

TMPM4L4

Motor Sample Software

Application Note

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Contents

1. Overview	6
1.1 Introduction	6
1.2 Overview of Specifications	6
1.3 Process Overview	8
2. System Block Diagram.....	10
3. Source File Configuration	11
4. Evaluation Environment.....	13
4.1 Evaluation Board Configuration	13
4.1.1 SBK-M4L4 Board Configuration	13
4.1.2 KES-P2 Board Configuration	13
4.1.3 KES-PH Board Configuration.....	13
4.1.4 Connection between the SBK-M4L4 and KES-P2 (KES-PH)	14
4.1.5 DAC Output Connection Configuration	15
4.1.6 Board Modification (KES-PH)	16
4.2 Development Tools	17
4.3 How to Start Up a Project	17
4.4 DAC Output	23
4.5 Port Output.....	24
4.5.1 Vector Control Software Processing Time	24
4.5.2 Current Detection State	24
4.5.3 Debug Output Function	24
4.6 Stage history.....	25
4.7 Overcurrent Detection	25
4.8 User Interface	25
5. Module Configuration	27
6. Microcontroller Hardware Assignment.....	28
6.1 IP.....	28
6.2 Interruption	30
7. General Flowchart.....	31
7.1 Main Routine (main).....	31
7.2 Main Loop (main_loop)	32
7.3 Interruption	33
7.3.1 VE Vector Processing (INT_VectorControl_byVE)	34
7.3.2 Software Vector Processing (INT_VectorControl_bySoft)	36
8. Status Transition.....	38
8.1 Sensor-less	38
8.2 Encoder.....	39
8.3 Encoder and Hall Sensor.....	40
9. User Application	41

9.1 User Control	41
9.1.1 Get AD Value (soft_adc_getdata)	42
9.1.2 Key Control (Uikeyscan)	42
9.1.3 User Setup (user_interface)	42
9.1.4 LED Display Control (led_display)	43
9.1.5 UART Transmitting Data Setup (send_data_set)	43
9.1.6 Temperature Measurement (temp_check)	43
9.1.7 Status Check Monitor	44
10. Functions	46
10.1 Control Commands	46
10.1.1 Control Method (usr.com_user)	46
10.1.2 Control Target Speed	46
10.1.3 Starting Current	46
10.2 Drive Command	47
10.2.1 Driving Method (drv.command)	47
10.2.2 Vector Control Command (drv.vector_cmd)	47
10.3 Driver Status	49
10.3.1 Error Status (drv.state)	49
10.4 Motor Control Structure	50
10.4.1 List of Variables	50
10.5 Function Details	60
10.5.1 Encoder Initial Setup (init_ENCen)	60
10.5.2 ADC Initial Setup (init_ADCen)	60
10.5.3 PMD Initial Setup (init_PMDen)	61
10.5.4 VE Initial Setting (init_VEen)	61
10.5.5 Shift2 Initial Setting (init_Shift2_CHx)	62
10.5.6 Comparator Initial Setting (init_COMPen)	63
10.5.7 Motor Control Initial Setup (B_Motor_Init)	63
10.5.8 DAC Control Initial Setup (init_Dac)	66
10.5.9 Cycle Timer Initial Setup (init_Timer_interval4kH)	67
10.5.10 User Control Initial Setup (init_user_control)	67
10.5.11 User Control (user_control)	68
10.5.12 User Motor Control (B_User_MotorControl)	69
10.6 Motor Control Function	70
10.6.1 Status Transfer Processing Function (C_Control_Ref_Model)	70
10.6.2 Motor Control Common Processing Function (C_Common)	72
10.6.3 Stop Stage Function (C_Stage_Stop)	73
10.6.4 Bootstrap Stage Function (C_Stage_Bootstrap)	74
10.6.5 Positioning Stage Function (C_Stage_Initposition)	75
10.6.6 Forced Commutation Stage Function (C_Stage_Force)	76

10.6.7 Forced Steady Changeover Stage Function (C_Stage_Change_up)	78
10.6.8 Steady Stage Function (C_Stage_Steady_A)	79
10.6.9 Protection Stage Function (C_Stage_Emergency)	81
10.6.10 Shift PWM Control (C_ShiftPWM_Control)	82
10.7 Motor Drive Function	83
10.7.1 Explanation of Terms.....	83
10.7.2 Acquisition of Motor Current, Power Supply Voltage (D_GetMotorCurrentPowerVolt)	84
10.7.3 Input Coordinate Conversion (D_InputTransformation).....	87
10.7.4 Clarke Transformation (E_Clarke).....	88
10.7.5 Park Transformation (E_Park).....	89
10.7.6 Induced voltage Position Estimation Function (D_Detect_Rotor_Position)	90
10.7.7 Flux Observer Position Estimation Function (D_Detect_Flux_Rotor_Position)	91
10.7.8 Encoder Control Function (H_Encoder)	93
10.7.9 Hall sensor and Encoder control function (H_HallCon H_Hall_Encoder).....	96
10.7.10 Speed Control Function (D_Control_Speed).....	97
10.7.11 Current Control Function (D_Control_Current)	99
10.7.12 Output Coordinate Conversion (D_OutputTransformation).....	101
10.7.13 Inverse Park Transformation (E_InvPark)	102
10.7.14 Sector Calculation (D_CalSector).....	103
10.7.15 Inverse Clarke Transformation (E_InvClarke).....	104
10.7.16 Spatial Vector Modulation (D_SVM)	105
10.7.17 Trigger Timing Calculation (D_CalTrgTiming).....	110
10.7.18 PWM Register Setup (PMD_RegDataSet)	114
10.7.19 Current Detection Error Detection Function (D_Check_DetectCurrentError)	115
10.7.20 3-shunt Current Mis-detection Detection Function (D_Check_DetectCurrentError_3shunt).....	117
10.7.21 1-shunt Current Mis-detection Function (D_Check_DetectCurrentError_1shunt)	118
10.7.22 Inverter Output Voltage Calculation Function (Cal_Vdq).....	121
11. Special Function Description	122
11.1 Flux Observer Based Position Detection Method	122
11.1.1 Function Specification	123
11.1.2 Data Strucure	129
11.1.3 Parameter	129
12. Explanation of Definitions for Constants	131
12.1 Motor Driver Setting Parameter Common (D_Para.h).....	131
12.1.1 Motor Control Channel Selection	131
12.1.2 Selecting a DAC Output	131
12.1.3 Fake Temperature Adjustment Selection	131
12.1.4 Selection of Unit for Command Speed.....	131

