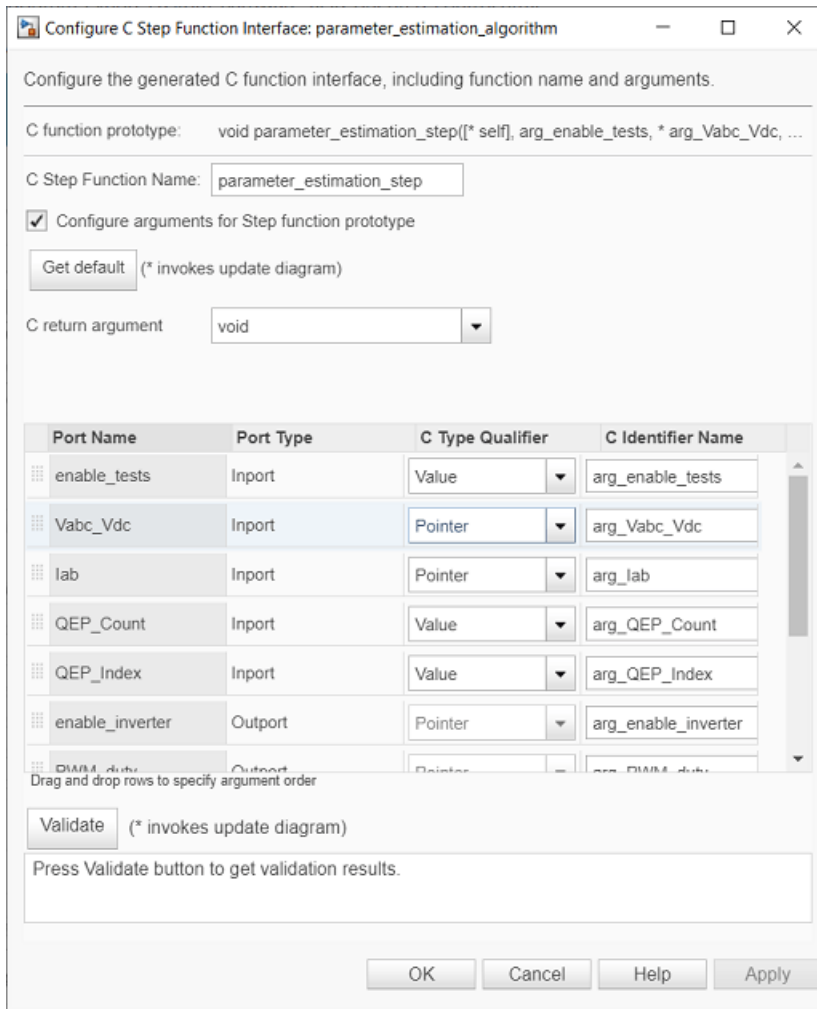


8. In the Code Mappings - C dialog box, open the **Functions** tab.

9. For a listed C function, click the hyperlink under the **Function Preview** column to open the Configure C Initialize Function Interface dialog box.



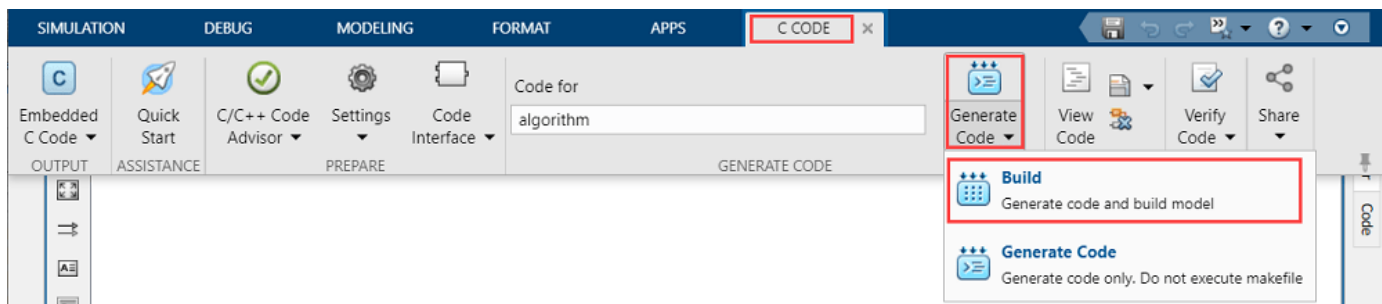
10. Use the Configure C Initialize Function Interface dialog box to configure the interface and arguments of the C function.



11. Click **Apply** and **OK** to complete configuring the C function.

12. Repeat steps 9 to 11 for all the listed functions.

13. In the Simulink toolstrip of the target model, select **C Code > Generate Code > Build** to build the model and generate a .c file for the target model for the current controller.



This image shows an example of a C function available in the generated current controller code.

```
/* Model step function */
void parameter_estimation_step(real32_T arg_enable_tests, uint16_T arg_Vabc_Vdc
[4], uint16_T arg_Iab[2], uint16_T arg_QEP_Count, uint16_T arg_QEP_Index,
real32_T *arg_enable_inverter, real32_T arg_PWM_duty[3], real32_T
*arg_position, real32_T *arg_speed, uint32_T *arg_estParaIdx, real32_T
*arg_estimatedParameter)
{
    real32_T rtb_Add1_e;
    real32_T rtb_Add3;
    real32_T rtb_InvertingNonInverting_idx_0;
    real32_T rtb_InvertingNonInverting_idx_1;
    real32_T rtb_Merge;
    real32_T rtb_Merge_f;
    real32_T rtb_MultiportSwitch_idx_0;
    real32_T rtb_MultiportSwitch_idx_1;
    real32_T rtb_PositionGain;
    real32_T rtb_Product_kr;
    real32_T rtb_Switch_bn;
    real32_T rtb_Switch_m_idx_0;
    uint32_T rtb_PositionToCount;
    uint16_T rtb_Sum3_b;
    boolean_T rtb_UnitDelay_kd;

    /* Gain: '<S9>/Inverting//Non Inverting' incorporates:
```

Note: The generated C function uses the interface that you configured in step 10.

Obtain C Code For Custom Hardware Drivers

You can use the code generation software supported by the hardware manufacturer to configure the hardware peripherals and generate C code for the hardware drivers.

Alternatively, you can also use a manually written driver code.

Integrate Parameter Estimation Algorithm Code With Driver Code

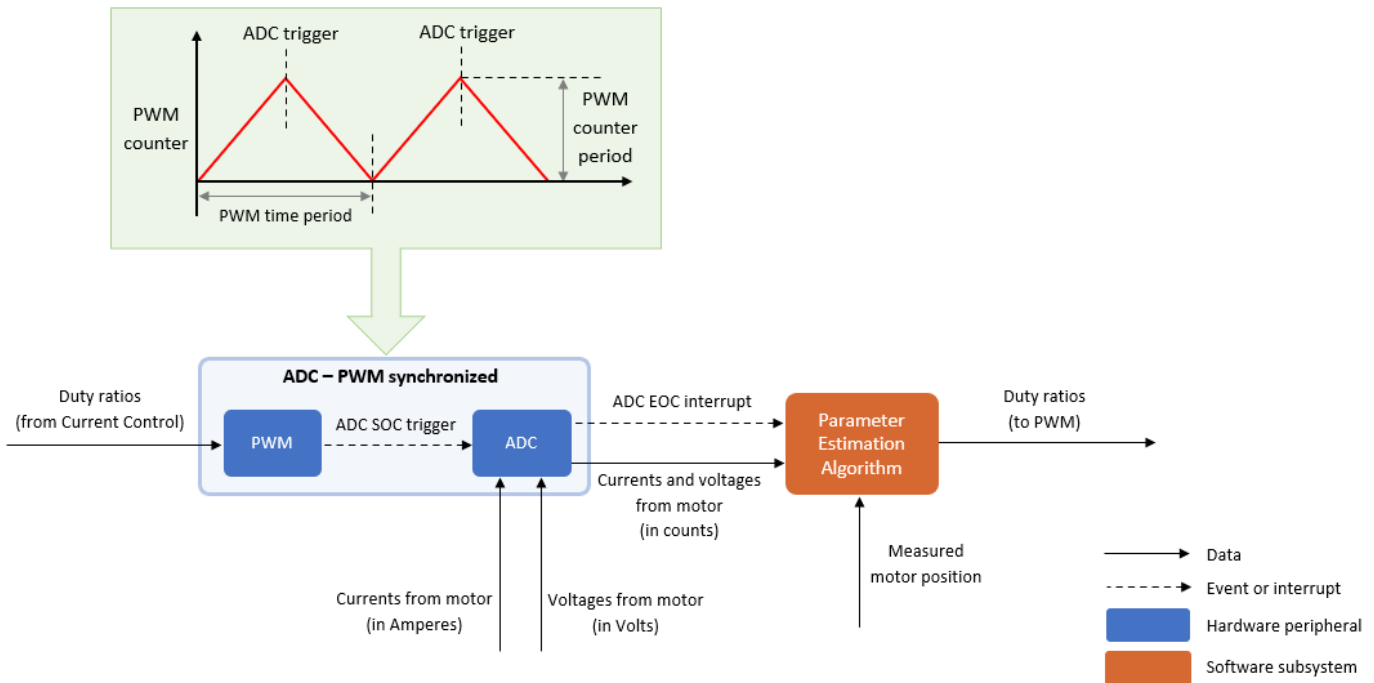
1. Call the parameter estimation algorithm functions from the driver code using the configured function parameters. This image shows a call to a parameter estimation algorithm C function.

```
// ADC conversion complete interrupt configured to trigger at every 50 us
void HAL_ADCEx_InjectedConvCpltCallback(ADC_HandleTypeDef *hadc){

    // call to parameter_estimation_step function here|
```

2. Use the return value from the function call to complete integrating the driver with the parameter estimation algorithm.

This figure describes the program control flow of the example.



For other details about the recommended code structure (that is used by the Motor Control Blockset™ examples), see “Program Control Flow of Motor Control Blockset Examples” on page 6-19.

Deploy Integrated Code to Hardware

1. Complete the hardware connections.
2. Use the code generation and deployment software supported by the hardware manufacturer to compile, build, and generate a binary (for example .HEX) file from the integrated code. Use the software to flash the binary file to the target hardware.
3. The integrated code running on the target hardware saves the computed motor parameters in these global variables:
 - R_s — Phase resistance
 - L_d — d axis inductance
 - L_q — q axis inductance
 - B_{emf} — Back-EMF constant
 - J — Motor inertia
 - B — Friction constant

Estimate Motor Parameters Using Motor Control Blockset Parameter Estimation Tool

Estimate Motor Parameters Using Motor Control Blockset Parameter Estimation Tool

Motor Control Blockset provides a parameter estimation tool that estimates the motor parameters accurately. You can use the estimated motor parameters to simulate the motor model and design the control system. Therefore, the simulation response of the motor model (configured with the estimated parameters) is close to the behavior of the actual motor under test.

The parameter estimation tool can determine the parameters for both permanent magnet synchronous motors (PMSM) and induction motors. You can use these workflows to use the parameter estimation tool according to the type of motor and motor-control hardware that you want to use:

- “Estimate PMSM Parameters Using Recommended Hardware” on page 4-188
- “Estimate PMSM Parameters Using Custom Hardware” on page 4-210
- “Estimate Induction Motor Parameters Using Recommended Hardware” on page 4-202

See Also

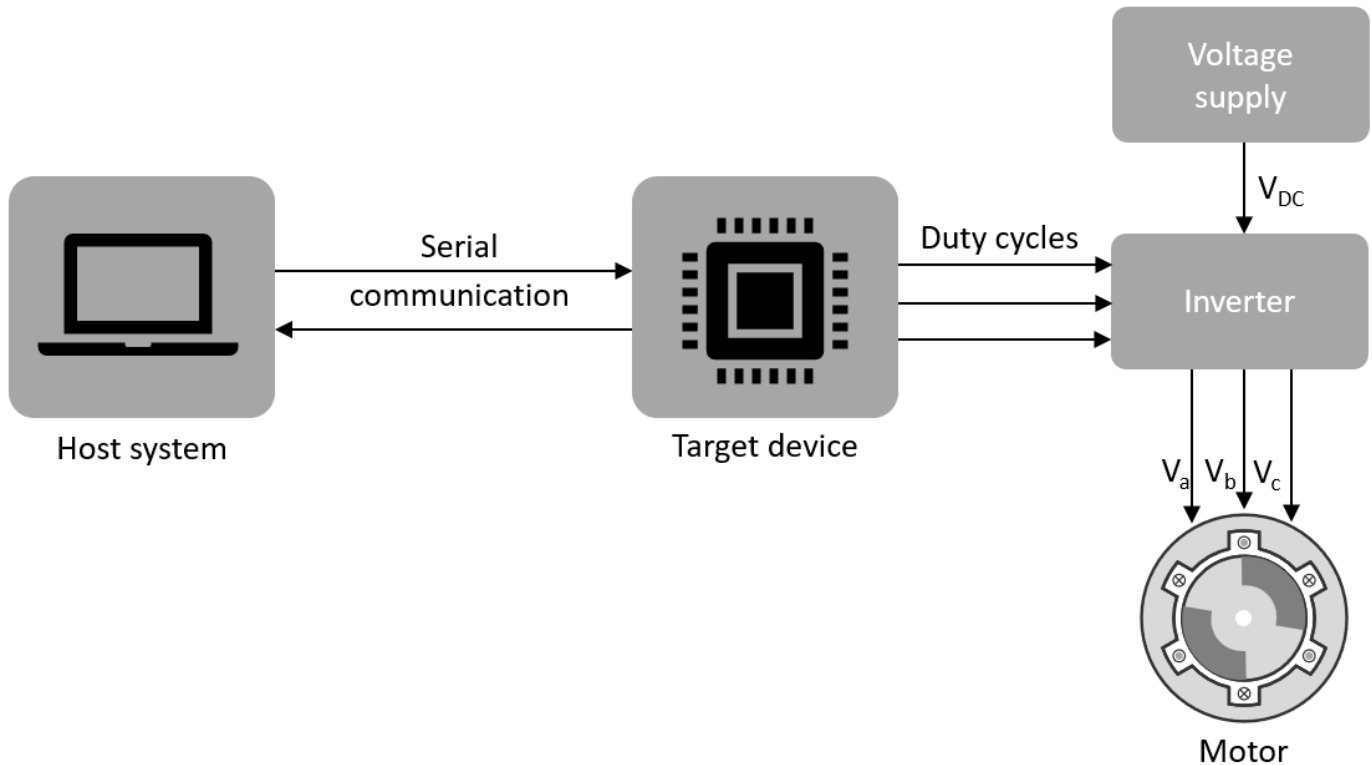
Interior PMSM | Surface Mount PMSM | Induction Motor

Concepts

- “Host-Target Communication” on page 6-2
- “Open-Loop and Closed-Loop Control” on page 6-9
- “Current Sensor ADC Offset and Position Sensor Calibration” on page 6-13
- “Per-Unit System” on page 6-16
- “Program Control Flow of Motor Control Blockset Examples” on page 6-19

Host-Target Communication

Motor Control Blockset uses a communication interface between the host model and the target model to control the motor and observe feedback.



Host Model

The host model is a user interface for the controller hardware board. Run the host model on the host computer. Before you run the host model on the host computer, make sure to deploy the target model on the controller hardware board.

The host model commands, controls, and exchanges data with the target hardware. You can perform these operations using the host model available in the Motor Control Blockset:

- Find the serial communication port (COM port) in the host system. For more details, see Find Communication Port section in this page.
- Configure the serial port and baud rate by using the Serial Setup block.
- Start or stop the motor.
- Specify the motor speed.
- View the debug or output signals that the host receives from the target by using the Time Scope and Display blocks.

Target Model

The target model runs on the controller hardware board. Deploy the target model to the embedded target hardware that controls the motor. The target model communicates with the host model to

receive commands from the user (for example, the command to start or stop the motor). Some common operations that a target model available in Motor Control Blockset performs:

- Serial communication with the host model to receive user commands and exchange binary data.
- Read data from the position and current sensors attached to the motor and inverter.
- Control motor speed and torque by running the control algorithms and processing the feedback.
- Generate duty cycle inputs for the inverter.
- Enable fast serial data monitoring for debugging the signals.

Serial Communication Blocks

The host and target models interact by using these Motor Control Blockset blocks that enable serial communication:

- Host Serial Receive
- Host Serial Setup
- Host Serial Transmit

Using these blocks you can monitor, control, and customize the motor operation in real time. For example, you can view the debug signals, stop or start the motor, and change the motor speed without repeated deployment of the target model.

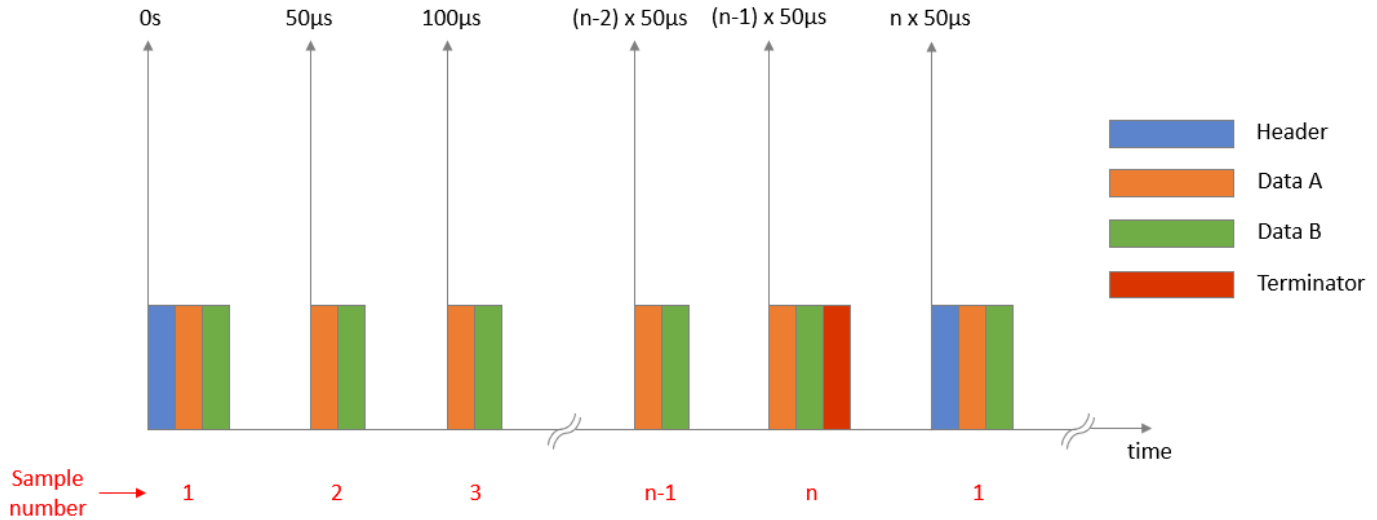
Fast Serial Data Monitoring

The Motor Control Blockset example models use the fast serial data monitoring algorithm, which performs control and diagnostic operations through the host model. This algorithm enables you to observe data from the target device at the same rate as the execution sample time (for example, PWM frequency of 20kHz). This, in turn, helps in diagnostics and analysis of transients.

Evaluation boards often provide serial communication over USB connections that enable fast serial transfers. The models running on the Texas Instruments™ LaunchPad hardware boards send signals like I_a and I_b currents over the serial interface.

For example, consider a situation where a model needs to sample two signals A and B every 50 μs and send them to the host model for monitoring and debugging. To fulfil this requirement, the Motor Control Blockset examples divide the entire signal data into packets of 600 data points. Therefore, a packet from signal A combined with a signal B packet results in 1200 data points. Using this approach, the target hardware sequentially sends a pair of data packets (from signals A and B) to the host model. The target further groups these packet pairs into sections. Each section begins with a header and ends with a terminator. Following a header, the host model starts buffering the data points until it receives a terminator, after which Simulink reads the buffered data that you can monitor.

To read the buffered data we select **Enable blocking mode** and set **Data size** to $[2 \ n]$ and **Sample time** to $n \cdot 50 \mu\text{s}$ in the Host Serial Receive block parameter dialog box. Using this configuration, the Host Serial Receive block reads $2 \times n$ data points every $n \cdot 50 \mu\text{s}$. We select a value for n such that the Simulink host model can run efficiently in real time.



Motor Control Blockset examples follow this approach because Simulink shows high efficiency when processing big packets of data at low data speeds and the target hardware (used by Motor Control Blockset) efficiently processes smaller data packets at higher data speeds.

Use the host model to receive these signals on your host computer. The Motor Control Blockset examples implementing Field Oriented Control (FOC) algorithm for the F28379D LaunchPad use `mcb_pmsm_foc_host_model_f28379d.slx`. Examples that implement the FOC algorithm for the F28069M targets, use `mcb_pmsm_foc_host_model_f28069m.slx`. The Motor Control Blockset also provides other host models for the application-based examples.