12.1.5 Selection of Special Control	131
12.1.6 Common Parameter List	131
12.2 Motor Driver Setting Parameter by Motor Channel (D_Para_Chx.h) x=0.....	132
12.2.1 Selection of Control	132
12.2.2 Parameter List per Motor Channel	133
12.2.3 Relationship of Constant Setups and Waveform.....	142
12.3 Constants for User Control	143
13. Timings for Control and Data Update	146
13.1 Vector Control Using Software.....	146
13.1.1 3-shunt Control.....	146
13.1.2 1-shunt Control.....	147
13.2 Vector Control by VE.....	149
13.2.1 3-shunt Control	149
13.2.2 1-shunt Control	150
14. Peripheral Driver.....	152
14.1 Microcontroller Peripheral Circuit Addresses.....	152
14.1.1 Data Structure.....	152
14.2 Vector Engine (VE)	152
14.2.1 Function Specification	152
14.2.2 Data Structure.....	174
14.3 Motor Control Circuit (PMD).....	175
14.3.1 Specifications of Functions	175
14.3.2 Data Structure.....	177
14.4 Analogue Digital Converter (ADC)	178
14.4.1 Specifications of Functions	178
14.4.2 Data Structure.....	179
15. Appendix	180
15.1 Fixed Decimal Point Processing.....	180
15.2 Normalization	180
15.3 Data Format.....	181
15.4 Computation with Fixed Decimal Point.....	183
15.5 Assert Function	184
16. Revision History	185
RESTRICTIONS ON PRODUCT USE	186

1. Overview

1.1 Introduction

The operation of this motor control sample software has been checked using the SBK-M4L4 (TMPM4L4FYAUG microcontroller evaluation board) by ESP, along with the KES-P2 and KES-PH (inverter board).

Please contact ESP (<http://esp.co.jp/>) for details on this evaluation board.

1.2 Overview of Specifications

- ◆ Microcontroller --- TMPM4L4FYAUG
- ◆ Clock --- 80MHz
- ◆ Evaluation motor --- KES-P2 : Tsukasa Electric Co., Ltd - TG611B
KES-PH : Mitsubishi Electric FA Industrial Products Corporation -
EM-AMF 0.1kW
- Development environment --- IAR Embedded Workbench V9.70
Keil µVision MDK V5.43
SEGGER Embedded Studio V8.24
- ◆ DC link voltage --- KES-P2 : 24 VDC
- ◆ Power Supply Voltage --- KES-PH : 100 VAC

- ◆ Control outline
 - Brushless DC Motor Vector Control (speed control)
 - Evaluation Purpose
 - DAC Output (variable analogue output)
 - Inverter Board Temperature Detection
 - UART Output (initial status checking using Tera Term, etc.)
 - LED Output (Monitor LED)

◆ Motor Control

Table 1.1 Motor Control

Item	Control
Motor Operation	Stop or start
Rotation Speed Control Method	Constant rotation speed control (switching)
Rotation Direction	CW/CCW (switch changeover)
PWM Modulation	Three-phase or two-phase modulation
Current Detection	3-shunt or 1-shunt
Position Detection	Sensor-less, encoder(Note1) , or Encoder and Hall (Note1)

Note1: Not evaluated

Note: Precautions

- When an EMG occurs, use "Reset" for releasing.
- When operating with 1-shunt, check the setups as follows:
- D_Para_CHx.h (Note1)
#define cSHUNT_TYPE_CHx (1) (Note1)
#define cBOOT_TYPE_CHx (cBoot_v) (Note1)

Note1: Choose a suitable number from "0" for "x" according to the channel of the motor used.

1.3 Process Overview

The vector control software consists of three layers: the application that takes care of the user interface processing, the motor controller that controls the motor operation status with the state transition and the motor driver that takes care of the motor drive processing by directly accessing the motor driver circuit.

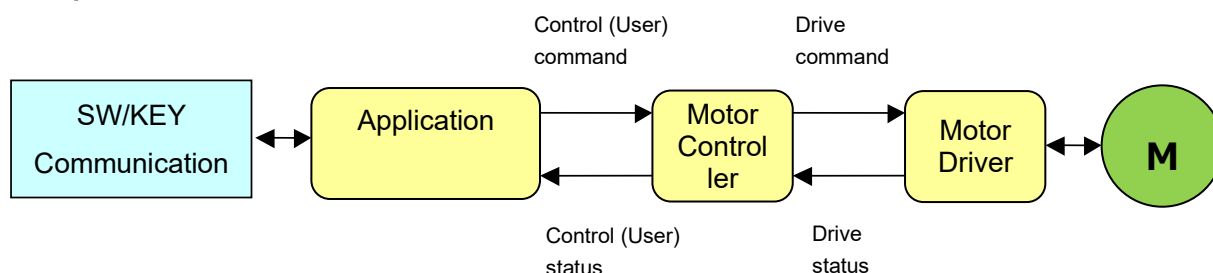


Figure 1.1 Vector Control Software Configuration

- i. The application will input the control commands that are set up through the switches, keys, communication, etc. and give it to the motor controller together with other control commands. Furthermore, it acquires the control status from the motor controller and as well as conducting the necessary processing, it outputs to the ports, etc.
- ii. The motor controller reads the control commands that are given from the application, converts it into the more specific drive commands according to the motor operating status, and gives it to the motor driver. Furthermore, it acquires the driver status from the motor driver and as well as conducting the necessary processing, transfers it to the application.
- iii. The motor driver reads the drive commands that are given from the motor controller and drives the motor. Furthermore, it monitors the motor operation and, as well as conducting the necessary processing according to the status, transfers the driver status to the motor controller.

For example, when a new control target speed is given from the application during the rotation of motor, it will be temporarily converted to the gradually varying driving target speed in the motor controller and be given to the motor driver because the motor driver cannot respond to an abrupt change in the target speed.