Selecting COM port and baud rate

Select the appropriate COM port that matches your board in the Serial Setup block of the host model. Adjust the baud rate for your board:

Texas Instruments LaunchPad	Baud Rate
F28027 LaunchPad	3.75e6
F28069 LaunchPad	5.625e6
F28377S LaunchPad	12e6
F28379D LaunchPad	12e6

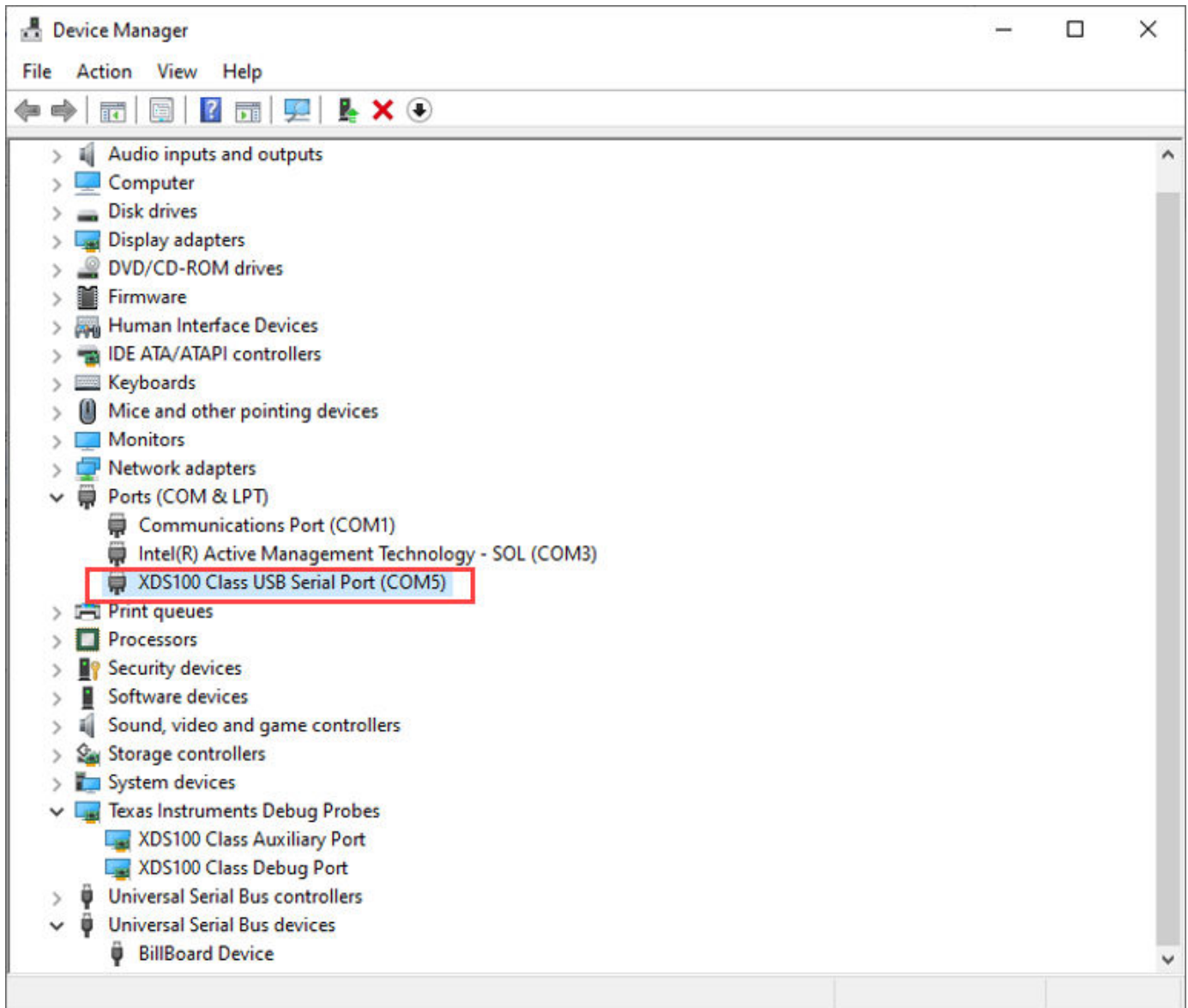
After you deploy the target model on the target device, run the host model and observe the debug signals update at 20 kHz, on the time scope. You can use the same technique to monitor other signals on other processors.

Note SCI A is usually connected to the FTDI chip that allows serial transfers over USB on the LaunchPad boards, docking stations, and ISO control cards.

Find Communication Port

Use these steps to find the serial communication port in the Device Manager of Windows PC, after you connect the target hardware to your system:

- 1 Open **Device Manager** on your Windows PC.
- 2 Look for an entry under **Ports (COM & LPT)** titled **USB Serial Port (COMX)**, where X is a number. You can note down this number to configure the serial setup block in the host model.

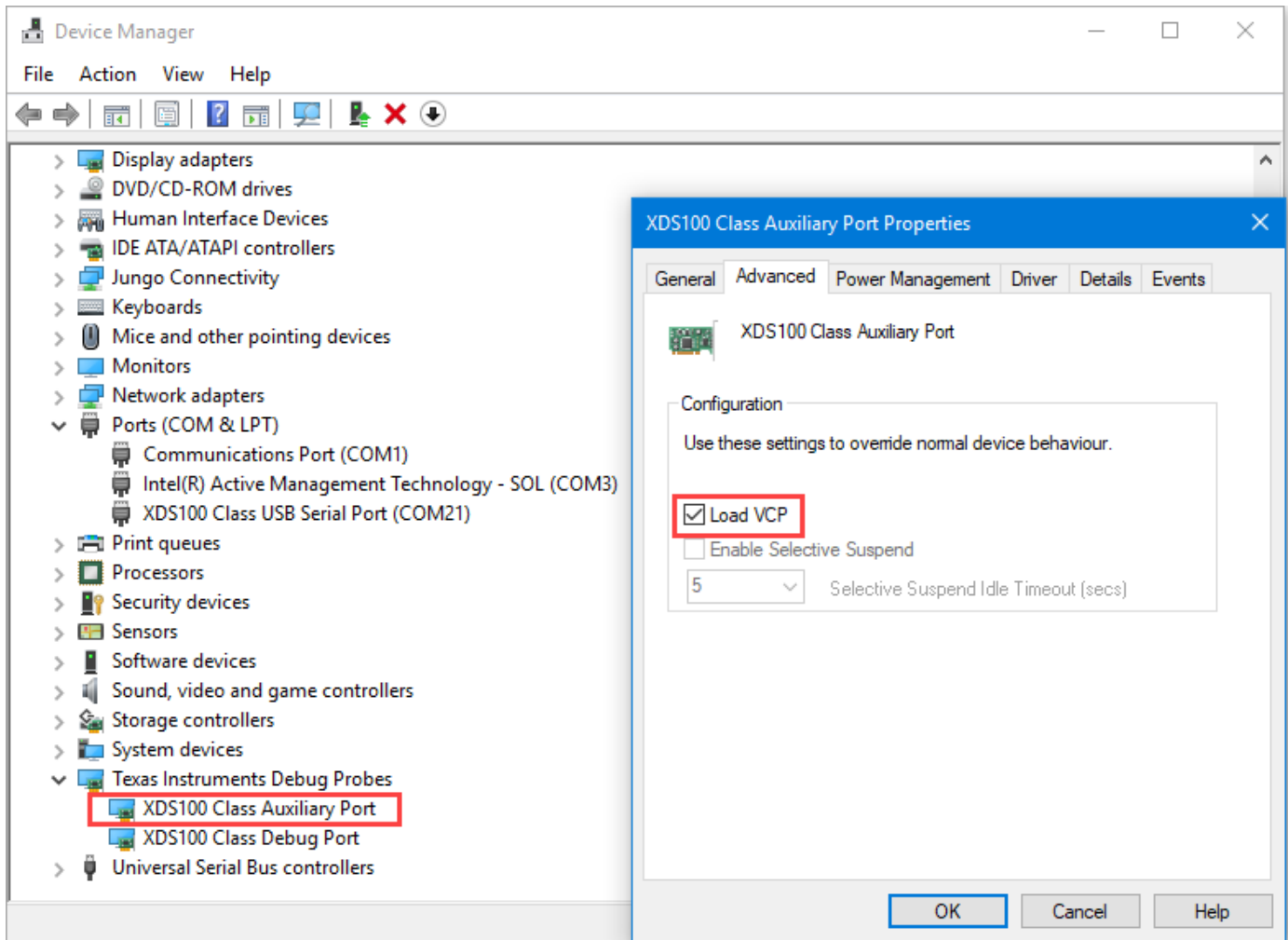


If you face difficulty in finding the COM port, follow these steps to determine the COM port:

- 1 Open **Device Manager** on your Windows PC.
- 2 Look for an entry under **Ports (COM & LPT)** titled **USB Serial Port (COMX)**, where X is a number. If there are multiple COM ports, you can disconnect and reconnect the C2000 board and observe the updates in Device Manager to determine the COM port.
- 3 Alternatively, follow these steps to determine the correct port name for the connected target hardware:
 - a Right-click a communication port and click **Properties**.

- b** In the **Details** tab, select **Hardware Ids** property.
- c** If the port indicates the following IDs, the communication port belongs to the connected TI's C2000™ controller hardware board:
 - VID: 0403
 - PID: A6D0
- 4** If you do not see or find the right port in **Ports (COM & LPT)**, navigate to **Texas Instruments Debug Probes** and follow these steps:
 - a** Right-click **XDS100 Class Auxiliary Port Properties** and select **Properties**. Navigate to **Advanced** tab and select **Load VCP**.
 - b** Right-click **XDS100 Class Debug Port Properties** and select **Properties**. Navigate to **Advanced** tab and clear **Load VCP**.
 - c** Disconnect and reconnect the USB cable to the system and observe the updates in Device Manager to determine the COM port. The system now displays the COM port that belongs to the connected TI's C2000 controller hardware board.

Tip VCP stands for Virtual COM Port (for devices that support serial over USB communication).



- 5 If **Texas Instruments Debug Probes** do not appear in the Device Manager, expand **Universal Serial Bus controllers** in the Device Manager and follow these steps:
 - a Right-click **TI XDS 100 Channel B** and select **Properties**. Navigate to **Advanced** tab and select **Load VCP**.
 - b Right-click **TI XDS 100 Channel A** and select **Properties**. Navigate to **Advanced** tab and clear **Load VCP**.
 - c Disconnect and reconnect the USB cable to the system and observe the updates in Device Manager to determine the COM port. The system now displays the COM port that belongs to the connected TI's C2000 controller hardware board.
- 6 If Device Manager does not detect the target hardware, follow these steps:
 - a Check that the target hardware is connected to the system.
 - b Check if the device drivers are installed correctly. Generally, device drivers are installed with the Code Composer Studio™ (CCS). Check if the CCS software is installed on your system. Alternatively, try re-installing the device drivers suggested by Texas Instruments.
 - c Check if the serial connection cable is intact.
 - d If the problem persists, try connecting the hardware to another system and check if Device Manager detects the hardware.

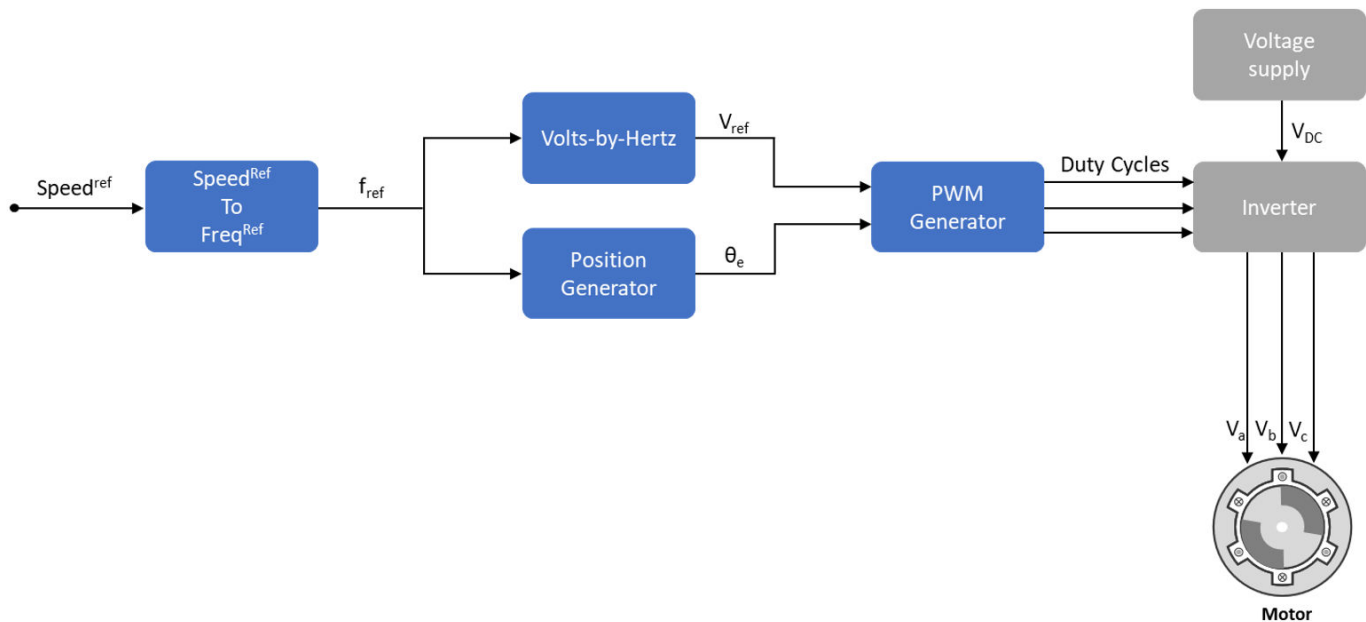
- e If you still face the problem, the target hardware may be faulty.

Open-Loop and Closed-Loop Control

This section describes the open-loop and closed loop motor control techniques.

Open-Loop Motor Control

Open-loop control (also known as scalar control or Volts/Hz control) is a popular motor control technique that you can use to run any AC motor. This is a simple technique that does not need any feedback from the motor. To keep the stator magnetic flux constant, we keep the supply voltage amplitude proportional to its frequency.



This figure shows an open-loop control system. The power circuit consists of a PWM voltage fed inverter supplied by a DC source. The system does not use any feedback signal for control implementation. It uses the reference speed to determine the frequency of the stator voltages. The system computes the voltage magnitude as proportional to the ratio of rated voltage and rated frequency (commonly known as Volts/Hz ratio), so that the flux remains constant.

$$\lambda_m \propto V_s / f_s$$

where:

- 1 λ_m is the rated flux of the motor in Wb.
- 2 V_s is the stator voltage of the AC motor in Volts.
- 3 f_s is the frequency of the stator voltage of the AC motor in Hz.

In an open-loop system, the speed for an AC motor is expressed as:

$$Speed_{(rpm)} = \frac{60 \times f_s}{p}$$

where:

- $Speed_{(rpm)}$ is the mechanical speed of the AC motor in rpm.
- f_s is the frequency of the stator voltage and currents of the AC motor in Hz.
- p is the number of pole pairs of the motor.

You can use the preceding expression to determine the frequency of reference voltages for a required speed (for a given machine).

$$f^{ref} = \frac{p \times RPM^{ref}}{60}$$

Use this frequency to generate PWM reference voltages for the inverter. Compute the magnitude of voltages by maintaining Volts/Hz ratio as:

$$V^{ref} = \left(\frac{V_{rated}}{f_{rated}} \right) f^{ref}$$

When using the per-unit system representation, the open-loop control system considers V_{rated} as the base quantity, which usually corresponds to 1PU or 100% duty cycle. Depending on the modulation technique (either Sinusoidal PWM or Space Vector PWM), you may need an additional gain $\left(\frac{2}{\sqrt{3}} \right)$ for sinusoidal PWM). At lower speeds, the system needs a minimum boost voltage (15% or 25% of the rated voltage) to overcome the effect of the stator resistance voltage drop.

You can use open-loop control in applications where dynamic response is not a concern, and a cost-effective solution is required. Open-loop motor control does not have the ability to consider external conditions that can affect the motor speed. Therefore the control system cannot automatically correct the deviation between the desired and the actual motor speeds.

Note Scalar control implementation does not consider compensating voltage drop due to stator resistance and field weakening.

Closed-Loop Motor Control

Closed-loop control takes the system feedback into consideration for control. Closed-loop control of the motor considers the feedback of motor signals like current and position. The control system uses the feedback signals to regulate the voltage (applied to the motor) to keep the motor response at a reference value.

In sensorless position control, the motor starts running at 10% of the base speed in the open-loop. After the reference switch goes beyond 10% of the base speed, the control system transitions from open-loop to closed-loop.

To ensure smooth transition from open-loop to closed-loop, the PI controllers reset and start from the same initial condition as the open-loop outputs.

Current Sensor ADC Offset and Position Sensor Calibration

This section explains about analog to digital controller (ADC) and position sensor offset calibration.

Current Sensor ADC Offset Calibration

In an inverter, signal conditioning for the current sensor introduces an offset voltage in the ADC input to measure both positive and negative current. This offset value is different for each target hardware because it depends on the tolerances of the components in the signal sensing and conditioning circuit. It is recommended that you measure the current sensor ADC offset for the target hardware. Current sensor ADC offset is represented in ADC counts that correspond to zero ampere current.

See the example “Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6 to manually measure the ADC offset value. In the Motor Control Blockset examples, update the measured value in the `inverter.CtSensAOffset` and `inverter.CtSensBOffset` variables in the model initialization script. By default, the script updates the `inverter.CtSensAOffset` and `inverter.CtSensBOffset` variables with the default values.

The examples in Motor Control Blockset calculate the current sensor ADC offset in the hardware initialization subsystem. In the model initialization script, when you set `inverter.ADCOffsetCalibEnable = 1`, the script enables the current sensor offset calibration in the target hardware during initialization. In the hardware initialization subsystem, ADC channels read the input current multiple times and averages them. The current controller uses this averaged ADC offset value. In the model initialization script, when you set `inverter.ADCOffsetCalibEnable = 0`, the script disables the current sensor offset calibration and uses the values from the initialization script.

Note Always measure the current sensor ADC offset when the motor is not running. It is recommended that you unplug the electric wires connected to the motor.

Position Sensor Offset Calibration for Quadrature Encoder and Hall Sensor

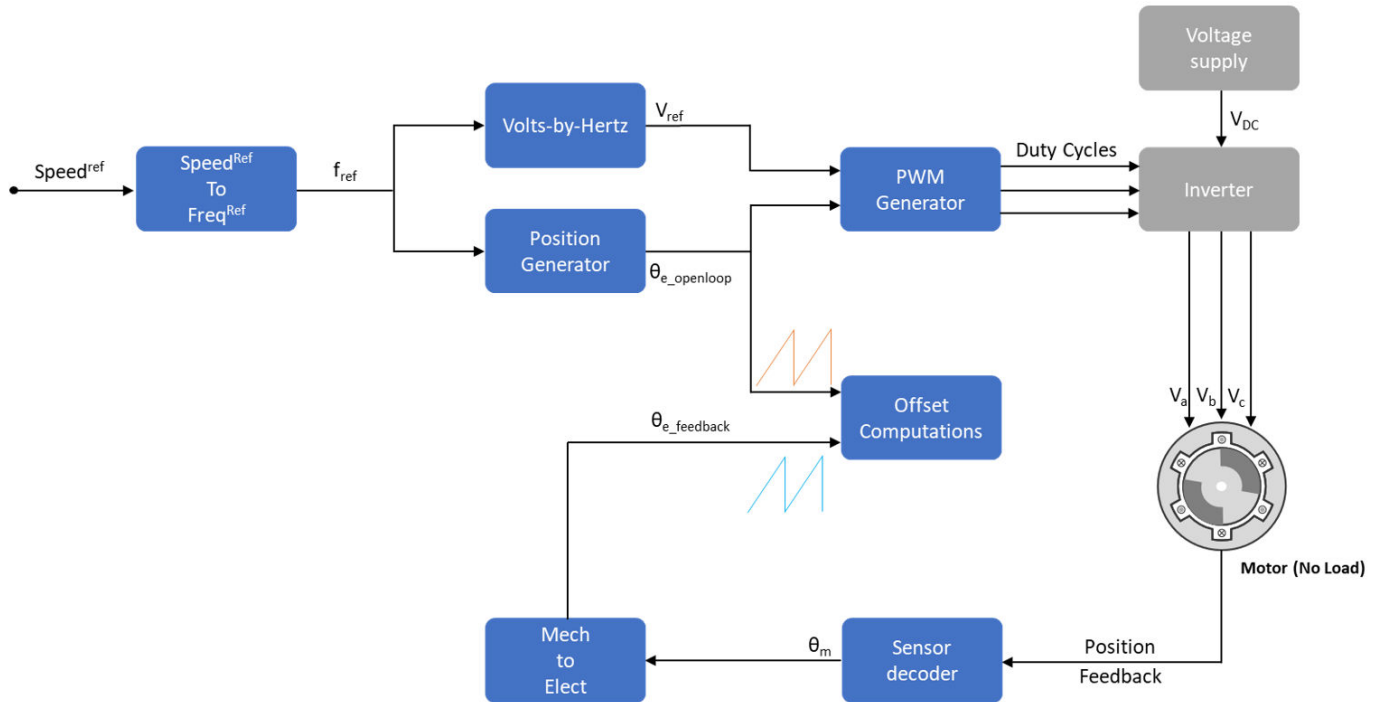
The controller requires the position sensor offset computation to determine accurate real-time feedback of the rotor position and implement the Field-Oriented Control (FOC) algorithm correctly. It is recommended that you use the examples for offset calibration to compute the position offset before running any other example that uses FOC.

Hall sensor offset is the angle between the d -axis of the rotor and the position detected by the Hall sensor. You can use the offset to correct and compute an accurate position of the d -axis of the rotor.

Quadrature encoder sensor offset is the angle between the d -axis of the rotor and the encoder index pulse position detected by the quadrature encoder.

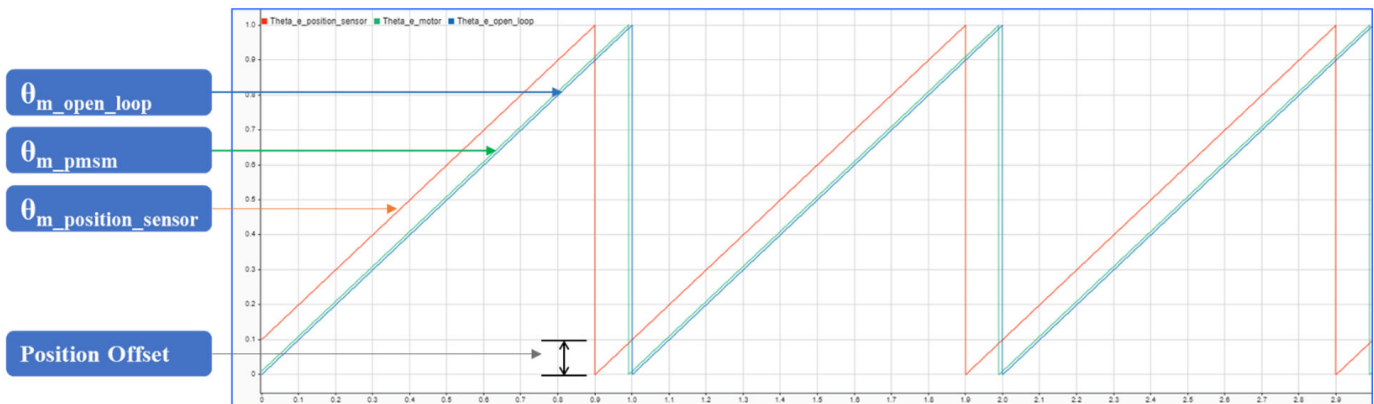
Motor Control Blockset offers examples like “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76 and “Hall Offset Calibration for PMSM Motor” on page 4-67 to obtain the accurate rotor position for implementing the control algorithm. The offset computation examples use a unique algorithm along with open-loop control to compute the position offsets of the position sensors (Hall or quadrature encoder). Open-loop control (also known as scalar control or volt/Hz control) is a popular motor control technique that can be used to run any AC motor. This is a simple

technique that does not need any feedback from the motor. To ensure a constant stator magnetic flux, keep the supply voltage amplitude proportional to its frequency. This figure shows an overview of the open-loop control. See “Open-Loop and Closed-Loop Control” on page 6-9 for more details.



By using this algorithm, the offset calibration examples detect the position offset in this manner:

- Check if the motor is in a no-load condition.
- Start and run the motor in open-loop at a very low speed (for example, 60rpm). At a low speed, the rotor d -axis closely aligns with the rotating magnetic field of the stator.
- Measure the feedback position of the available position sensor (Hall or quadrature encoder).
- Compare the open-loop position with feedback position and check that the phase-sequence is correct. If required, correct the motor phase-sequence.
- Compute the Hall sensor position offset by obtaining the difference between the open-loop position and feedback position.
- Run the motor in the open-loop for few cycles and stop the motor. Ensure that the encoder index pulse is detected at least once. Lock the rotor in the d -axis. The quadrature encoder position offset is identical to the position feedback. This outputs the quadrature encoder mechanical offset position.



This figure shows the comparison of open-loop position from the control algorithm along with the actual position of the motor. The figure also shows the feedback from the position sensor. The position offset, which is the difference between the open-loop position and feedback position from the sensor, is computed by the algorithm provided in the offset calibration models.

- Update the measured offset in the `pmsm.PositionOffset` variable in the model initialization script of the examples.
- For parameter estimation, update the measured Hall offset in the Hall Offset field of the `mcb_param_est_host_read` model.

Note The “Hall Offset Calibration for PMSM Motor” on page 4-67 example outputs the electrical position offset. Whereas, the “Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76 example outputs the mechanical position offset.

For steps to compute the offsets, see these examples:

“Quadrature Encoder Offset Calibration for PMSM Motor” on page 4-76

“Hall Offset Calibration for PMSM Motor” on page 4-67

“Run 3-Phase AC Motors in Open-Loop Control and Calibrate ADC Offset” on page 4-6

Per-Unit System

Motor Control Blockset uses these International System of Units (SI):

Quantity	Unit	Symbol
Voltage	volt	V
Current	ampere	A
Speed	radians per second	rad/s
	revolutions per minute	rpm
Torque	newton-meter	N.m
Power	watt	W

Note The SI Unit for speed is rad/s. However, most manufacturers use rpm as the unit to specify the rotational speed of the motors. Motor Control Blockset prefers rpm as the unit of rotational speed over rad/s. However, you can use either value based on your preference.

Per-Unit System

The per-unit (PU) system is commonly used in electrical engineering to express the values of quantities like voltage, current, power, and so on. It is used for transformers and AC machines for power system analysis. Embedded systems engineers also use this system for optimized code-generation and scalability, especially when working with fixed-point targets.

For a given quantity (such as voltage, current, power, speed, and torque), the PU system expresses a value in terms of a base quantity:

$$\text{quantity expressed in PU} = \frac{\text{quantity expressed in SI units}}{\text{base value}}$$

Generally, most systems select the nominal values of the system as the base values. Sometimes, a system may also select the maximum measurable value as the base value. After you establish the base values, all signals are represented in PU with respect to the selected base value.

For example, in a motor control system, if the selected base value of the current is 10A, then the PU representation of a 2A current is expressed as $(2/10)$ PU = 0.2 PU.

Similarly,

$$\text{quantity expressed in SI units} = \text{quantity expressed in PU} \times \text{base value}$$

For example, the SI unit representation of 0.2 PU = $(0.2 \times \text{base value}) = (0.2 \times 10)$ A.

Per-Unit System and Motor Control Blockset

Motor Control Blockset uses these conventions to define the base values for voltage, current, speed, torque, and power.

Quantity	Representation	Convention
Base voltage	V_{base}	<p>This is the maximum phase voltage supplied by the inverter.</p> <p>Generally, for Space Vector PWM, it is</p> $\text{PU_System.V_base} = \frac{\text{inverter.V_dc}}{\sqrt{3}}$ <p>For Sinusoidal PWM, it is</p> $\text{PU_System.V_base} = \frac{\text{inverter.V_dc}}{2}$
Base current	I_{base}	<p>This is the maximum current that can be measured by the current sensing circuit of the inverter.</p> <p>Generally, but not necessarily, it is I_{max} of the inverter.</p> $\text{PU_System.I_base} = \text{inverter.I_max}$
Base speed	N_{base}	<p>This is the nominal (or rated) speed of the motor. This is also the maximum speed that the motor can achieve at the nominal voltage and nominal load without a field-weakening operation.</p>
Base torque	T_{base}	<p>This torque is mathematically derived from the base current. Physically, the motor may or may not be able to produce this torque.</p> <p>Generally, it is</p> $\text{PU_System.T_base} = \frac{3}{2} \times \text{pmsm.p} \times \text{pmsm.FluxPM} \times \text{PU_System.I_base}$

Quantity	Representation	Convention
Base power	P_{base}	<p>This is the power derived by the base voltage and base current.</p> <p>Generally, it is</p> $PU_System.P_base = \frac{3}{2} \times PU_System.V_base \times PU_System.I_base$

where:

- V_{dc} is the DC voltage that you provide to the inverter.
- I_{max} is the maximum current measured by the ADCs connected to the current sensors of the inverter.
- p is the number of pole pairs available in the PMSM.
- $FluxPM$ is the permanent magnet flux linkage of the PMSM.
- $pmsm$ is the MATLAB workspace parameter structure that saves the motor variables.
- $inverter$ is the MATLAB workspace parameter structure that saves the inverter variables.
- PU_System is the MATLAB workspace parameter structure that saves the PU system variables.

For the voltage and current values, you can generally consider the peak value of the nominal sinusoidal voltage (or current) as 1PU. Therefore, the base values used for voltage and current are the RMS values multiplied by $\sqrt{2}$, or the peak value measured between phase-neutral.

You can simplify your calculations by using the PU system. Motor Control Blockset uses these base value definitions for the PU-system-related conversions performed by the algorithms used in the toolbox examples. The toolbox stores the PU-system-related variables in a structure called `PU_System` in the MATLAB workspace.

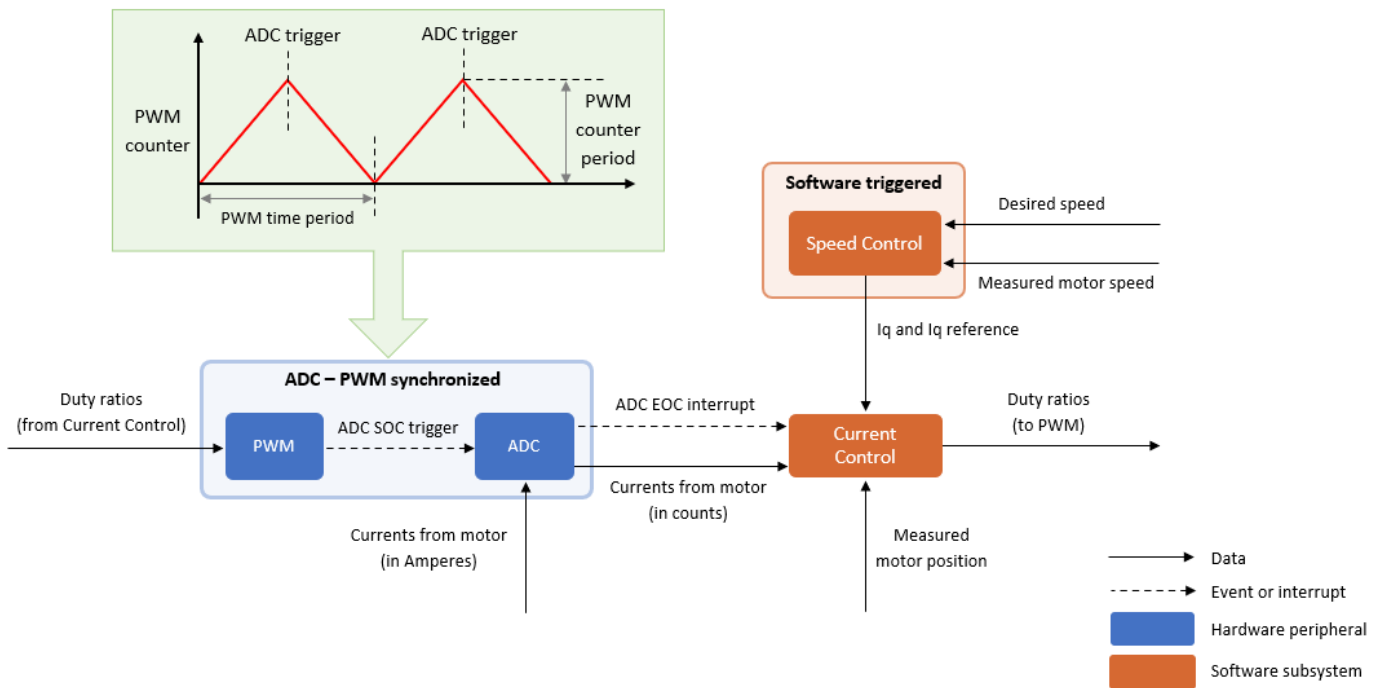
Why Use Per-Unit System Instead of Standard SI Units

Per-unit representation of signals has many advantages over the SI units. This technique:

- Improves the computational efficiency of code execution, and therefore is a preferred system for fixed-point targets.
- Creates a scalable control algorithm that can be used across many systems.

Program Control Flow of Motor Control Blockset Examples

This section describes the control flow of the field-oriented control (FOC) algorithm that the Motor Control Blockset examples use. The control flow operates using the hardware events along with the triggered software and hardware interrupts. This figure describes the interactions between the hardware modules and software subsystems.

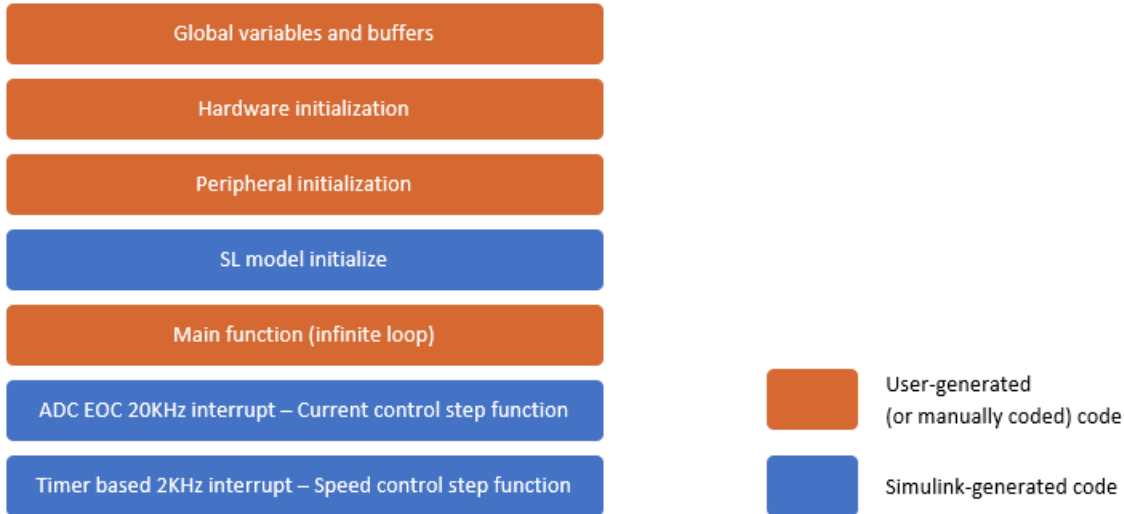


The FOC based examples generally use the data speed of 20KHz for the **Current Control** triggered software subsystem. Similarly, the examples use the data speed of 2KHz for the **Speed Control** triggered software subsystem. The ADC end of conversion (EOC) interrupt (a hardware interrupt) triggers the current control subsystem. The PWM-ADC synchronization controls the rate of this trigger. Similarly, a software interrupt triggers the speed control subsystem.

The entire system uses external inputs for motor position, motor speed, motor currents, and the desired motor speed. The preceding figure shows the interactions between these data points and the enclosed subsystems.

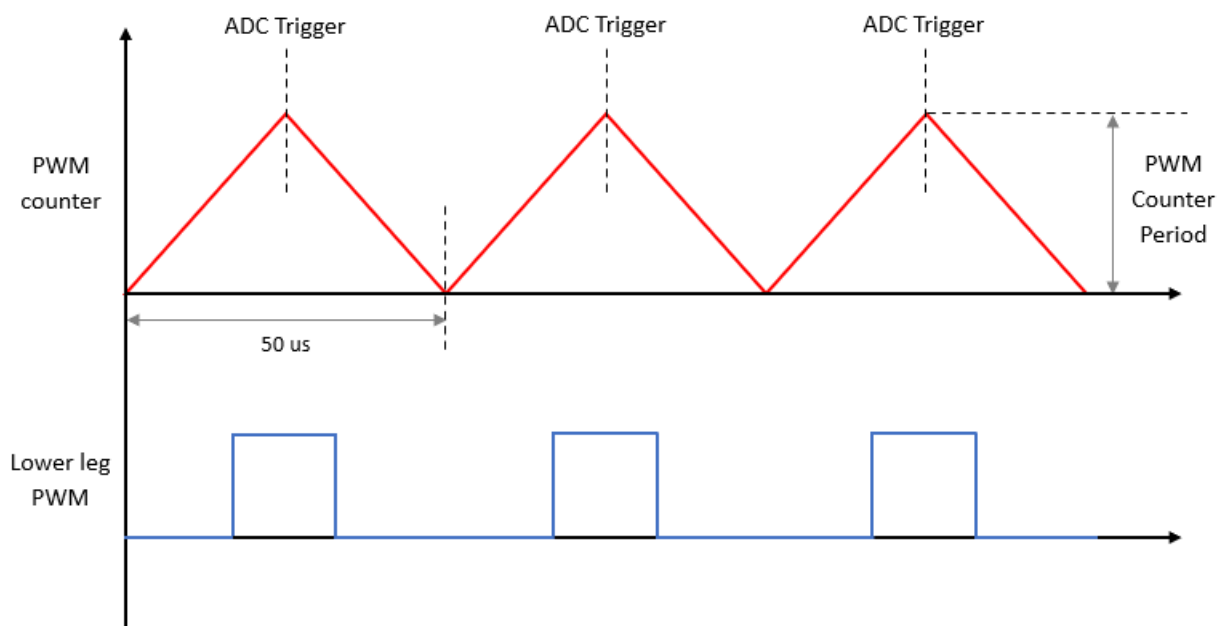
Motor Control Blockset provides the “Algorithm-Export Workflows for Custom Hardware” on page 4-186 example that include Simulink models for current control and speed control systems. The example provides instructions to generate code for these models. To create a FOC algorithm that can run on any motor control hardware, integrate this generated code with the hardware peripheral code (either auto-generated or manually written). Ensure that you activate the **Current Control** and **Speed Control** systems at appropriate times for the prescribed time intervals as shown in the preceding figure.

The following figure shows the entire structure of the integrated code.



ADC-PWM Synchronization

The interaction between the PWM and ADC modules controls the rate of triggering of the **Current Control** subsystem. To reduce harmonics in the system, the PWM counter runs in center-aligned or up-down mode. We configure the PWM such that when PWM counter reaches the PWM counter period value, it triggers the ADC start of conversion (SOC) event. This ensures that the currents available at the ADC inputs are updated currents, and therefore, helps to measure the ADC currents correctly. Usually when you use shunt current sensors to measure the motor currents, the current-sense resistor is located on the lower legs of the inverter. Therefore, if we ensure to switch on the lower leg of the ADC a little before the instant when ADC SOC is triggered (by configuring the PWM module), we can ensure that the ADC reads the currents correctly and that the measured current values are average values (the current measurements when the current has settled down). This figure shows this interaction.



Motor Speed and Position Measurement

The FOC algorithm needs current position and speed of the motor. Usually either the position sensors or the sensorless estimation techniques help determine these values. The choice of the position sensing method depends on the factors such as cost, available space, required accuracy, and the motor control application itself. Motor Control Blockset supports these position sensing methods.

- Position sensors:
 - Quadrature encoder sensor
 - Hall sensor
 - Resolver
- Sensorless position estimation techniques:
 - Sliding mode observer
 - Flux observer

Serial Communication

Motor Control Blockset FOC examples use serial communication protocols for providing commands to the motor and reading debugging-related information from the motor control hardware. For details about this protocol, see “Fast Serial Data Monitoring” on page 6-3.