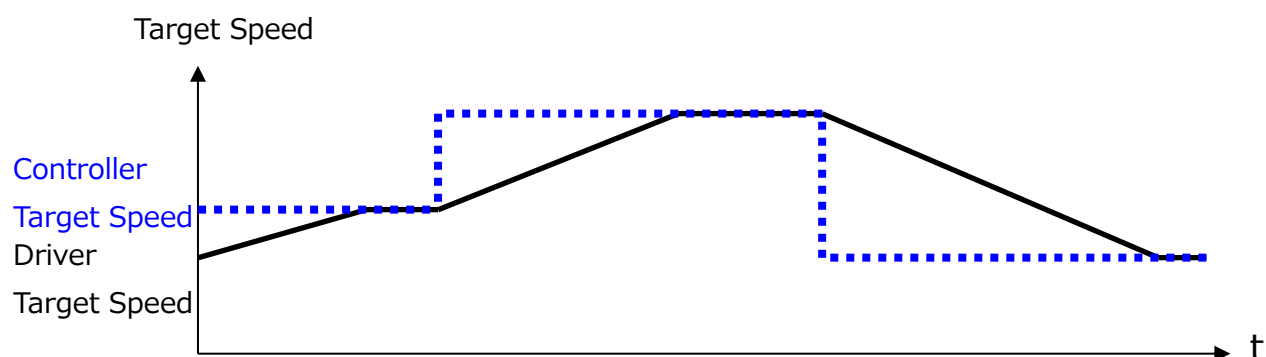


Figure 1.2 Controller Target Speed and Driver Target Speed

2. System Block Diagram

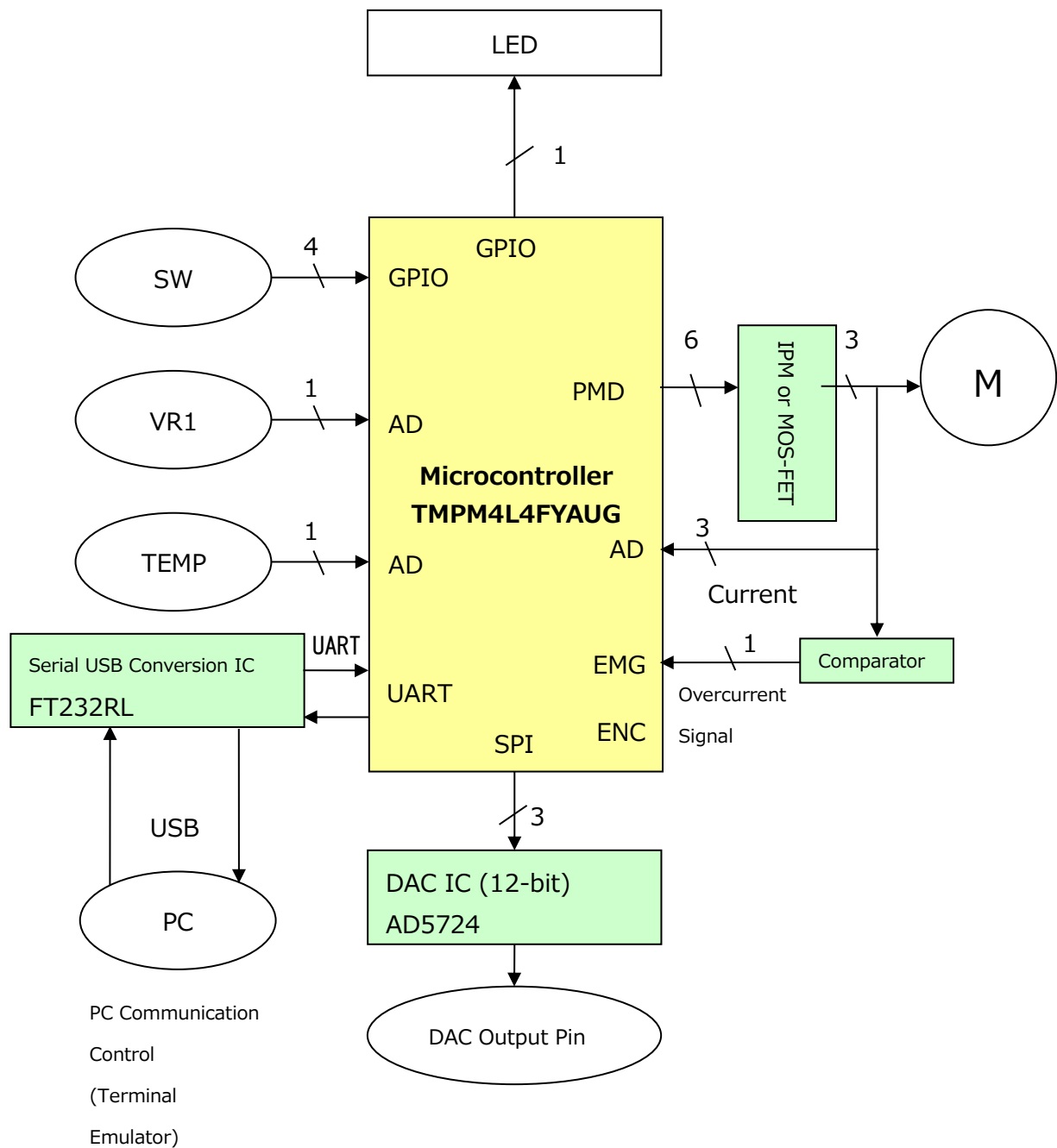


Figure 2.1 System Block Diagram

3. Source File Configuration

source

B_User.c	Vector Control User Setup Source File
B_User.h	Vector Control User Setup Header File
C_Control.c	Vector Control Control Source File
C_Control.h	Vector Control Control Header File
C_phi.lib	Flux Observer Control Library File (arm)
C_phi_i.a	Flux Observer Control Library File (IAR)
C_phi_s.a	Flux Observer Control Library File (SEGGER)
C_phi.h	Flux Observer Control Header File (Note1)
C_phi_KES-P2.h	Flux Observer Control Header File (Note1)
C_phi_KES-PH.h	Flux Observer Control Header File (Note1)
CheckVdq.c	dq-Axis Voltage Check Source File
CheckVdq.h	dq-Axis Voltage Check Header File
dac_drv.c	DAC IC Driver Source File
dac_drv.h	DAC IC Driver Header File
D_Driver.c	Vector Control Driver Source File
D_Driver.h	Vector Control Driver Header File
D_Para.h	Vector Control Parameter (common to channels) Header File
D_Para_ch0.h	Vector Control Parameter (Channel 0) Header File (Note2)
D_Para_ch0_KES-P2.h	Vector Control Parameter (Channel 0) Header File (Note2)
D_Para_ch0_KES-PH.h	Vector Control Parameter (Channel 0) Header File (Note2)
E_Sub.c	Computing Function Source File
E_Sub.h	Computing Function Header File
initial.c	Microcontroller Initial Setup Source File
initial.h	Microcontroller Initial Setup Header File
interrupt.c	Interruption Control Source File
interrupt.h	Interruption Control Header File
H_Hall.c	Vector Control for Hall Sensor Source File
H_Hall.h	Vector Control for Hall Sensor header File
ipdefine.h	Microcontroller Setup Header File
main.c	Main Routine
mcuip_drv.c	Microcontroller Hardware Setup Driver Source File
mcuip_drv.h	Microcontroller Hardware Setup Driver Header File
system_int.c	Interruption Function Source File
system_int.h	Interruption Function Header File
ipdrv.c	Microcontroller Hardware Reference Source File
ipdrv.h	Microcontroller Hardware Reference Header File
sys_macro.h	Macro Definition Header File
usercon.c	User Control Source File (Note3)
usercon_KES-P2.c	User Control Source File (Note3)
usercon_KES-PH.c	User Control Source File (Note3)
usercon.h	User Control Header File
Libraries	The libraries for CMSIS Core and individual IPs are stored.
└─M4L4	
└─CMSIS	CMSIS Core is stored.

```

| | system_TMPM4LxA.c          Microcontroller Initial Setup Source File
| | system_TMPM4LxA.h          Microcontroller Initial Setup Header File
| | TMPM4L4A.h                 Microcontroller Register Definition Header File
| | TMPM4LxA.h                 Microcontroller Register Definition Selection Header File
| └─ startup
|     └─ arm
|         | startup_TMPM4L4A.s      Start Up Assembler Source (arm)
|         | M4L4.scats             Linker File (arm)
|     └─ iar
|         | startup_TMPM4L4A.s      Start Up Assembler Source (IAR)
|         | TMPM4Lx.icf             Linker File (IAR)
|     └─ segger
|         | TMPM4L4A_Vectors.s      Start Up Assembler Source (SEGGER)
|         | SEGGER_THUMB_Startup.s  Start Up Assembler Source (SEGGER)
|         | TXZplus4E_M4L_Startup.s Start Up Assembler Source (SEGGER)
|         | TXZplus4E_M4L_Flash.icf Linker File (SEGGER)
|
└─ IP_Driver                    Peripheral Driver is stored.
    ipdrv_adc.c
    ipdrv_adc.h
    ipdrv_cg.c
    ipdrv_cg.h
    ipdrv_common.h
    ipdrv_enc.c
    ipdrv_enc.h
    ipdrv_siwdt.c
    ipdrv_siwdt.h
    ipdrv_t32a.c
    ipdrv_t32a.h
    ipdrv_tspi.c
    ipdrv_tspi.h

```

Note1: C_phi.h is initially set to the KES-P2 configuration. For use with KES-PH, rewrite it using the contents of C_phi_KES-PH.h.