Hardware Connections

Hardware Connections

Motor Control Blockset supports the following hardware configurations:

- 1 F28069 control card configuration
- 2 LAUNCHXL-F28069M configuration
- 3 LAUNCHXL-F28379D configuration
- 4 C2000 MCU Resolver Eval Kit [R2]

F28069 control card configuration

The configuration includes the following hardware components:

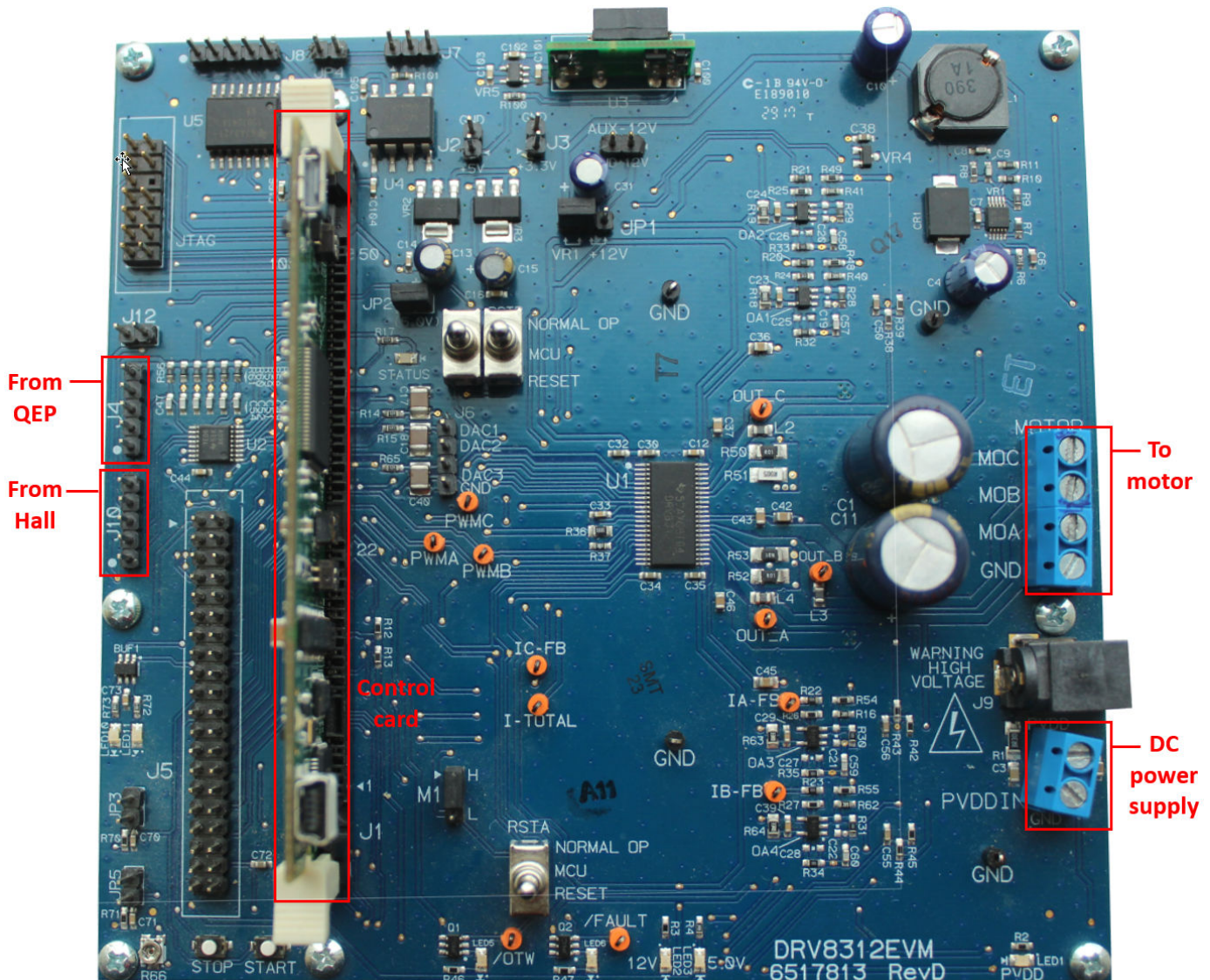
- Texas Instruments DRV8312-69M-KIT inverter board
- Texas Instruments F28069 microcontroller control card
- Motor BLY171D (supports both Hall and quadrature encoder sensors)
- Motor BLY172S (supports Hall sensor)
- Quadrature encoder
- DC power supply

Note Due to auxiliary power supply related hardware issues, the DRV8312-69M-KIT does not support the position sensors connected to some motors (for example, Teknic M-2310P motor).

The following steps describe the hardware connections for the F28069 control card configuration:

- 1 Connect the F28069 control card to J1 of DRV8312-69M-KIT inverter board.
- 2 Connect the motor three phases, to MOA, MOB, and MOC on the inverter board.
- 3 Connect the DC power supply (24V) to PVDDIN on the inverter board.

Warning Be careful when connecting PVDD and GND to the positive and negative connections of the DC power supply. A reverse connection can damage the hardware components.

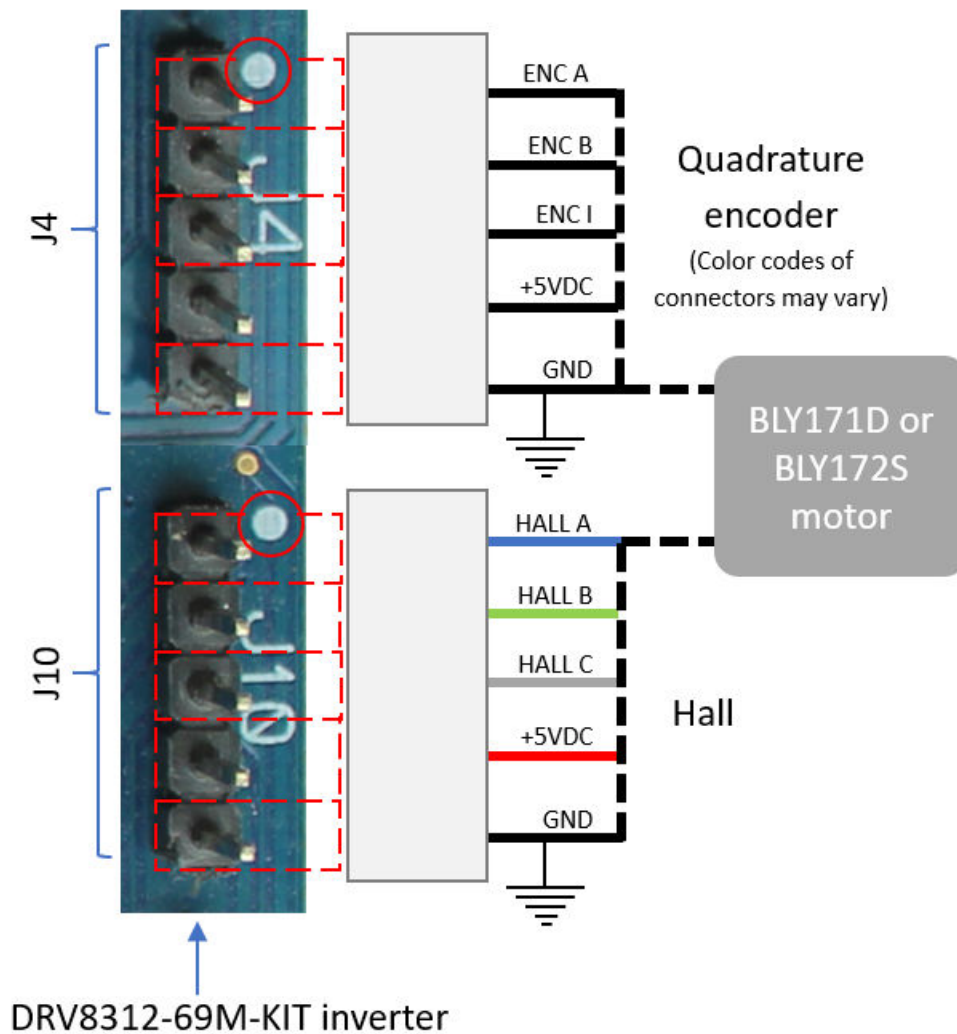


The following step describes about interfacing the quadrature encoder sensor:

- Connect the quadrature encoder pins (G, I, A, 5V, B) to J4 on the inverter board.

To implement position-sensing by using Hall sensor, use a motor that has inbuilt Hall sensors (for example, BLY171D and BLY172S). The following steps describe the steps to interface the Hall sensor:

- Connect the Hall sensor encoder output to J10 on the inverter board.



We recommend the following jumper settings for DRV8312-69M-KIT inverter board when working with Motor Control Blockset. You can customize these settings depending on the application requirements. For more information about these settings, see the device user guide available on Texas Instruments website.

- JP1 - VR1
- JP2 - ON
- JP3 - OFF
- JP4 - OFF
- JP5 - OFF
- M1 - H
- J2 - OFF
- J3 - OFF
- RSTA - MCU
- RSTB - MCU

- RSTC - MCU

LAUNCHXL-F28069M and LAUNCHXL-F28379D Configurations

The LAUNCHXL-F28069M configuration includes the following hardware components:

- LAUNCHXL-F28069M controller
- BOOSTXL-DRV8305 (supported inverter)
- Teknic motor M-2310P (supports both Hall and quadrature encoder sensors)
- Motor BLY171D (supports both Hall and quadrature encoder sensors)
- Motor BLY172S (supports Hall sensor)
- DC power supply

The LAUNCHXL-F28379D configuration includes the following hardware components:

- LAUNCHXL-F28379D controller
- BOOSTXL-DRV8305 and BOOSTXL-3PHGANINV (supported inverters)
- Teknic motor M-2310P (supports both Hall and quadrature encoder sensors)
- Motor BLY171D (supports both Hall and quadrature encoder sensors)
- Motor BLY172S (supports Hall sensor)
- DC power supply

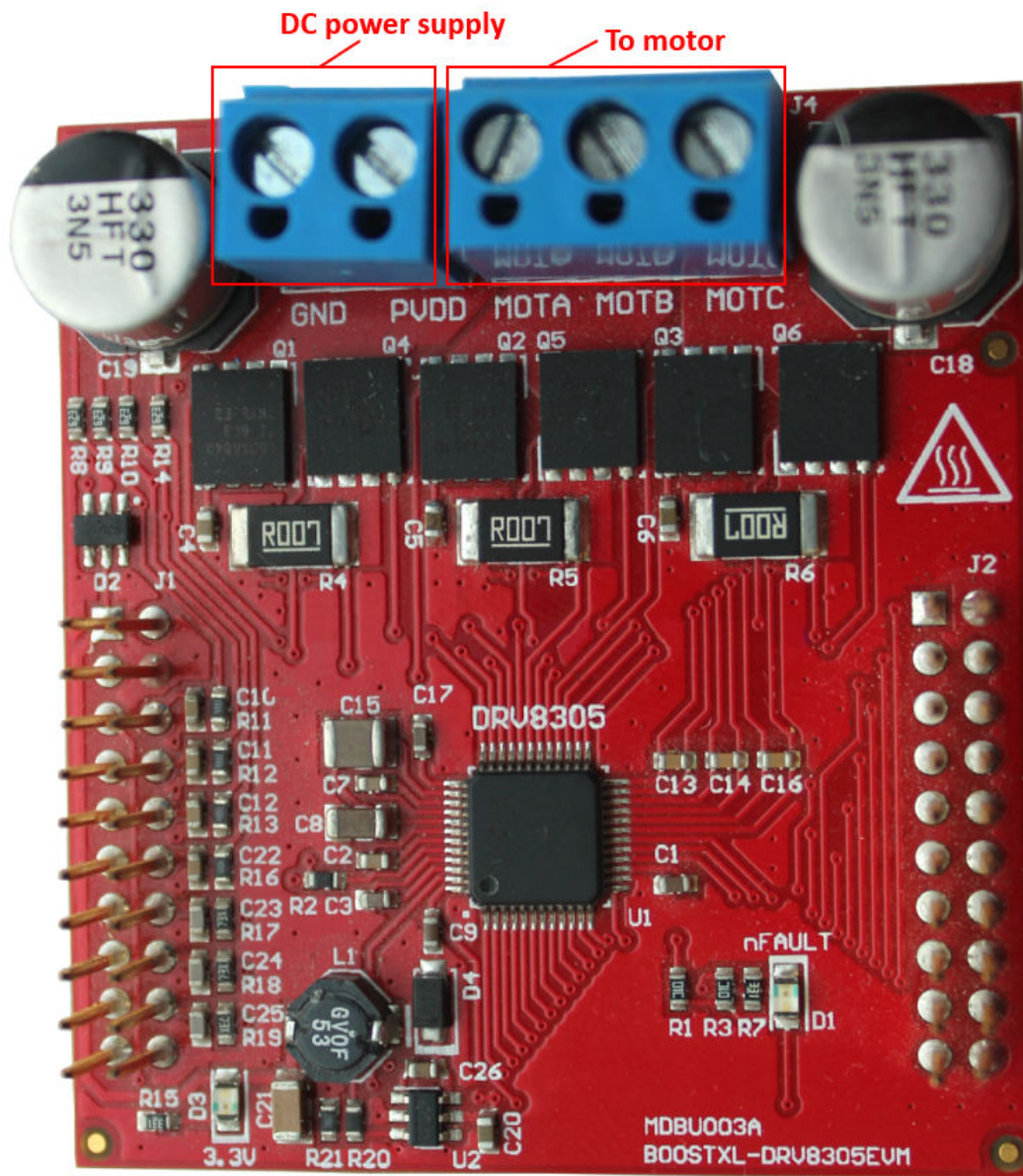
The following steps describe the hardware connections for the LAUNCHXL-F28069M and LAUNCHXL-F28379D configurations:

- 1 Attach the BOOSTXL inverter board to J1, J2, J3, J4 on the LAUNCHXL controller board.

Note Attach the inverter board to the controller board such that J1, J2 of BOOSTXL aligns with J1, J2 of LAUNCHXL.

- 2 Connect the motor three phases, to MOTA, MOTB, and MOTC on the BOOSTXL inverter board.
- 3 Connect the DC power supply (24V) to PVDD and GND on the BOOSTXL inverter board.

Warning Be careful when connecting PVDD and GND to the positive and negative connections of the DC power supply. A reverse connection can damage the hardware components.

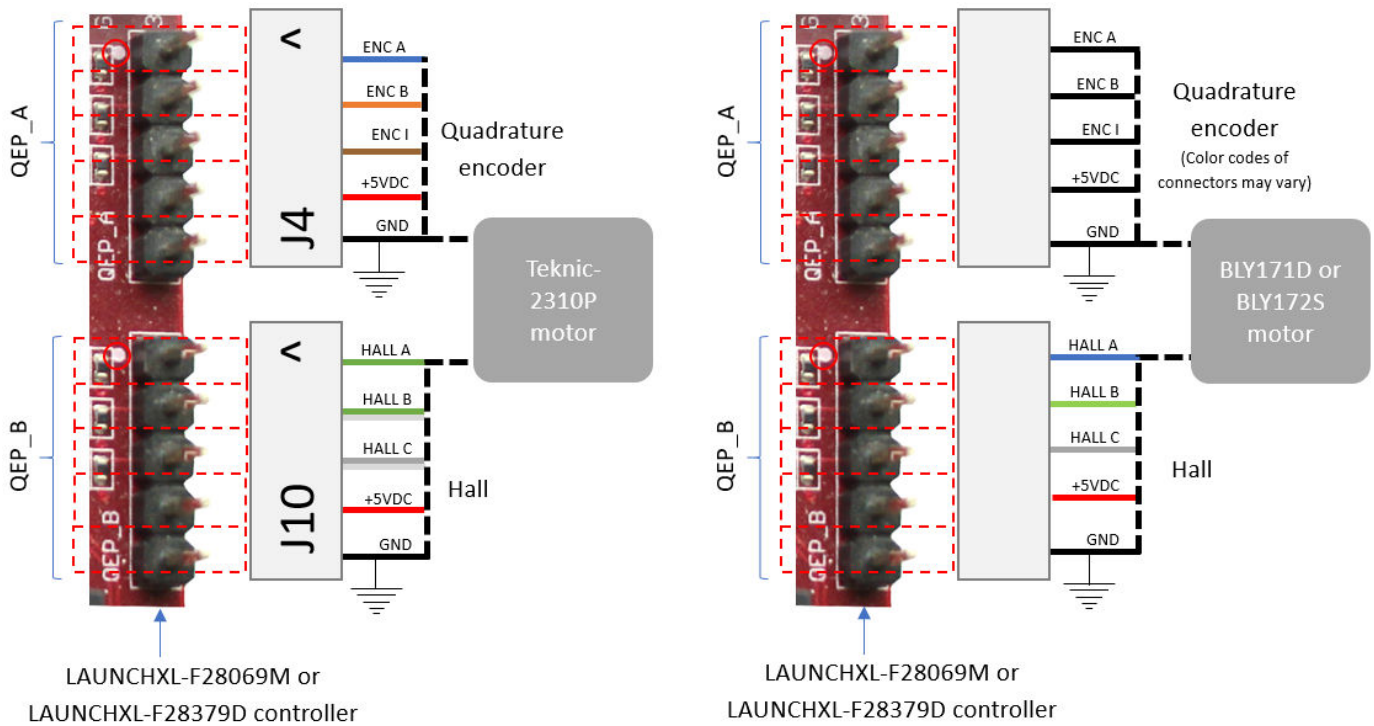


The following step describes about interfacing the quadrature encoder sensor:

- Connect the quadrature encoder pins (G, I, A, 5V, B) to QEP_A on the LAUNCHXL controller board.

To implement position-sensing by using Hall sensor, use a motor that has inbuilt Hall sensors (for example, Teknic motor M-2310P, BLY171D and BLY172S). The following steps describe the steps to interface the Hall sensor:

- Connect the Hall sensor encoder output to a GPIO port that is configured as eCAP, on the LAUNCHXL controller board.



We recommend the following jumper settings for the LAUNCHXL inverter boards when working with Motor Control Blockset. You can customize these settings depending on the application requirements. For more information about these settings, see the device user guide available on Texas Instruments website.

For LAUNCHXL-F28069M controller

- JP1 - ON
- JP2 - ON
- JP3 - ON
- JP4 - ON
- JP5 - ON
- JP6 - OFF
- JP7 - ON

For LAUNCHXL-F28379D controller

- JP1 - ON
- JP2 - ON
- JP3 - ON
- JP4 - ON
- JP5 - ON
- JP6 - OFF

Instructions for Dyno (Dual Motor) Setup

- 1 Connect the three phases of Motor1 and Motor2, to MOTA, MOTB, and MOTC on the corresponding BOOSTXL inverter boards.
- 2 Attach the BOOSTXL inverter board (connected to Motor1) to J1, J2, J3, J4 on the LAUNCHXL controller board.

Note Attach the inverter board to the controller board such that J1, J2 of BOOSTXL aligns with J1, J2 of LAUNCHXL.

- 3 Attach the BOOSTXL inverter board (connected to Motor2) to J5, J6, J7, J8 on the LAUNCHXL controller board.

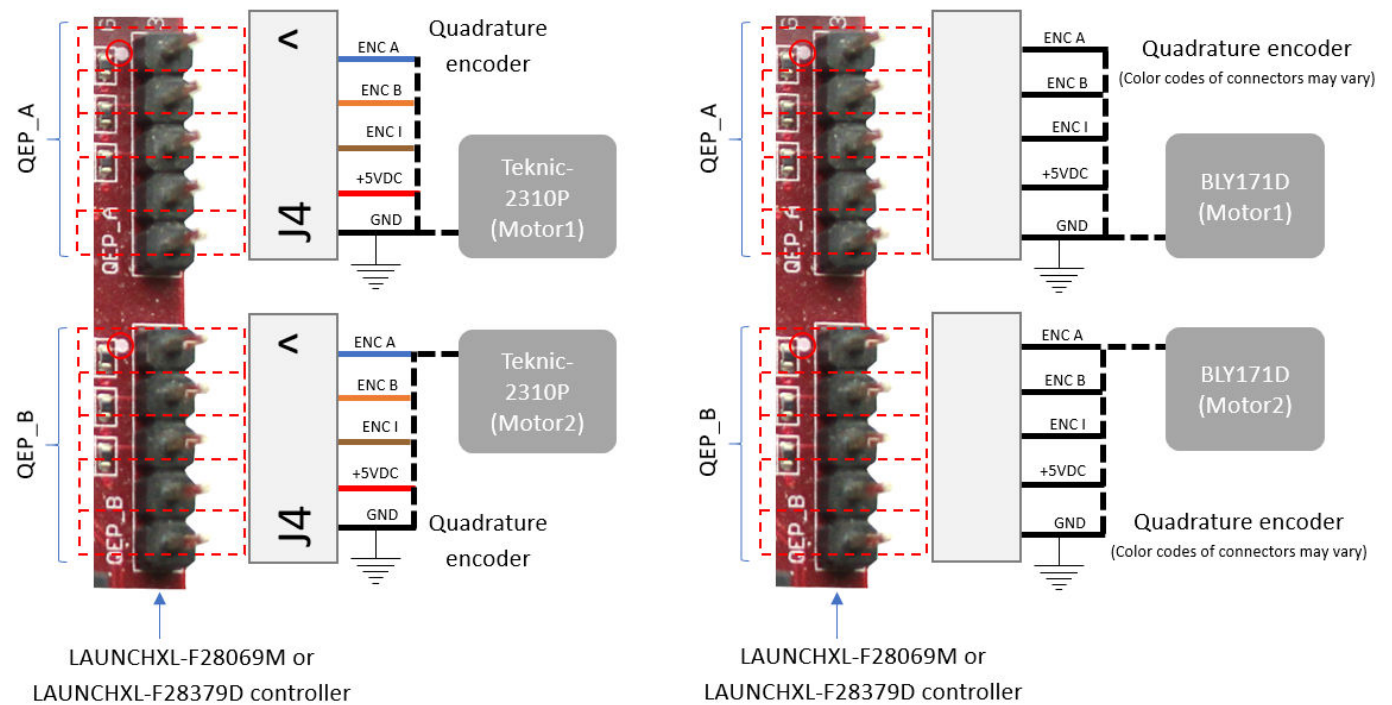
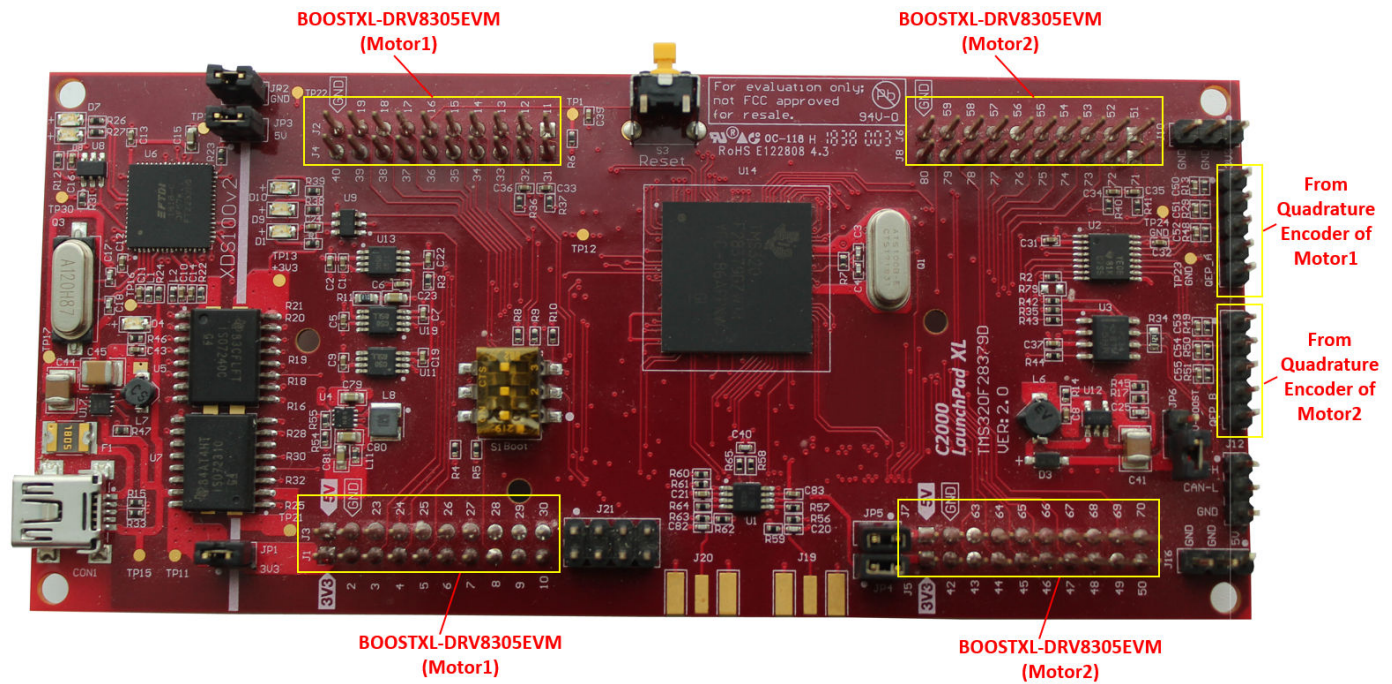
Note Attach the inverter board to the controller board such that J1, J2 of BOOSTXL aligns with J5, J6 of LAUNCHXL.