Note2: D_Para_ch0.h is initially set to the KES P2 configuration. For use with KES PH, rewrite it using the contents of D_Para_ch0_KES PH.h.

Note3: usercon.c is initially set to the KES-P2 configuration. For use with KES-PH, rewrite it using the contents of usercon_KES-PH.c.

4. Evaluation Environment

4.1 Evaluation Board Configuration

This software was developed using the following evaluation boards.

4.1.1 SBK-M4L4 Board Configuration

Configure the jumpers to select the inverter board as the power supply source.

Table 4.1 SBK-M4L4 Board Configuration

Jumper Name	Terminal name (Silk marking)	function	open	short	Configuration for Evaluation
JP1	DAPEN	Uses onboard ICE (Short if using the on-board CMSIS-DAP)	Unused	use	short
JP2	DnBOOT	M366-BOOT mode setting (Normally, leave this open.)	Prohibited	permission	open
JP3	BOOT	M4KN-BOOT mode setting (Normally, leave this open.)	Prohibited	permission	open
JP4	LVSFT	Level shift circuit enabled (Short when using CMSIS-DAP)	Prohibited	permission	short
JP5 JP6 JP7	USB OBJT 5VIN	Microcomputer 5V power supply source selection Be sure to set JP5, JP6, and JP7 as shown in the table. (Only one jumper should be shorted.)	Power supply source JP5 JP6 JP7	USB2 (USB) short open open USB1 (DAP) open short open	Inverter Board open open short
JP8	(VDD-AVDD)	Digital/analog 5V power supply separation	separation	common	common
JP9	(GND-AGND)	Digital/analog GND separation	separation	common	common

4.1.2 KES-P2 Board Configuration

Set the jumpers to either the 1-shunt or 3-shunt configuration to match the software settings.

Table 4.2 KES-P2 Board Configuration

Position detection	JPR	3-shunt system(initial)	1 shunt system	
3/1 shunt switching	JPR1	open	short	Be sure to match the settings on the software side.
	JPR2	open	open	
	JPR3	open	open	
	JPR4	open	open	

4.1.3 KES-PH Board Configuration

The KES-PH is a dedicated 3-shunt board. No jumper settings are required.

4.1.4 Connection between the SBK-M4L4 and KES-P2 (KES-PH)

The SBK-M4L4 and the KES-P2 are connected using the supplied 26-pin flat cable. Between the SBK-M4L4 and the KES-PH, an approximately 8 kHz low-pass filter (LPF) is added to the motor current signals (ADU, ADV, ADW) and the reference voltage VDC, as shown in the figure below.

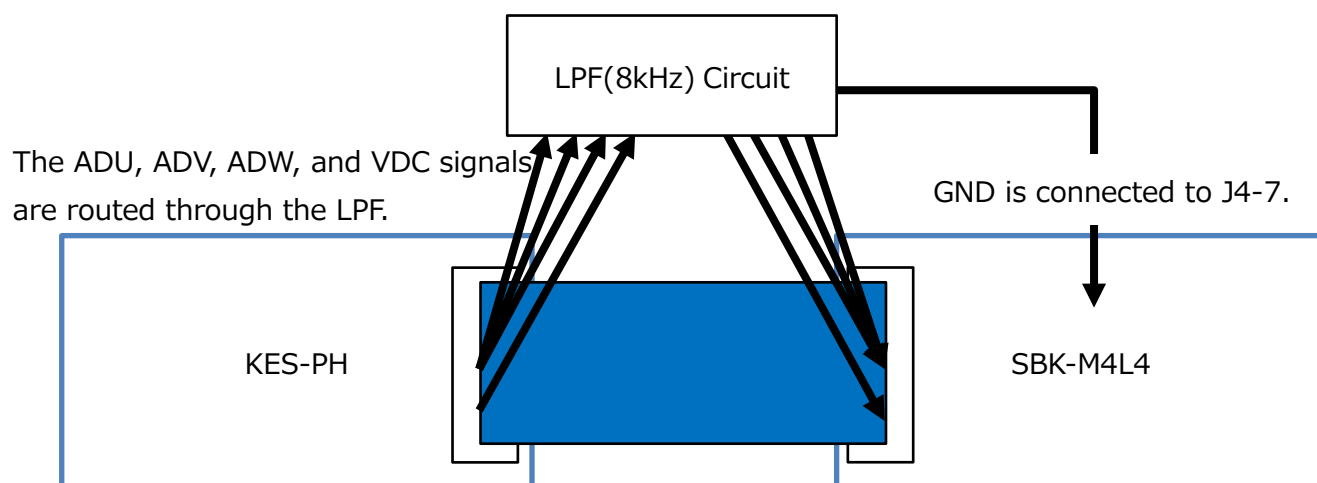


Figure 4.1 Addition of the LPF

4.1.5 DAC Output Connection Configuration

To use the DAC output function, it is necessary to connect the DAC board (KES-DAC12), which is supplied with the KES-P2, to the SBK-M4L4 board.

Connect them as shown in the table below.

Table 4.3 DAC Output Connection Configuration

DAC board KES-DAC12 J28			SBK-M4L4 board J4	
number	Signal Name		number	Signal Name
1	DVDD	→	5	VDD
2	GND	→	6	GND
			SBK-M4L4 board J7	
3	TSPI1RXD	→	5	TSPI1RXD/PC3
4	TSPI1TXD	→	4	TSPI1TXD/PC2
5	TSPI1CLK	→	6	TSPI1SCK/PC1

4.1.6 Board Modification (KES-PH)

Disable the DC-DC converter on the KES-PH. (Remove diode D7 between the power supply voltage and the DC-DC converter.)

Use regulated power supplies for the 5 V and 15 V rails.

The GND of the 15 V power supply is connected to the PGND side of R25, and the positive terminal is connected to the opposite side.