- 4 Connect the DC power supply (24V) to PVDD and GND on both BOOSTXL inverter boards.

Note Connect the PVDD and GND on the BOOSTXL boards (for MOTOR1 and MOTOR2) to the same power supply. When one motor consumes power, the second motor generates power. If you connect both motors to the same power supply, the power generated by one motor is consumed by the other motor. The DC power supply delivers power only for the losses.

- 5 Connect the quadrature encoder pins of Motor1 (G, I, A, 5V, B) to QEP_A on the LAUNCHXL controller board.
- 6 Connect the quadrature encoder pins of Motor2 (G, I, A, 5V, B) to QEP_B on the LAUNCHXL controller board.

Warning Be careful when connecting PVDD and GND to the positive and negative connections of the DC power supply. A reverse connection can damage the hardware components.



TMDRSRSLVR C2000 Resolver to Digital Conversion Kit

The TMDRSRSLVR C2000 Resolver to Digital Conversion Kit configuration includes the following hardware components:

- LAUNCHXL-F28069M controller

- BOOSTXL-DRV8305 (supported inverter)
- DC power supply
- TMDRSRLVR C2000 Resolver to Digital Conversion Kit (Resolver Eval Kit [R2])
- Resolver encoder

The following steps describe the hardware connections for the TMDRSRLVR board:

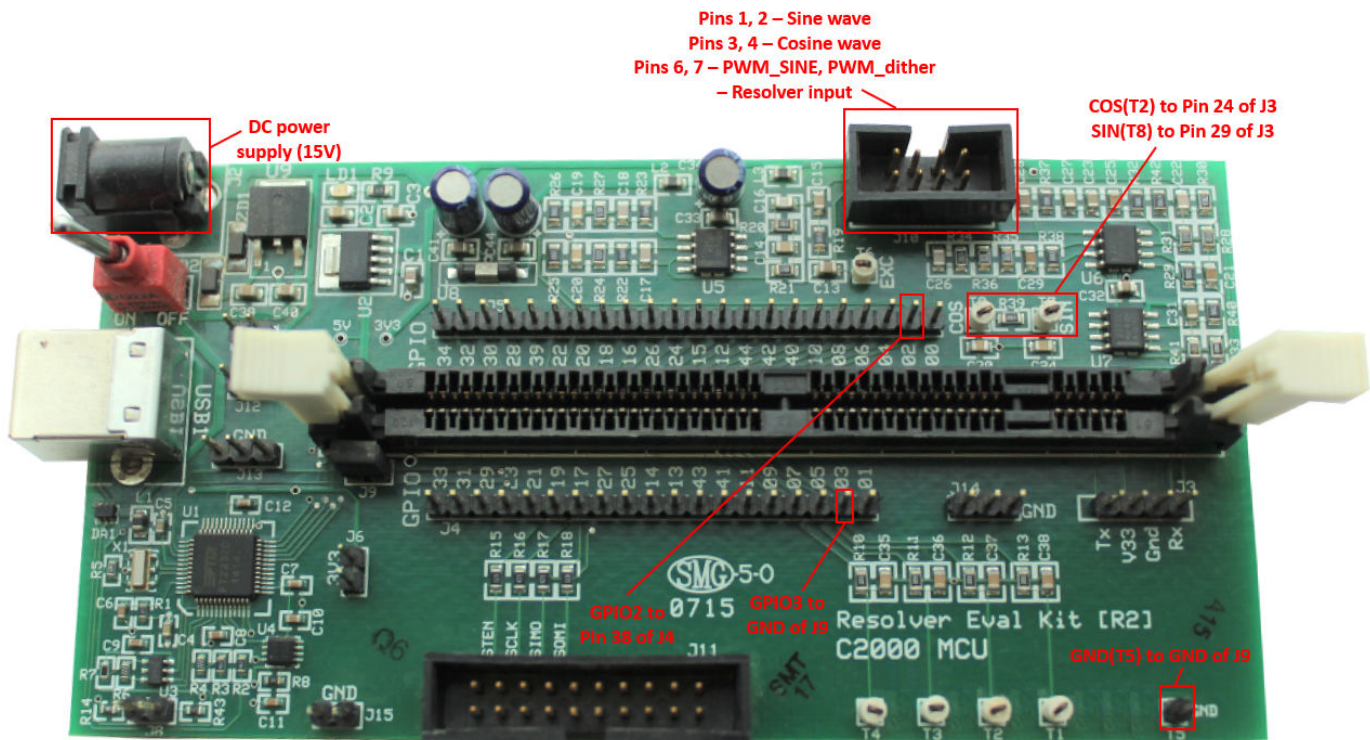
- 1 Connect DC power supply (15V) to J2 on the TMDRSRLVR board.
- 2 Connect the resolver output pins for sine wave to pins 1, 2 of J10 on the TMDRSRLVR board.
- 3 Connect the resolver output pins for cosine wave to pins 3, 4 of J10 on the TMDRSRLVR board.
- 4 Connect the resolver input pins to the PWM_dither and PWM_SINE pins of J10 on the TMDRSRLVR board.

The following step describes the hardware connection for the LAUNCHXL-F28069M controller board:

- Connect the LAUNCHXL-F28069M controller board to a computer via USB port.

The following steps describe the hardware connections between the MCU Resolver Eval Kit [R2] and LAUNCHXL-F28069M controller boards:

- 1 Connect the COS(T2) pin on the TMDRSRLVR board to pin 24 of J3 on the LAUNCHXL-F28069M controller board.
- 2 Connect the SIN(T8) pin on the TMDRSRLVR board to pin 29 of J3 on the LAUNCHXL-F28069M controller board.
- 3 Connect the GPIO2 pin on the TMDRSRLVR board to pin 38 of J4 on the LAUNCHXL-F28069M controller board.



Algorithm Export Workflows for Custom Hardware

- “Open-Loop Control and ADC Offset Calibration” on page 8-2
- “Quadrature Encoder Offset Calibration” on page 8-11
- “Field-Oriented Control” on page 8-18

Open-Loop Control and ADC Offset Calibration

This is the first workflow that uses an algorithm to run a three-phase permanent magnet synchronous motor (PMSM) using open-loop control. The workflow uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you run the host model on the host computer, build and deploy the target model algorithm (integrated with the hardware drivers) to the controller hardware board. The host model uses serial communication to command the target model algorithm and run the motor.

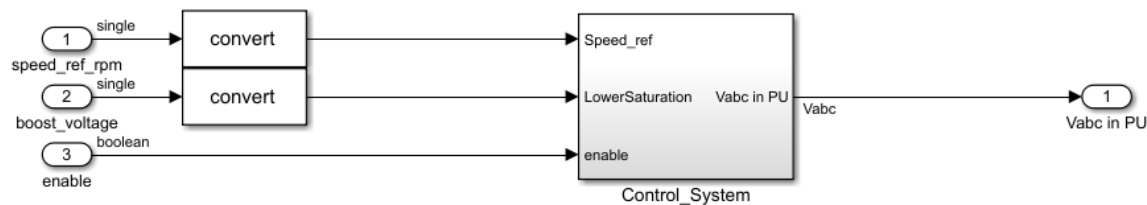
Expand the `open_loop` folder to access these files.

- `open_loop_algorithm.slx` (target model)
- `open_loop_data.m` (model initialization script associated with the target model)
- `open_loop_host.slx` (host model)

Generate Code For Control Algorithm Using Embedded Coder

- 1 After you open the MATLAB project, double-click the `open_loop_algorithm.slx` file in the `open_loop` folder.

Openloop Algorithm

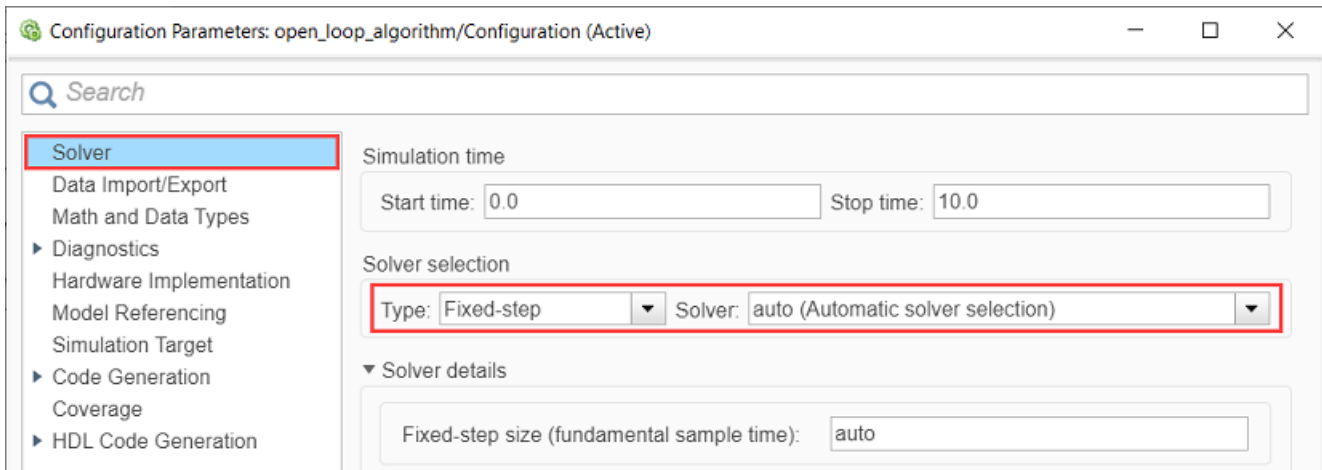


Explore more:

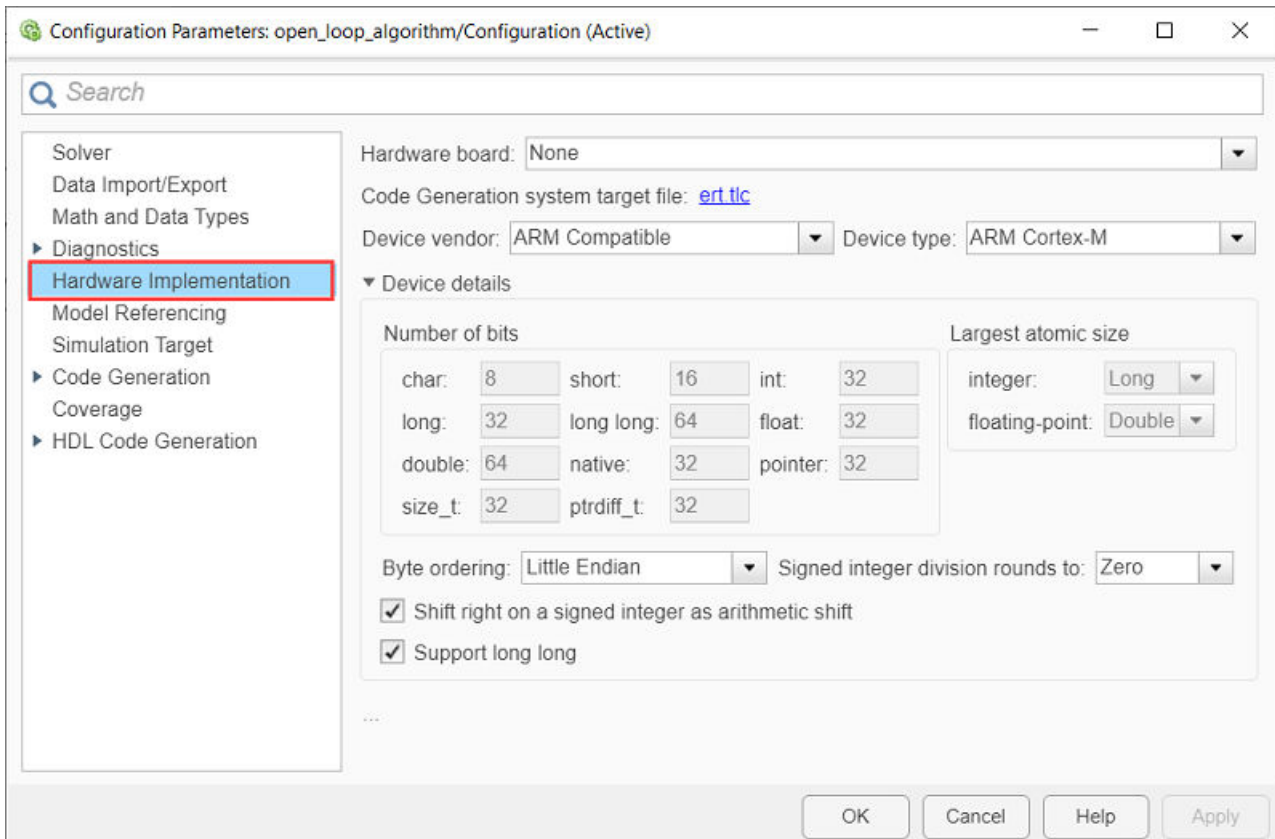
1. [Edit motor & inverter parameters](#)
2. Generate c code using the 'Embedded Coder' app
3. Integrate generated code with driver code
4. Control motor via [host model](#)

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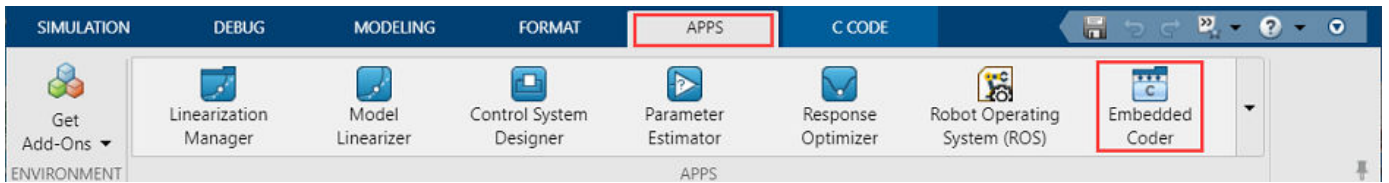
- 2 Select **Modeling > Model Settings > Model Settings** to open the Configuration Parameters dialog box.
- 3 In the **Solver Selection** area of the **Solver** tab, update the **Type** and **Solver** fields.



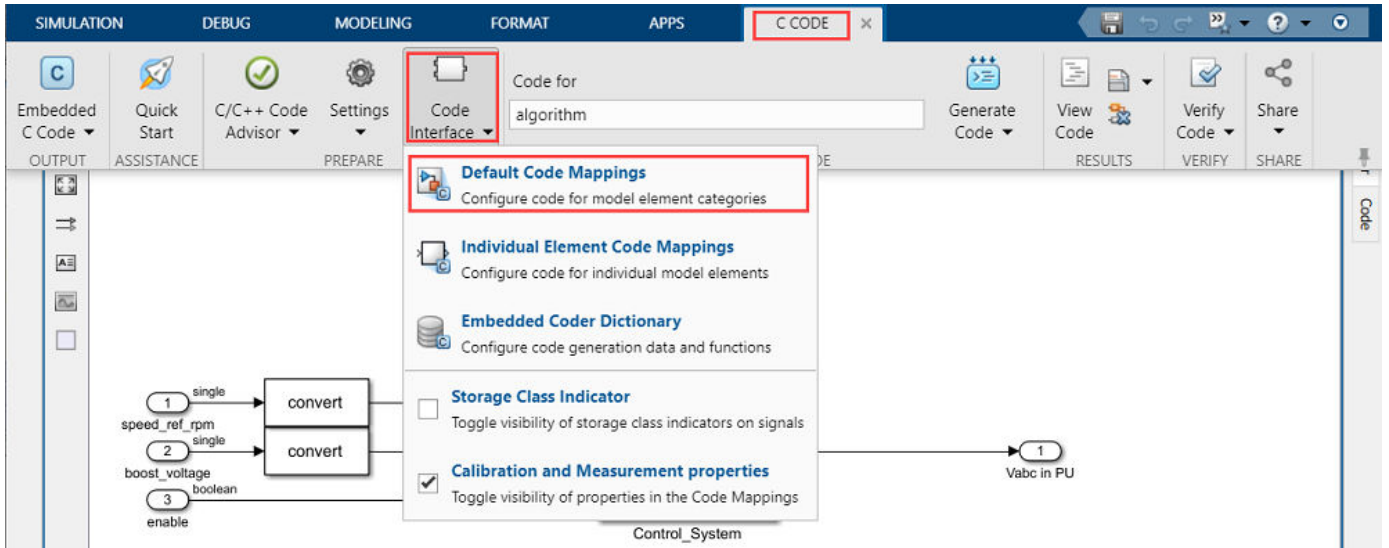
- 4 In the **Hardware Implementation** tab of the Configuration Parameters dialog box, configure the parameters according to your hardware.



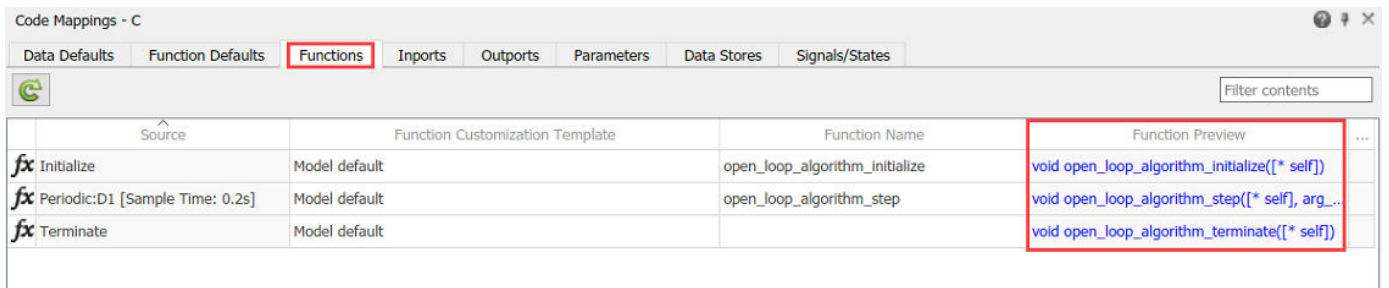
- 5 In the Simulink toolstrip of the target model, select **Apps > Embedded Coder** to open the Embedded Coder application.