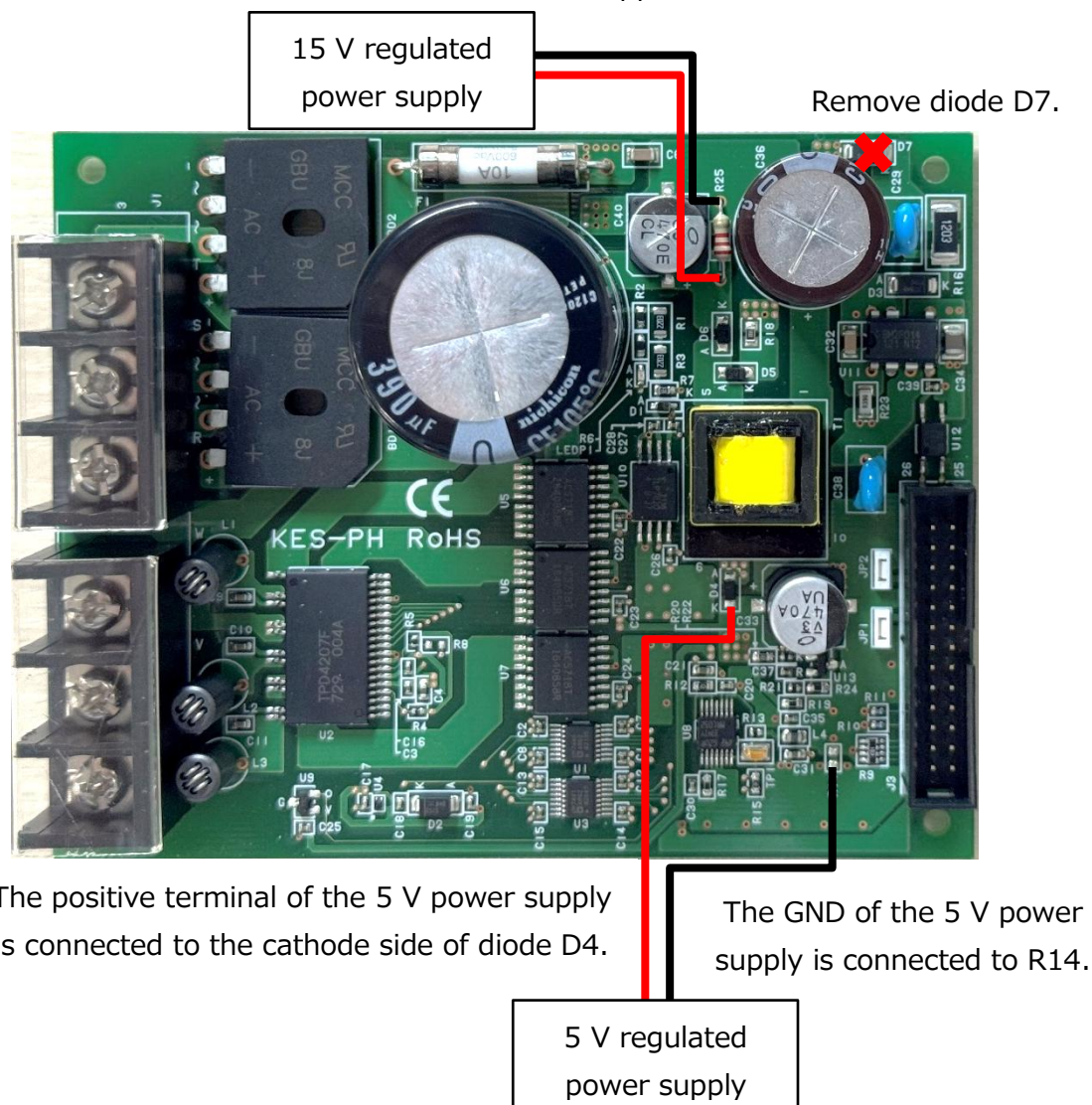


Figure 4.2 Board Modification (KES-PH)

4.2 Development Tools

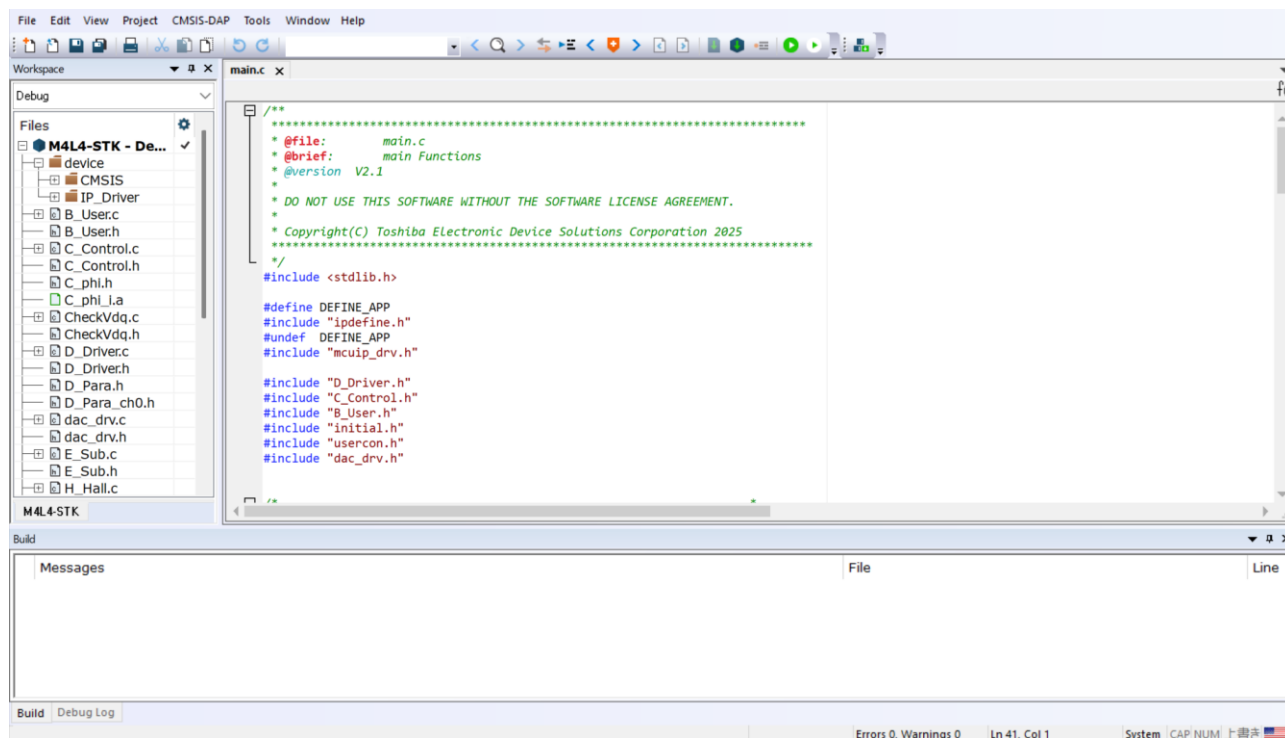
This software was developed using the following development tools:

IAR Embedded Workbench for ARM	9.70
Keil µVision MDK	5.43
Segger Embedded Studio	8.24