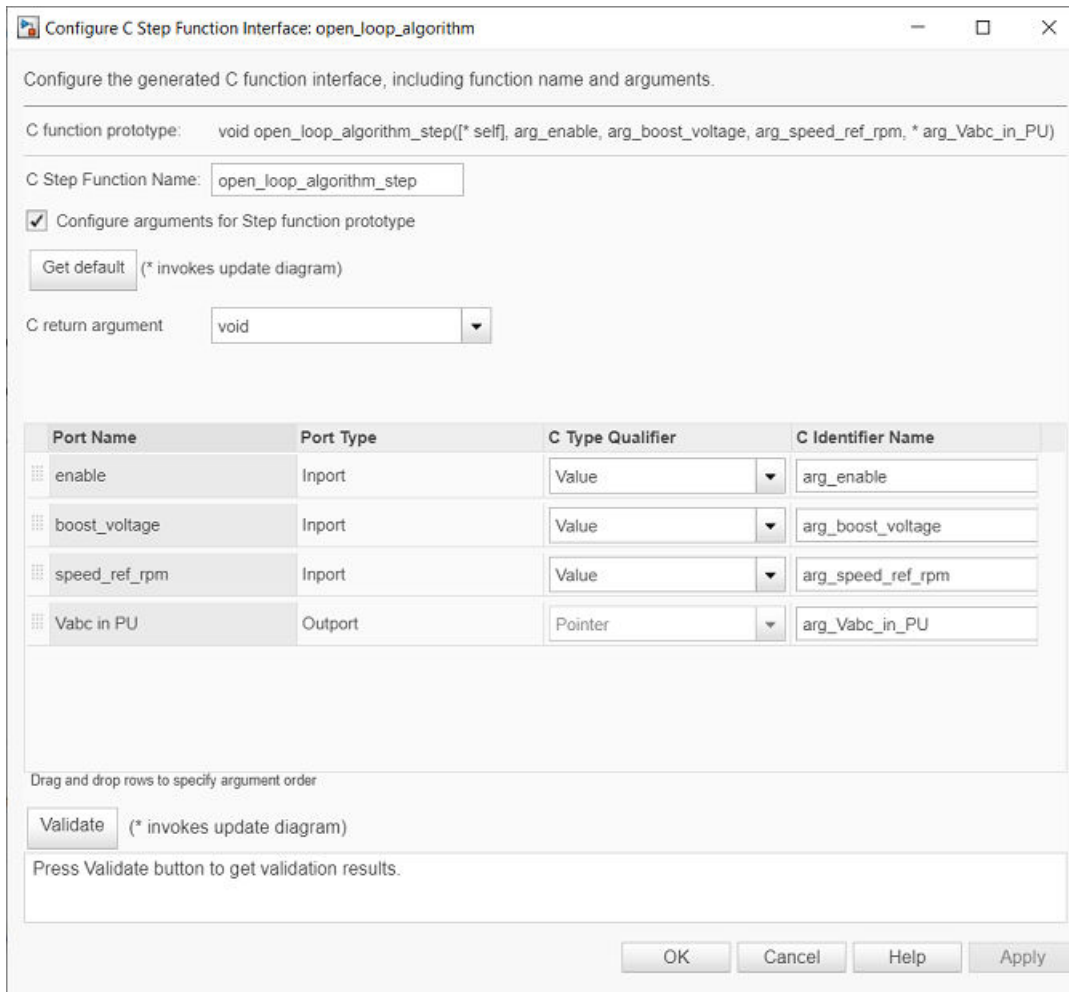
- 6 In the Simulink toolstrip, select **C Code > Code Interface > Default Code Mappings** to open the Code Mappings - C dialog box.



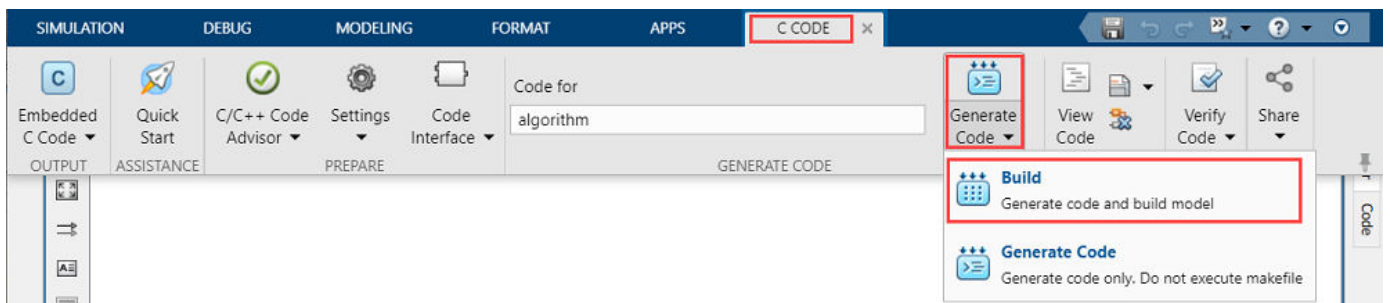
- 7 In the Code Mappings - C dialog box, open the **Functions** tab.
- 8 For a listed C function, click the hyperlink under the **Function Preview** column to open the Configure C Initialize Function Interface dialog box.



- 9 Use the Configure C Initialize Function Interface dialog box to configure the interface and arguments of the C function.



- 10 Click **Apply** and **OK** to complete configuring the C function.
- 11 Repeat steps 10 to 12 for all the listed functions.
- 12 In the Simulink toolstrip of the target model, select **C Code** > **Generate Code** > **Build** to build the model and generate a .c file for the target model.



This image shows an example of the generated code for a C function.

```

/* Model step function */
void open_loop_algorithm_step(boolean_T arg_enable, real32_T arg_boost_voltage,
    real32_T arg_speed_ref_rpm, real32_T arg_Vabc_in_PU[3])
{
    real32_T rtb_Abs;
    real32_T rtb_Abs_g;
    real32_T rtb_Sum4;
    real32_T rtb_Sum6;
    real32_T rtb_Switch_o_idx_0;
    real32_T rtb_add_b;
    uint16_T rtb_Get_Integer_tmp_tmp;

    /* DiscreteIntegrator: '<S4>/Ramp Generator' incorporates:

```

Note

- The generated C function uses the interface that you configured.
 - For details about the per-unit system used in the algorithm, see “Per-Unit System” on page 6-16.
-

Obtain C Code For Hardware Drivers

You can use the code generation software supported by the hardware manufacturer to generate the code for the hardware drivers. For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, you can use the STM32CubeMX STM32Cube initialization code generator software to configure the hardware peripherals and generate C code for the hardware drivers. The example also includes the FOC_QEP.ioc file (created by STM32CubeMX software) containing the hardware initialization data for the reference hardware.

Alternatively, you can also use a manually written driver code.

Integrate Control Algorithm Code With Driver Code

- 1 Call the control algorithm functions from the driver code using the configured control algorithm function parameters. This image shows a call to the speed control algorithm C function.

```

// call the open loop algorithm step function
open_loop_algorithm_step(ENABLE_INV, VOLTAGE_AMP_LOW_LIMIT, SPEED_REF, duty_vals);

// scale duty ratio to PWM counter period
for (int i = 0; i < 3; i++)
{
    duty_vals[i] = (1 - duty_vals[i]) * htim1.Init.Period;
}

// update duty cycles

```

- 2 Use the return value from the function call to complete integrating the driver with the controller algorithm.

For details about the code structure and program control flow used by the Motor Control Blockset examples, see “Program Control Flow of Motor Control Blockset Examples” on page 6-19.

View the integrated sample code `main.c` available in the `open_loop\STM32Code` folder as a reference.

Deploy Integrated Code to Hardware

- 1 Complete the hardware connections.
- 2 Use the code generation and deployment software supported by the hardware manufacturer to compile, build, and generate a binary (for example `.HEX`) file from the integrated code. Use the software to flash the binary file to the target hardware.

For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, use the STM32CubeMX STM32Cube initialization code generator to generate and flash the binary file.

Control Motor Using Host Simulink Model

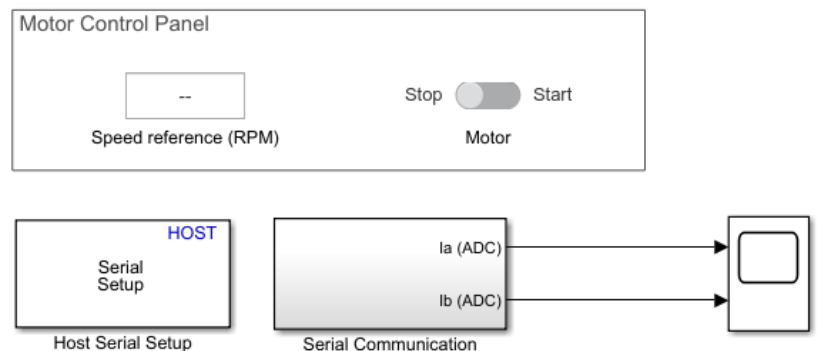
Follow these steps to run a three-phase PMSM using open-loop control:

- 1 Click the **host model** hyperlink in the target model to open the associated host model. You can also double-click the `open_loop_host.slx` file in the `open_loop` folder.

Openloop Control Host

Steps:

1. Set the baud rate for serial communication in '**Host Serial Setup**' block.
2. Select the serial port in '**Serial 1**' tab of '**Host Serial Setup**' block.
3. Use '**Motor Start / Stop**' switch to control the motor.
4. Enter speed request in RPM using 'Speed Reference' edit box. Limit the reference speed to half of the rated speed.
5. Observe the ADC counts for phase current measurement in Scope.



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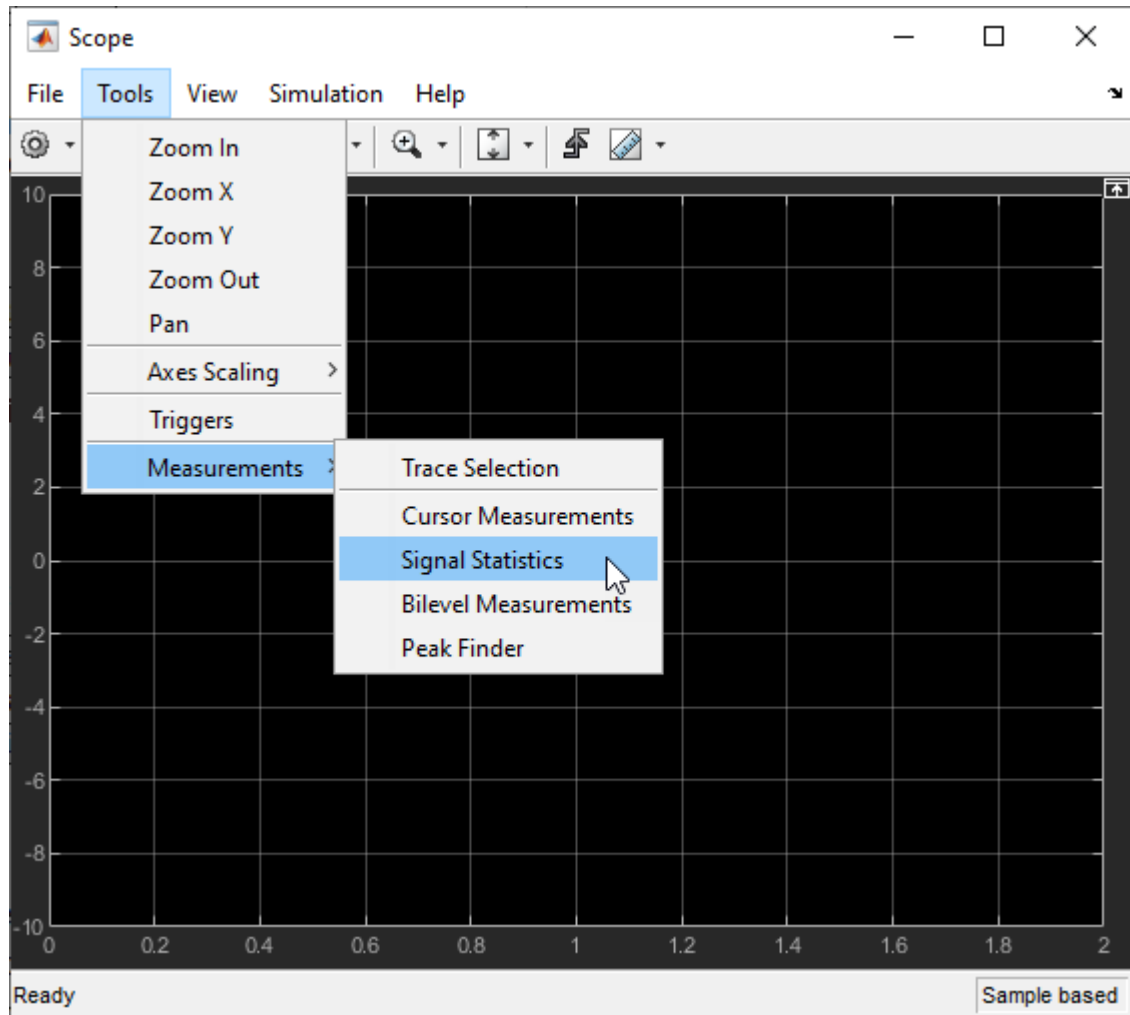
- 2 In the **Serial 1** tab of the block parameters dialog box for the Host Serial Setup block, select a **Port name** and enter a **Baud rate** for serial communication.

For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

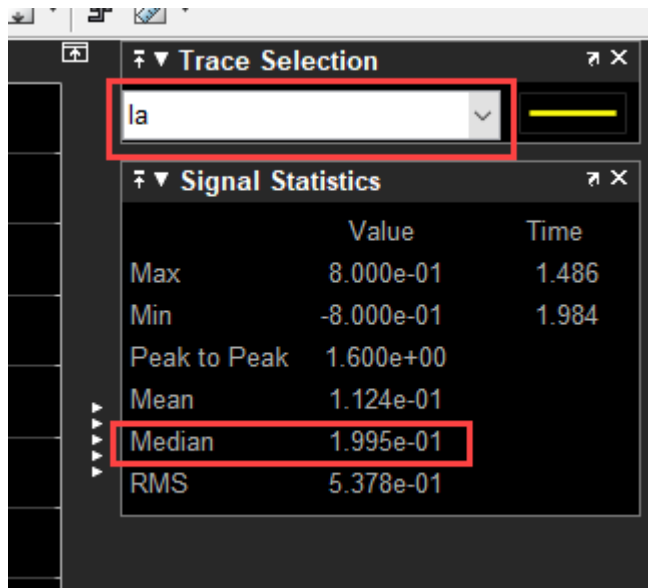
- 3** Click **Run** on the **Simulation** tab to run the host model.
- 4** Turn the **Motor** slider switch to the **Start** position to start running the motor.
- 5** Update the reference speed value in the **Speed Reference (RPM)** field. It is recommended that you set the speed to a value that is approximately half the rated speed of the motor.
- 6** After the motor runs, observe the ADC counts for the I_a and I_b currents in the time scope.
- 7** Stop the host model simulation and turn the **Motor** slider switch to the **Stop** position to stop the motor.

Follow these steps to determine the ADC offsets for the current sensors:

- 1** Disconnect the DC voltage supply from the hardware.
- 2** Disconnect the motor wires for three phases from the hardware board terminals and then reconnect the DC voltage supply to the hardware.
- 3** Click **Run** on the **Simulation** tab to run the host model.
- 4** Observe the ADC counts for the I_a and I_b currents in the time scope. The average values of the ADC counts are the ADC offset corrections for the currents I_a and I_b . Follow these steps to obtain the average (median) values of ADC counts:
 - In the Scope window, navigate to **Tools > Measurements** and select **Signal Statistics** to display the **Trace Selection** and **Signal Statistics** areas.



- Under **Trace Selection**, select a signal (I_a or I_b). The time scope displays the characteristics of the selected signal in the **Signal Statistics** area. You can see the median value of the selected signal in the **Median** field.



Update this ADC (or current) offset value in the *inverter.CtSensAOffset* and *inverter.CtSensBOffset* variables in the model initialization script linked to "Field-Oriented Control" on page 8-18.

To compute the offset of the quadrature encoder position sensor attached to the motor, see "Quadrature Encoder Offset Calibration" on page 8-11.

Quadrature Encoder Offset Calibration

This is the second workflow that uses an algorithm to calculate the offset between the d -axis of the rotor and the index pulse position as detected by the quadrature encoder sensor attached to the permanent magnet synchronous motor (PMSM). The workflow uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you run the host model on the host computer, build and deploy the target model algorithm (integrated with the hardware drivers) to the controller hardware board. The host model uses serial communication to command the target model algorithm and run the motor.

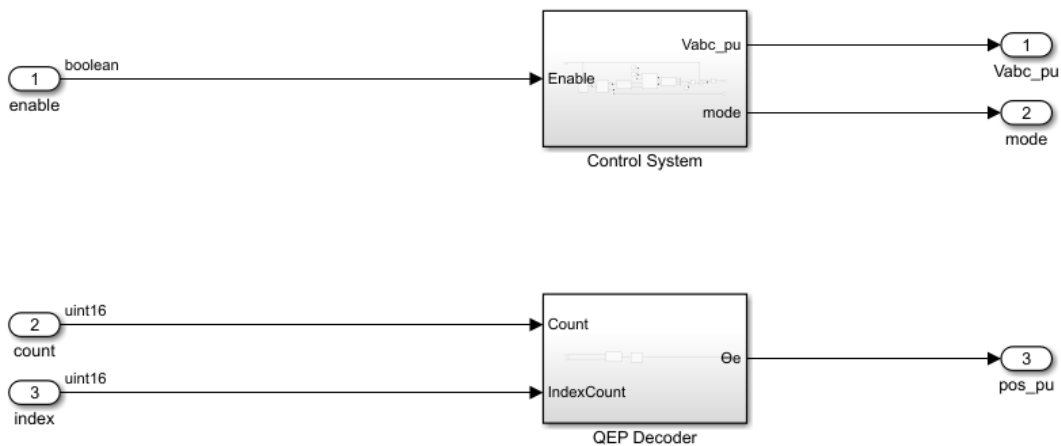
Expand the `qep_calibration` folder to access these files.

- `qep_calibration_algorithm.slx` (target model)
- `qep_calibration_data.m` (model initialization script associated with the target model)
- `qep_calibration_host.slx` (host model)

Generate Code For Control Algorithm Using Embedded Coder

- 1 After you open the MATLAB project, double-click the `qep_calibration_algorithm.slx` file in the `qep_calibration` folder.