4.3 How to Start Up a Project

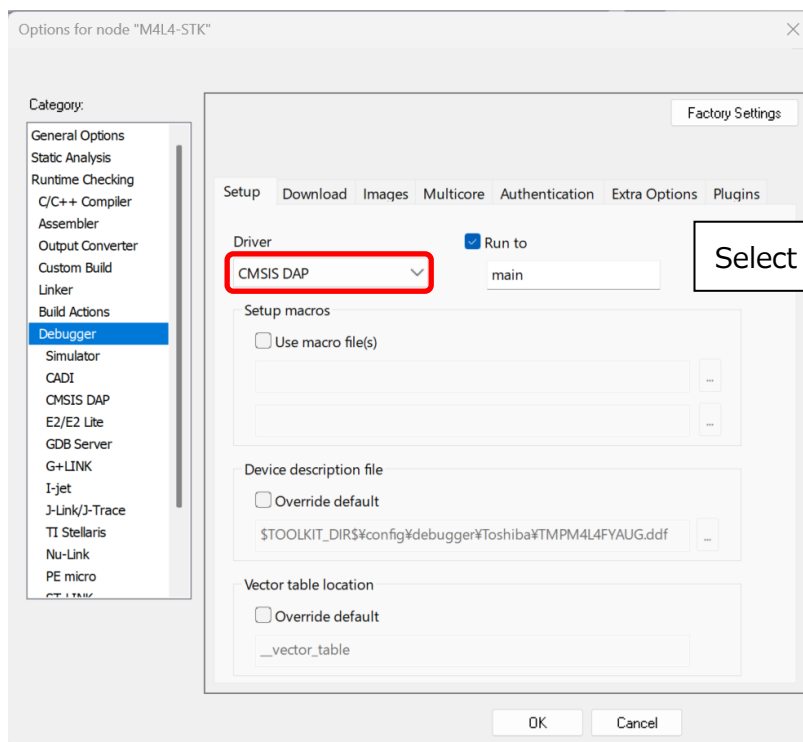
The procedure is explained using IAR Embedded Workbench as an example.

1. Double-click iar¥M4L4-STK.eww, or select [File] > [Open] > [Workspace], then open M4L4-STK.eww.
2. The following window appears.



- Open the Option window to select a tool to use.

[Project] > [Option] > [Debugger], then the <Setup> tab page



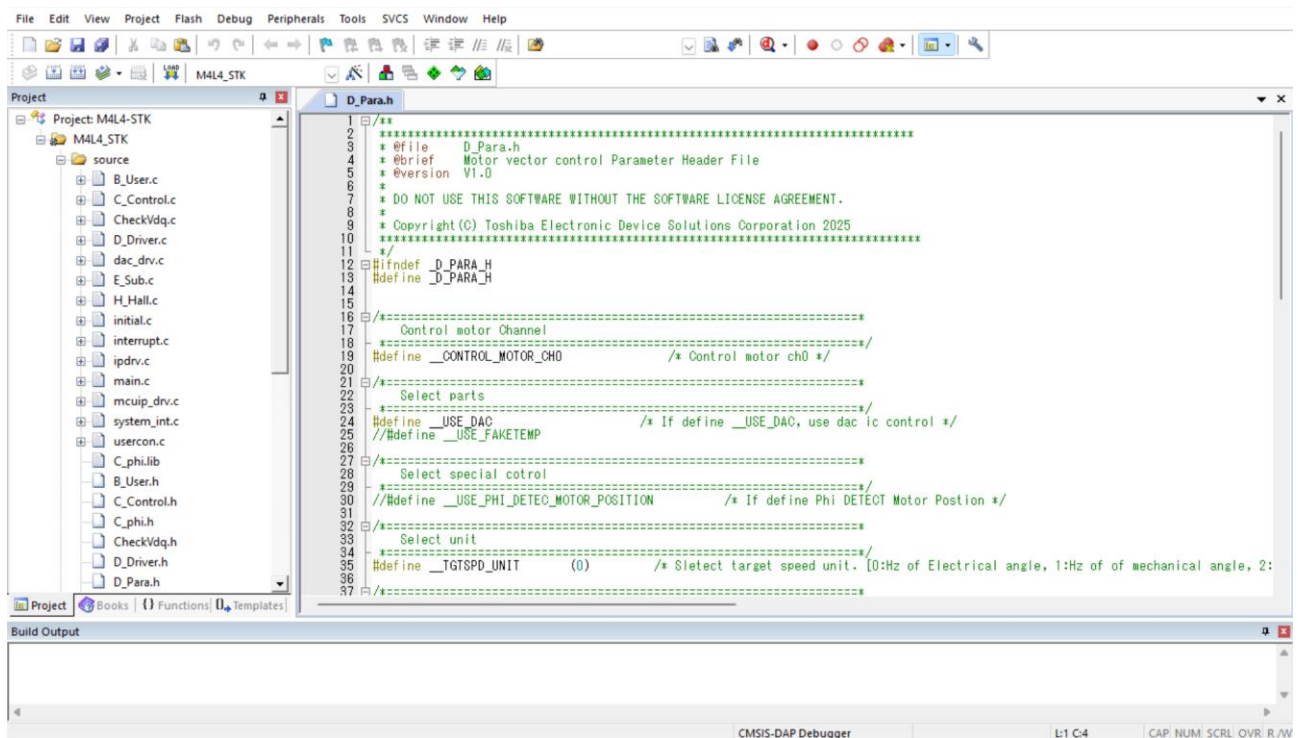
Select a tool to use.

- To start debugging, connect the tool and select [Project] > [Download and Debug], or press the following button.



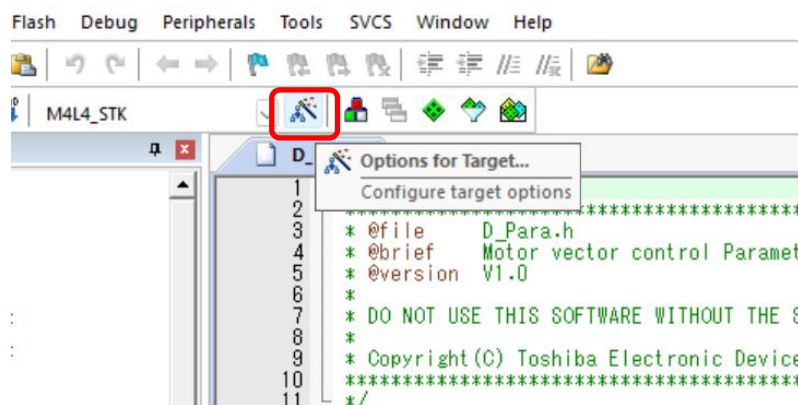
The following explains the case of Take Keil μ Vision MDK.