Offset Computation algorithm for QEP

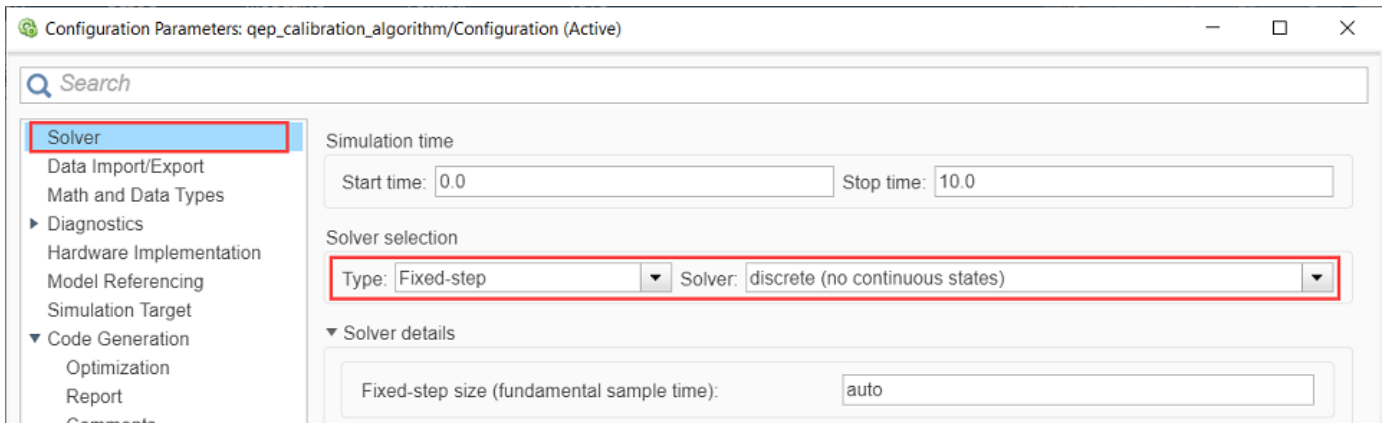


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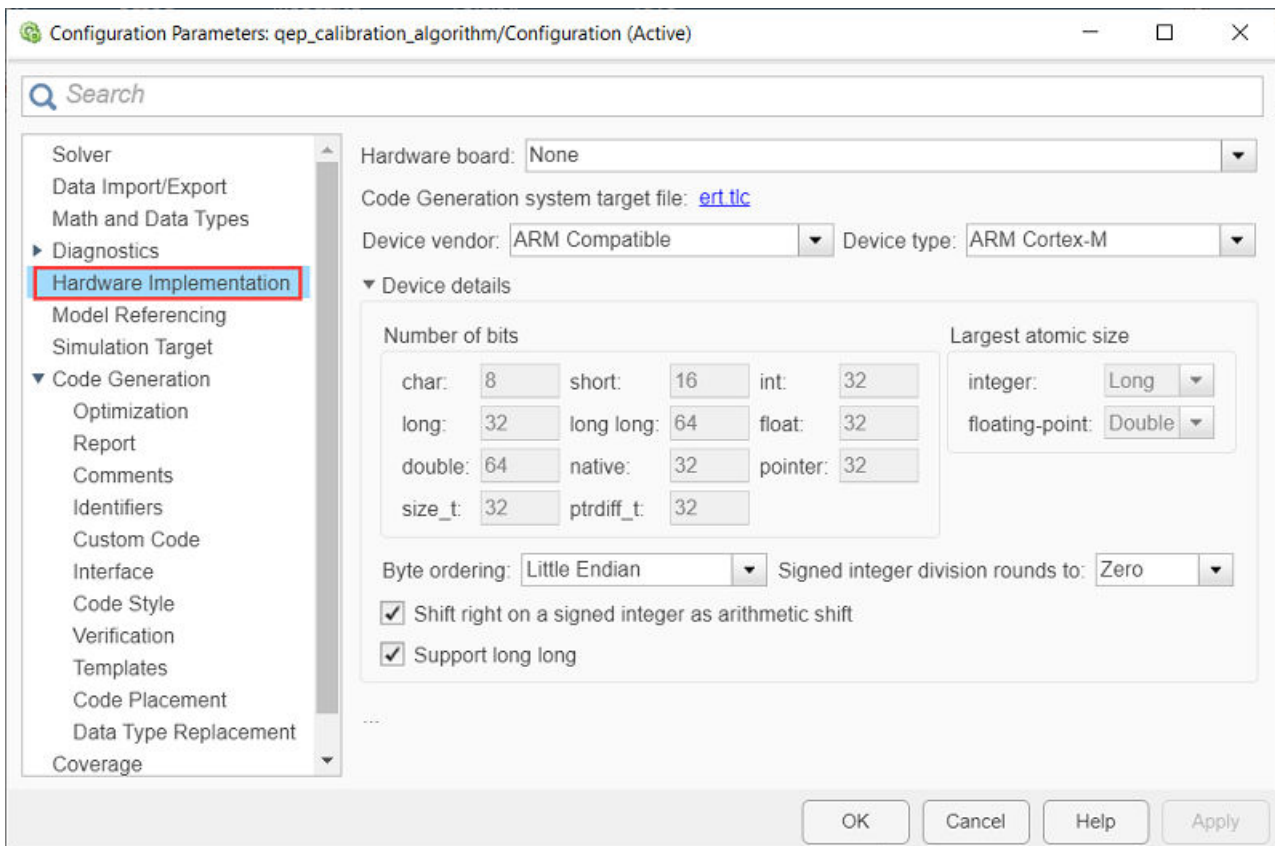
Explore more:

1. [Edit motor & inverter parameters](#)
2. Generate c code using the 'Embedded Coder' app
3. Integrate generated code with driver code
4. Control motor via [host model](#)

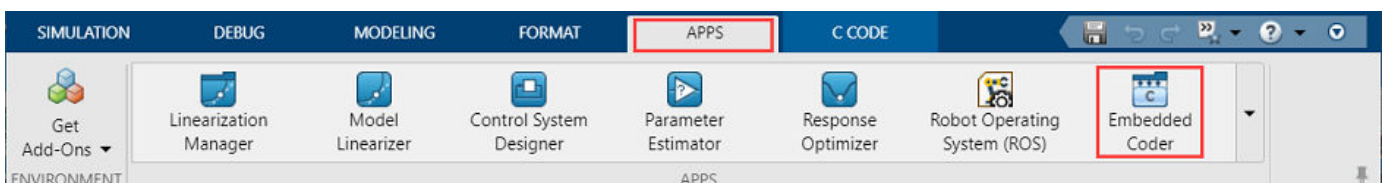
- 2 Select **Modeling > Model Settings > Model Settings** to open the Configuration Parameters dialog box.
- 3 In the **Solver Selection** area of the **Solver** tab, update the **Type** and **Solver** fields.



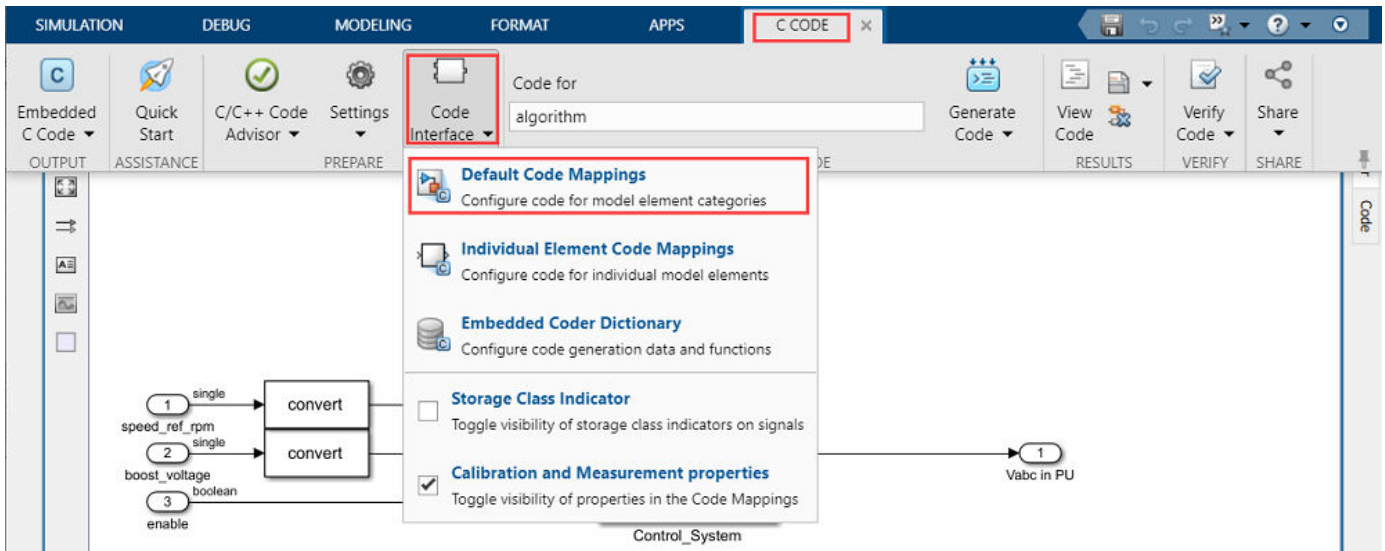
- 4 In the **Hardware Implementation** tab of the Configuration Parameters dialog box, configure the parameters according to your hardware.



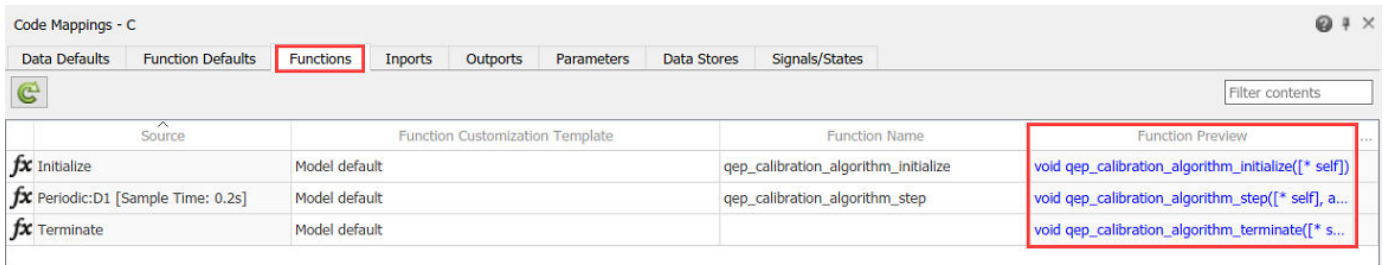
- 5 In the Simulink toolstrip of the target model, select **Apps > Embedded Coder** to open the Embedded Coder application.



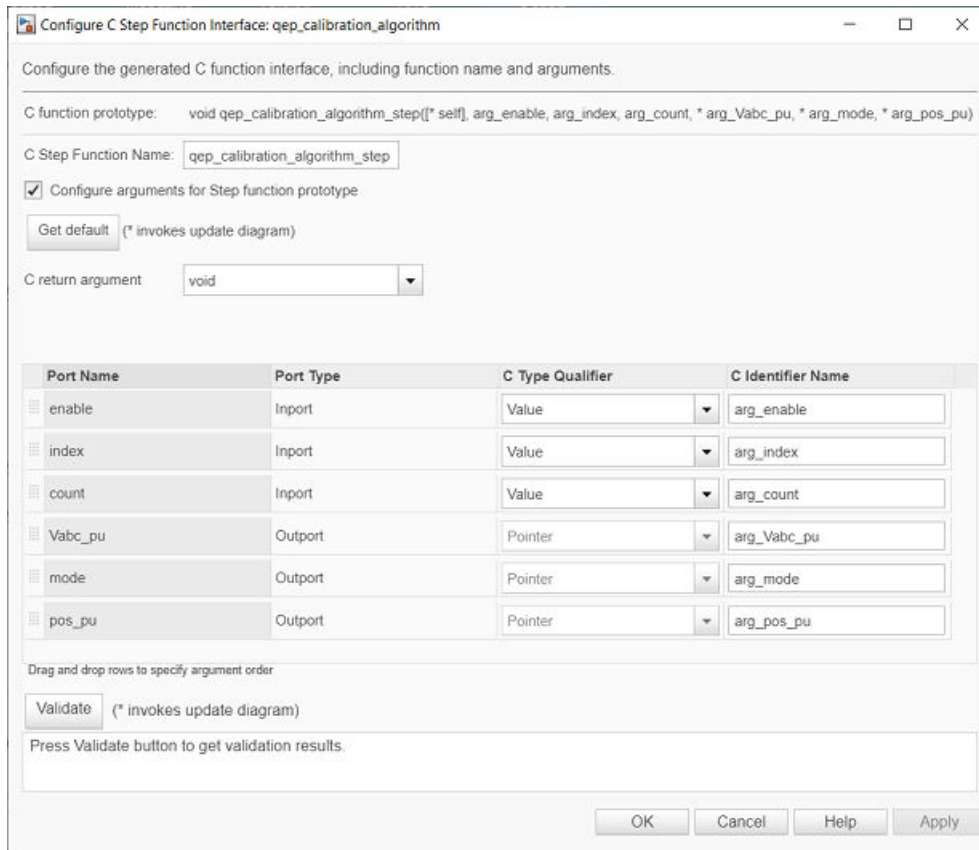
- In the Simulink toolstrip, select **C Code > Code Interface > Default Code Mappings** to open the Code Mappings - C dialog box.



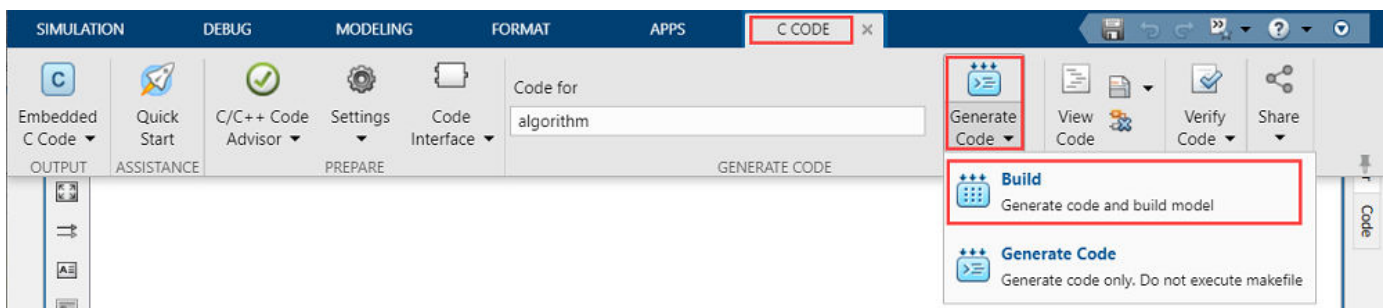
- In the Code Mappings - C dialog box, open the **Functions** tab.
- For a listed C function, click the hyperlink under the **Function Preview** column to open the Configure C Initialize Function Interface dialog box.



- Use the Configure C Initialize Function Interface dialog box to configure the interface and arguments of the C function.



- 10 Click **Apply** and **OK** to complete configuring the C function.
- 11 Repeat steps 10 to 12 for all the listed functions.
- 12 In the Simulink toolstrip of the target model, select **C Code** > **Generate Code** > **Build** to build the model and generate a .c file for the target model.



This image shows an example of the generated code for a C function.

```

/* Model step function */
void qep_calibration_algorithm_step(boolean_T arg_enable, uint16_T arg_index,
    uint16_T arg_count, real32_T arg_Vabc_pu[3], real32_T *arg_mode, real32_T
    *arg_pos_pu)
{
    real32_T rtb_Abs;
    real32_T rtb_Sum4;
    real32_T rtb_Switch_j;
    real32_T rtb_Switch_o_idx_0;
    real32_T rtb_add_c;
    uint16_T rtb_Sum3;

    /* Outputs for Enabled SubSystem: '<S1>/counter' incorporates:

```

Note

- The generated C function uses the interface that you configured.
 - For details about the per-unit system used in the algorithm, see “Per-Unit System” on page 6-16.
-

Obtain C Code For Hardware Drivers

You can use the code generation software supported by the hardware manufacturer to generate the code for the hardware drivers. For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, you can use the STM32CubeMX STM32Cube initialization code generator software to configure the hardware peripherals and generate C code for the hardware drivers. This example also includes the FOC_QEP.ioc file (created by STM32CubeMX software) containing the hardware initialization data for the reference hardware.

Alternatively, you can also use a manually written driver code.

Integrate Control Algorithm Code With Driver Code

- 1 Call the control algorithm functions from the driver code using the configured control algorithm function parameters. This image shows a call to the speed control algorithm C function.

```

// call the QEP calibration algorithm step function
qep_calibration_algorithm_step(ENABLE_INV, QEP_INDEX_COUNT, QEP_COUNT, duty_vals, &mode, &position_meas);

uint16_t debug_1 = (uint16_t)(position_meas * 65535);
uint16_t debug_2 = (uint16_t)mode;

// scale duty ratio to PWM counter period
for (int i = 0; i < 3; i++)
{
    duty_vals[i] = (1 - duty_vals[i]) * htim1.Init.Period;
}

// update duty cycles

```

- 2 Use the return value from the function call to complete integrating the driver with the controller algorithm.

For details about the code structure and program control flow used by the Motor Control Blockset examples, see “Program Control Flow of Motor Control Blockset Examples” on page 6-19.

View the integrated sample code `main.c` available in the `qep_calibration\STM32Code` folder as a reference.

Deploy Integrated Code to Hardware

- 1 Complete the hardware connections.
- 2 Use the code generation and deployment software supported by the hardware manufacturer to compile, build, and generate a binary (for example `.HEX`) file from the integrated code. Use the software to flash the binary file to the target hardware.

For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, use the STM32CubeMX STM32Cube initialization code generator to generate and flash the binary file.

Control Motor Using Host Simulink Model

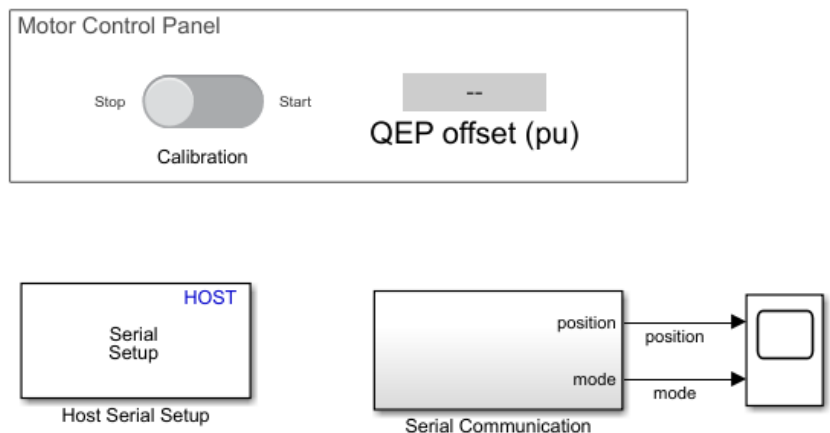
Follow these steps to determine the offset of the quadrature encoder sensor attached to a three-phase PMSM:

- 1 Click the **host model** hyperlink in the target model to open the associated host model. You can also double-click the `qep_calibration_host.slx` file in the `qep_calibration` folder.

QEP offset calibration host

Steps:

1. Set the baud rate for serial communication in 'Host Serial Setup' block.
2. Select the serial port in 'Serial 1' tab of 'Host Serial Setup' block.
3. Use 'Calibration Start / Stop' switch to control the motor.
4. Observe the position signal on the scope and ensure that the signal has a positive slope. If not, stop the calibration, disconnect the power supply and interchange two of the motor phases.
5. The calculated offset will be displayed on the "QEP offset (pu)" block



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- 2 In the **Serial 1** tab of the block parameters dialog box for the Host Serial Setup block, select a **Port name** and enter a **Baud rate** for serial communication.

For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

- 3 Click **Run** on the **Simulation** tab to run the host model.
- 4 Turn the **Calibration** slider switch to the **Start** position to start the calibration process by running the motor.
- 5 Observe the *position* signal in the time scope.

After the calibration process is complete, simulation ends and the motor stops automatically. The model displays the computed encoder offset value in the **QEP offset (pu)** field.

- 6 Check if the *position* signal has a positive slope. Follow these steps, if the slope is negative:
 - Turn the **Calibration** slider switch to the **Stop** position to stop the calibration process and stop running the motor.
 - Disconnect the DC voltage supply from the hardware.
 - Interchange any two motor phase connections and then reconnect the DC voltage supply to the hardware.
 - Follow steps 4 and 5 to run the calibration algorithm again and determine the encoder offset value.

The example automatically saves the computed offset value in the *PositionOffset* variable available in the base workspace.

Update computed offset value in the *pmsm.PositionOffset* variable available in the model initialization script linked to “Field-Oriented Control” on page 8-18.

Field-Oriented Control

This is the third workflow that runs a three-phase permanent magnet synchronous motor (PMSM) using closed-loop field-oriented control (FOC). For more details about FOC, see “Field-Oriented Control (FOC)” on page 4-2. The workflow uses a host and a target model. The host model is a user interface to the controller hardware board. You can run the host model on the host computer. Before you run the host model on the host computer, build and deploy the target model algorithm (integrated with the hardware drivers) to the controller hardware board. The host model uses serial communication to command the target model algorithm and run the motor.

Expand the `foc_qep` folder to access these files.

- `current_control_algorithm.slx` (target model for current controller)
- `speed_control_algorithm.slx` (target model for speed controller)
- `foc_qep_data.m` (model initialization script associated with the target models)
- `foc_qep_host.slx` (host model)

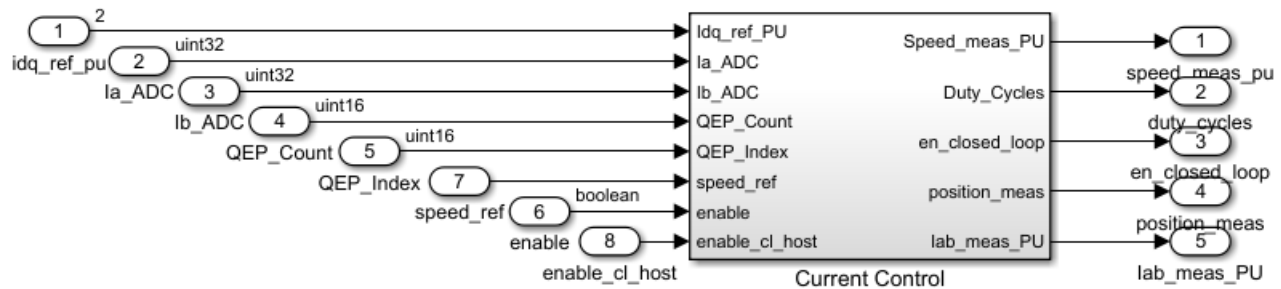
Before using this workflow, complete “Open-Loop Control and ADC Offset Calibration” on page 8-2 and “Quadrature Encoder Offset Calibration” on page 8-11 to compute the ADC and position sensor offsets. Update the offsets in these variables available in the model initialization script `foc_qep_data.m`:

- `inverter.CtSensAOffset` and `inverter.CtSensBOffset` variables (ADC offsets for I_a and I_b current sensors)
- `pmsm.PositionOffset` (position offset for quadrature encoder sensor)

Generate Code For Control Algorithm Using Embedded Coder

- 1 After you open the MATLAB project, double-click the `current_control_algorithm.slx` file in the `foc_qep` folder.

Current Control Algorithm

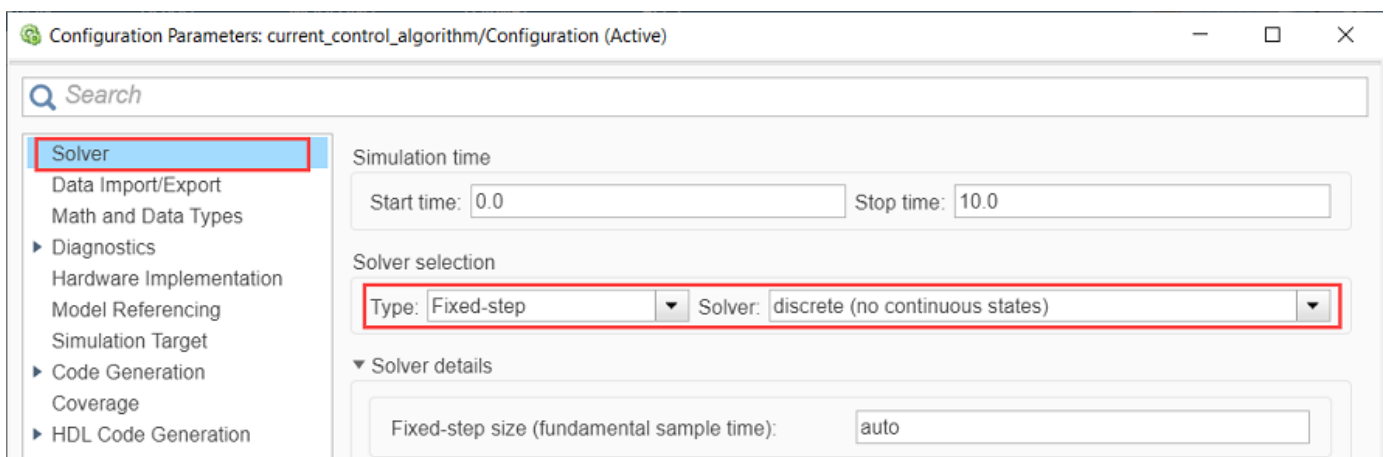


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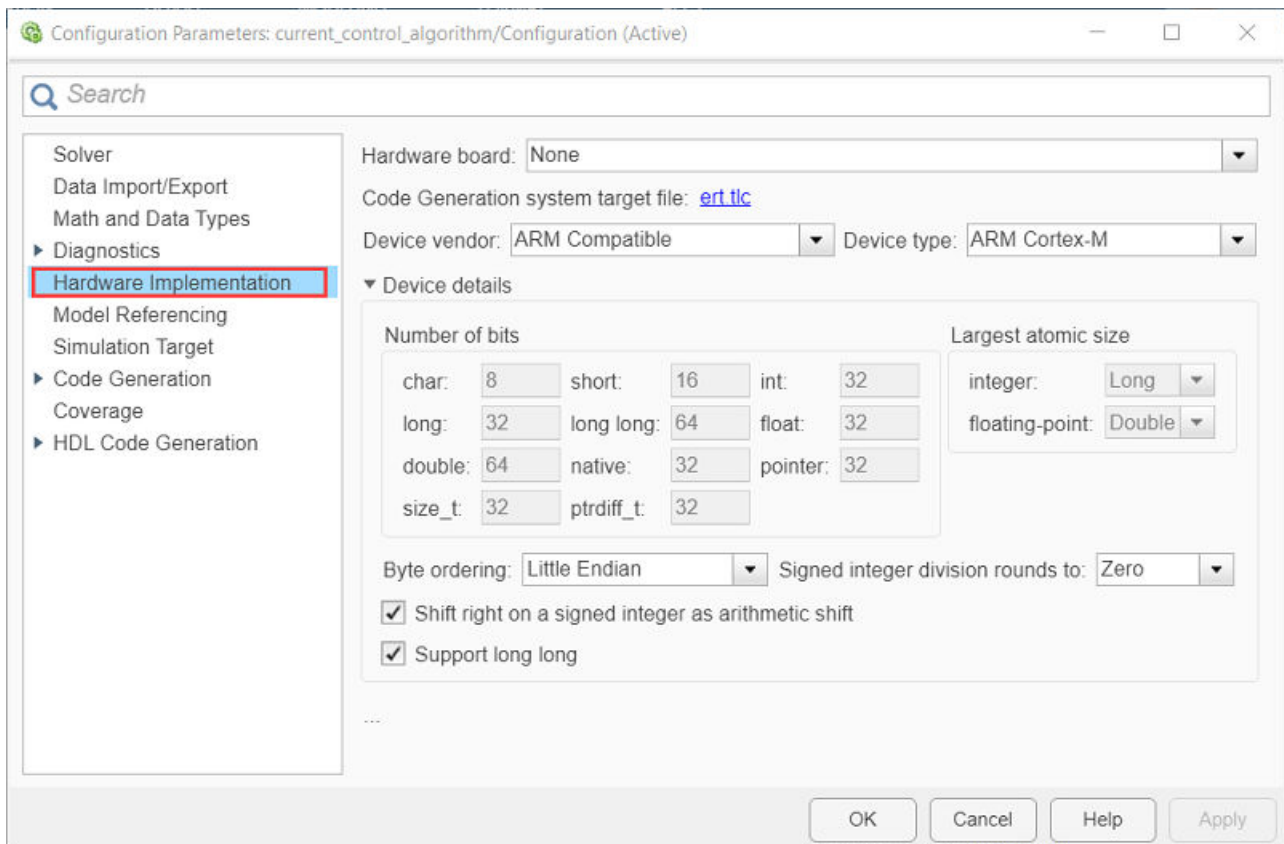
Explore more:

1. [Edit motor & inverter parameters](#)
2. Generate c code using the 'Embedded Coder' app
3. Integrate generated code with driver code
4. Control motor via [host model](#)

- 2 Select **Modeling > Model Settings > Model Settings** to open the Configuration Parameters dialog box.
- 3 In the **Solver Selection** area of the **Solver** tab, update the **Type** and **Solver** fields.



- 4 In the **Hardware Implementation** tab of the Configuration Parameters dialog box, configure the parameters according to your hardware.



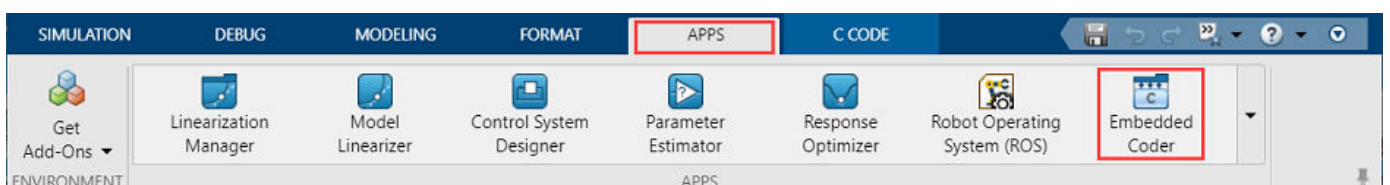
- 5 Obtain the motor and inverter parameters. The target model uses default motor parameters that you can replace with values from either the motor datasheet or other sources.

However, you can use your motor control hardware to estimate the parameters for the motor that you want to use by using the Motor Control Blockset parameter estimation tool. For instructions, see “Estimate PMSM Parameters Using Custom Hardware” on page 4-210. The parameter estimation tool updates the *motorParam* variable (in the MATLAB workspace) with the estimated motor parameters.

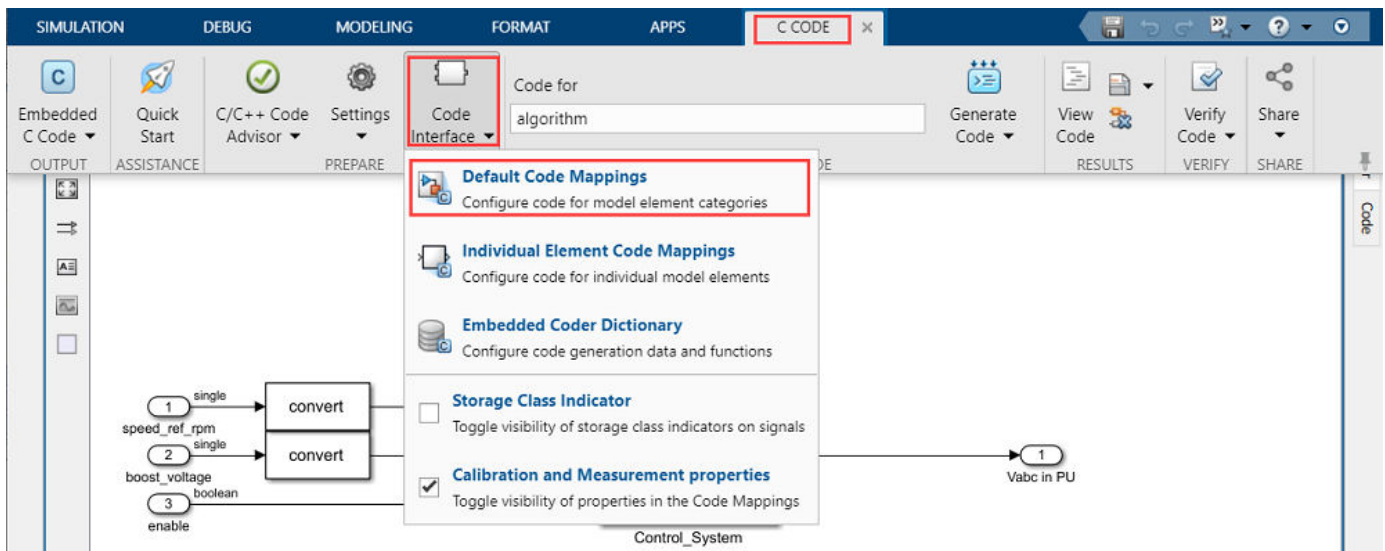
- 6 Update the motor and inverter parameters. If you obtain the motor parameters from the datasheet or from other sources, update the motor and inverter parameters in the model initialization script (*foc_qep_data.m*) associated with the Simulink model. For instructions, see “Estimate Control Gains from Motor Parameters” on page 3-2.

If you use the parameter estimation tool, you can update the inverter parameters, but do not update the motor parameters in the model initialization script. The script automatically extracts the motor parameters from the updated *motorParam* workspace variable.

- 7 In the Simulink toolstrip of the target model, select **Apps > Embedded Coder** to open the Embedded Coder application.



- 8 In the Simulink toolstrip, select **C Code > Code Interface > Default Code Mappings** to open the Code Mappings - C dialog box.



- 9 In the Code Mappings - C dialog box, open the **Functions** tab.
- 10 For a listed C function, click the hyperlink under the **Function Preview** column to open the Configure C Initialize Function Interface dialog box.

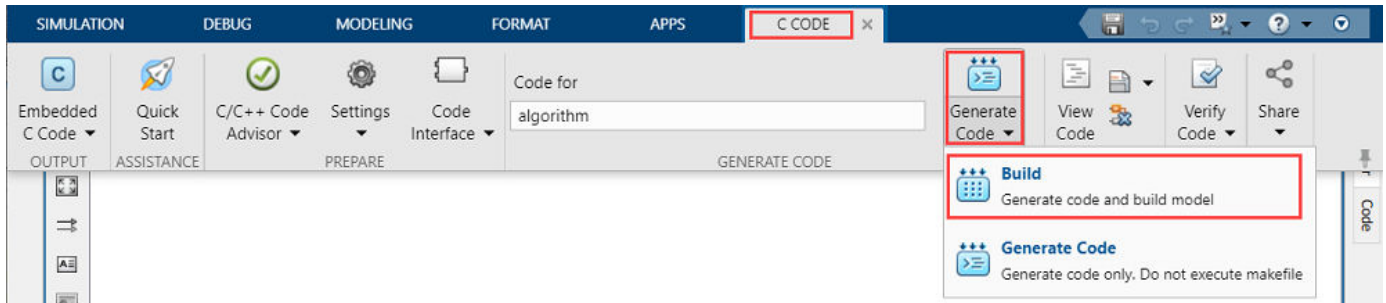
The screenshot shows the 'Code Mappings - C' dialog box with the 'Functions' tab selected. The table below lists the functions and their previews. The 'Function Preview' column is highlighted with a red box.

Source	Function Customization Template	Function Name	Function Preview
fx Initialize	Model default	current_control_algorithm_initialize	void current_control_algorithm_initialize([]* self)
fx Periodic:D1 [Sample Time: 5e-05s]	Model default	current_control_algorithm_step	void current_control_algorithm_step([]* self, arg_enable, ...)
fx Terminate	Model default		void current_control_algorithm_terminate([]* self)

- 11 Use the Configure C Initialize Function Interface dialog box to configure the interface and arguments of the C function.



- 12 Click **Apply** and **OK** to complete configuring the C function.
- 13 Repeat steps 10 to 12 for all the listed functions.
- 14 In the Simulink toolstrip of the target model, select **C Code** > **Generate Code** > **Build** to build the model and generate a .c file for the target model for current controller.



This image shows an example of a C function available in the generated current controller code.

```

/* Model step function */
void current_control_algorithm_step(boolean_T arg_enable, boolean_T
  arg_enable_cl_host, uint32_T arg_Ia_ADC, uint32_T arg_Ib_ADC, uint16_T
  arg_QEP_Index, uint16_T arg_QEP_Count, real32_T arg_speed_ref, real32_T
  arg_idq_ref_pu[2], real32_T *arg_speed_meas_pu, real32_T arg_duty_cycles[3],
  boolean_T *arg_en_closed_loop, real32_T *arg_position_meas, real32_T
  arg_Iab_meas_PU[2])
{
  real32_T rtb_Add2_n;
  real32_T rtb_Frequency;
  real32_T rtb_PositionGain;
  real32_T rtb_algDD_o1_c;
  real32_T rtb_one_by_two;
  uint32_T rtb_PositionToCount;
  uint16_T rtb_Sum3;

  /* Outputs for IfAction SubSystem: '<S55>/PositionNoReset' incorporates:

```

Note

- The generated C function uses the interface that you configured in step 11.
 - For details about the per-unit system used in the algorithm, see “Per-Unit System” on page 6-16.
-

Repeat steps 1 to 14 for the target model for speed controller (`speed_control_algorithm.slx`) to generate the speed controller code.

Obtain C Code For Hardware Drivers

You can use the code generation software supported by the hardware manufacturer to generate the code for the hardware drivers. For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, you can use the STM32CubeMX STM32Cube initialization code generator software to configure the hardware peripherals and generate C code for the hardware drivers. The example also includes the `FOC_QEP.ioc` file (created by STM32CubeMX software) containing the hardware initialization data for the reference hardware.

Alternatively, you can also use a manually written driver code.

Integrate Control Algorithm Code With Driver Code

- 1 Integrate the code for the speed and current controllers.
- 2 Call the control algorithm functions from the driver code using the configured control algorithm function parameters. This image shows a call to the speed control algorithm C function.

```

// call the current control step function
current_control_algorithm_step(ENABLE_INV, ENABLE_CL_HOST, Ia, Ib, QEP_INDEX_COUNT, QEP_COUNT, SPEED_REF, (real32_T *)IDQ_REF,
    (real32_T *)&SPEED_MEAS_PU, duty_vals, (boolean_T *)&CL_ENABLE, &pos_meas, Iab_meas_pu);

uint16_t debug_1 = (uint16_t)(((Iab_meas_pu[0] + 1)/2) * 65535);
uint16_t debug_2 = (uint16_t)(((SPEED_MEAS_PU + 1)/2) * 65535);

// scale duty ratio to PWM counter period
for (int i = 0; i < 3; i++)
{
    duty_vals[i] = (1 - duty_vals[i]) * htim1.Init.Period;
}

// update duty cycles

```

- 3 Use the return value from the function call to complete integrating the driver with the controller algorithm.

For details about the code structure and program control flow used by the Motor Control Blockset examples, see “Program Control Flow of Motor Control Blockset Examples” on page 6-19.

View the integrated sample code `main.c` available in the `foc_qep\STM32Code` folder as a reference.

Deploy Integrated Code to Hardware

- 1 Complete the hardware connections.
- 2 Use the code generation and deployment software supported by the hardware manufacturer to compile, build, and generate a binary (for example `.HEX`) file from the integrated code. Use the software to flash the binary file to the target hardware.

For example, for the reference STM32F302R8 controller and X-NUCLEO-IHM07M1 inverter, use the STM32CubeMX STM32Cube initialization code generator to generate and flash the binary file.

Control Motor Using Host Simulink Model

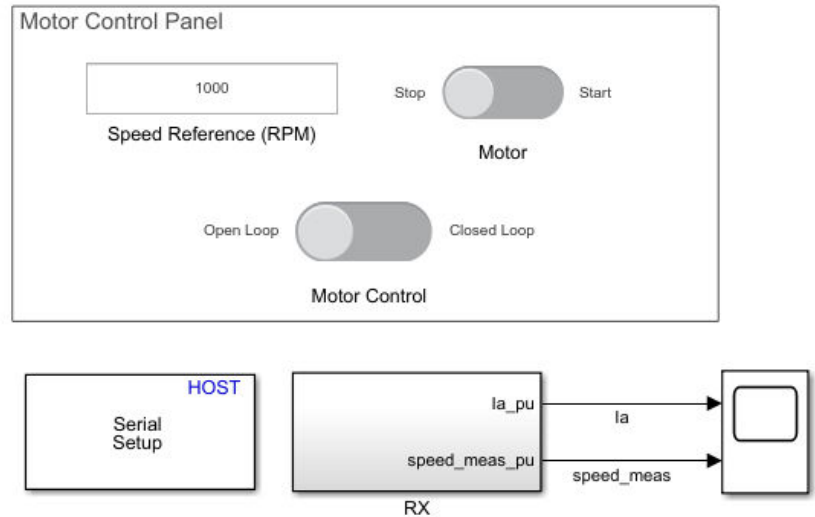
Follow these steps to determine the offset of the quadrature encoder sensor attached to a three-phase PMSM:

- 1 Click the **host model** hyperlink in the target model to open the associated host model. You can also double-click the `foc_qep_host.slx` file in the `foc_qep` folder.

FOC QEP Host Control

Steps:

1. Set the baud rate for serial communication in '**Host Serial Setup**' block.
2. Select the serial port in '**Serial 1**' tab of '**Host Serial Setup**' block.
3. Use '**Motor Start / Stop**' switch to control the start and stop of the motor.
4. Use the '**Motor Control Open Loop / Closed Loop**' switch to switch between open loop and closed loop control.
4. Enter speed request in RPM using 'Speed Reference' edit box. Limit the reference speed to half of the rated speed while starting the motor in open loop.
5. Observe the I_a and measured speed signals on the scope.



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- 2 In the **Serial 1** tab of the block parameters dialog box for the Host Serial Setup block, select a **Port name** and enter a **Baud rate** for serial communication.

For details about the serial communication between the host and target models, see “Host-Target Communication” on page 6-2.

- 3 Click **Run** on the **Simulation** tab to run the host model.
- 4 Ensure that the current position of **Motor Control** slider switch is **Open Loop**. Turn the **Motor Start / Stop** slider switch to the **Start** position to start running the motor using open-loop control.
- 5 Before entering closed-loop control, enter the reference speed for the motor in the **Speed Reference (RPM)** field. It is recommended that you set the speed to a value that is approximately half the rated speed of the motor.
- 6 Turn the **Motor Control** slider switch to the **Closed Loop** position to start running the motor using closed-loop field-oriented control.
- 7 Observe the I_a and speed signals in the time scope.

Modeling Guidelines for Motor Control Applications

Create and Validate Model for Motor Control System

Use Motor Control Blockset to design a Simulink model for a motor control system and validate it after deploying the model to the motor control hardware. This table lists the fundamental steps for creating and deploying a field-oriented control algorithm for a PMSM.

Note You can use a similar procedure to design and deploy a control algorithm for the other types of motors.

Modeling Steps	Learn More
Compute estimated motor parameters and create plant model	"Estimate PMSM Parameters Using Recommended Hardware" on page 4-188
	"Creating Plant Model Using Motor Control Blockset"
Create controller algorithm for motor control system	"Design Field-Oriented Control Algorithm"
	"Estimate Control Gains from Motor Parameters" on page 3-2
	"Code Verification and Profiling Using PIL Testing"
Deploy and validate motor control system	"Prepare Target Hardware"
	"Add Hardware Drivers to Simulation Model and Deploy to Target Hardware"
	"Validate System"

See these instructions to identify and debug common problems that can occur when you run the model on the target hardware.

Troubleshooting Steps	Learn More
Check for errors in measurements by analog to digital converter (ADC) peripheral in motor control applications	"Check ADC Inputs"
Verify pulse width modulation (PWM) signals	"Verify PWM Outputs"
Check for issues in hardware connections	"Check Hardware Connections"
Check for issues in algorithm used for model	"Test Algorithm Design"
Check for problems related to software architecture, code performance, and code execution time	"Check Generated Code"