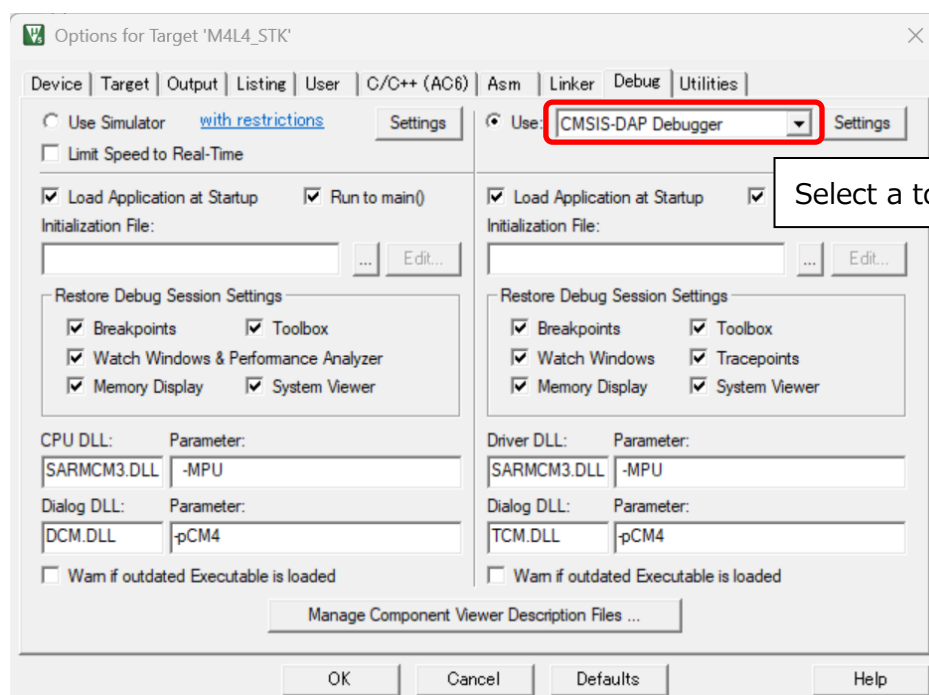
1. Double-click M4L4_STK.uvprojx, or select [File] > [Open], then open M4L4_STK.uvprojx.
2. The following window appears.



3. Open the Options for Target window and select a tool to use.

[Options for Target] > [Debug], then the <Use> field



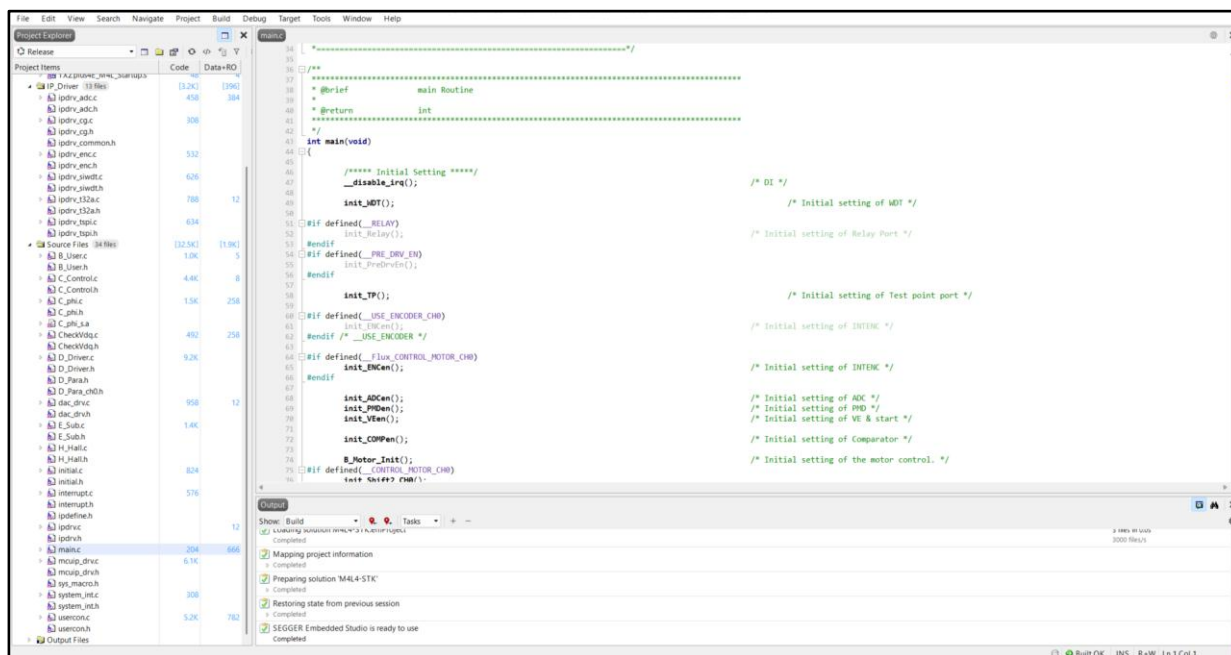


- To start debugging, connect the tool and select [Debug] > [Start/Stop Debug Session], or press the following button.



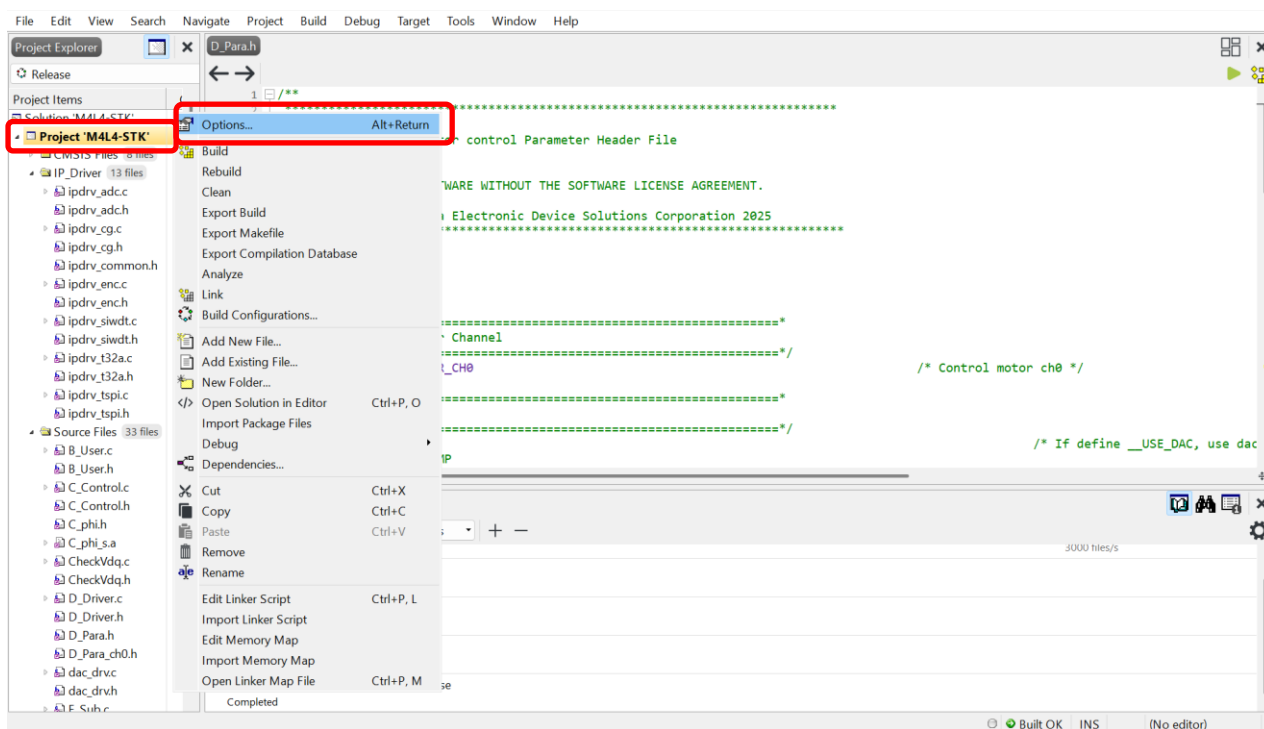
The following explains the case of the Segger Embedded Studio.

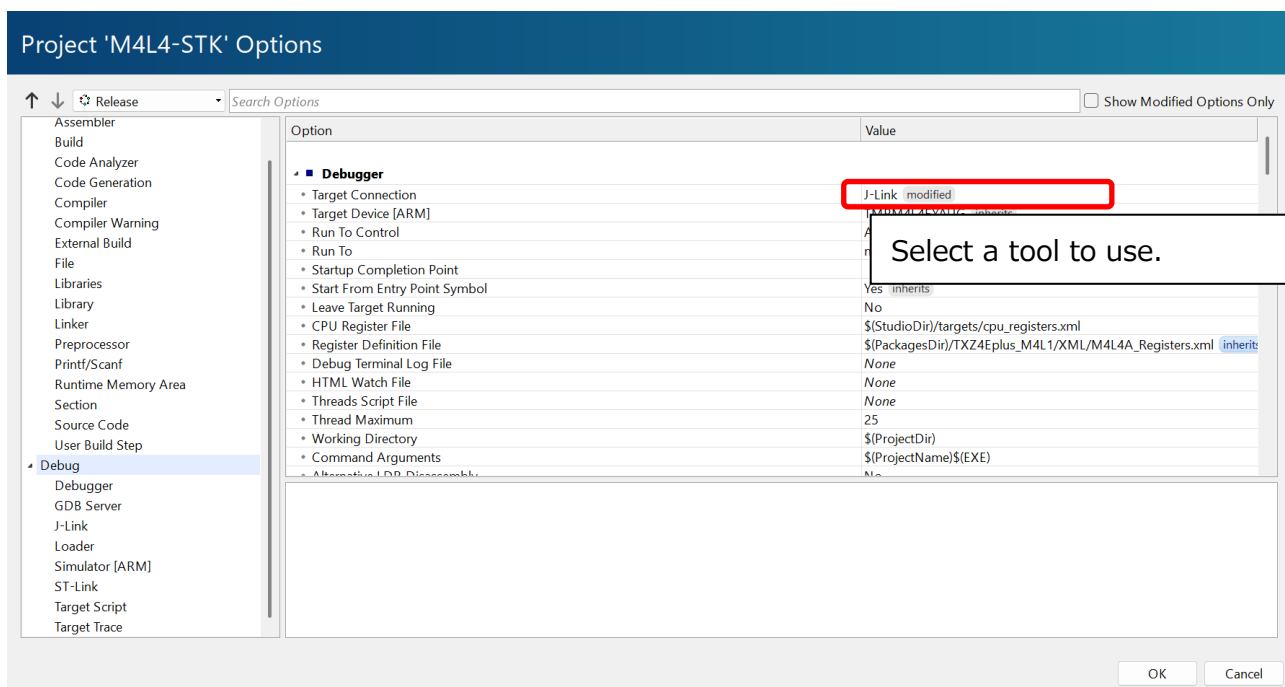
1. Double-click M4L4_STK.emProject, or select [File] > [Open], then open M4L4_STK.emProject.
2. The following window appears.



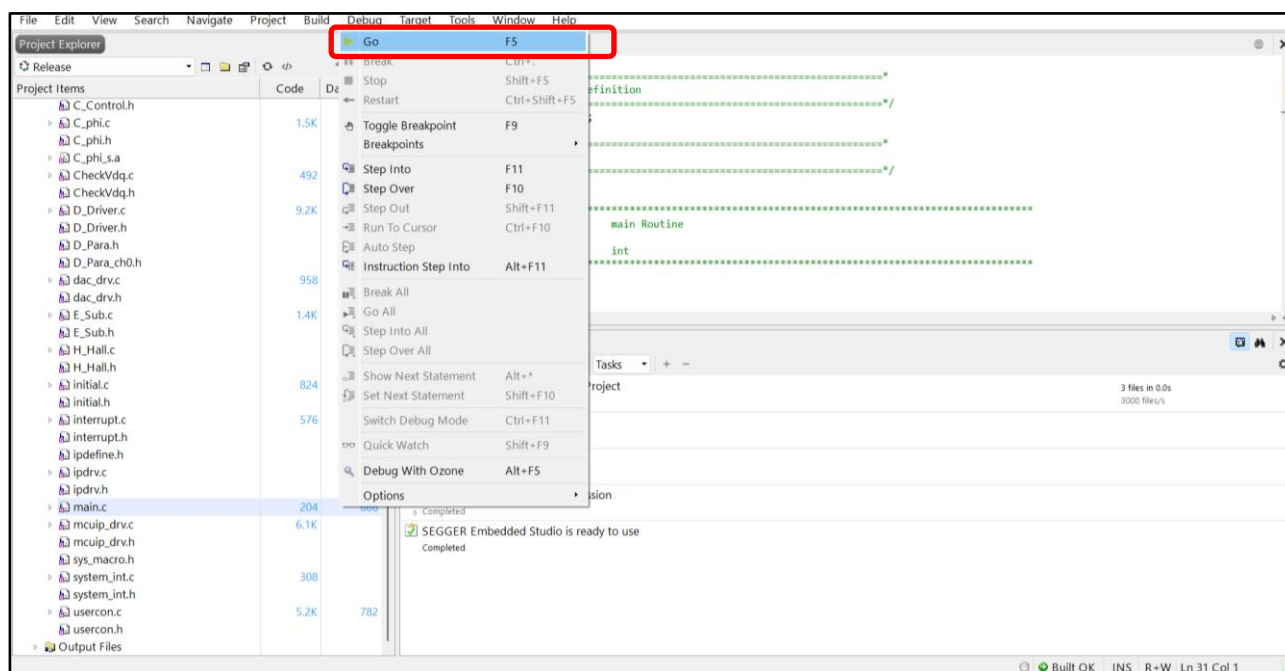
3. Open Options and select a tool to use.

Right-click on the project name > [Options] > [Debugger], then <Target Connection>.





4. To start debugging, connect the tool and select [Debug] > [Go].



4.4 DAC Output

Equipped with the DAC output function for viewing the fluctuation of variables with the Oscilloscope.

For enabling the DAC output, enable the following definitions for D_Para.h

```
#define __USE_DAC
```

The variables for executing the DAC output are listed in the function UiOutDataStart() in the file usercon.c.

Add a variable as necessary if the function does not have any variable for checking.

<<DAC Output Setup Variables>>

dac.select	Select DAC Output.
dac.motch	Set up a Motor CH for DAC Output
dac.datsft0 – 3	Set the amount of data shifting. Formula (x): data x (2^x)

4.5 Port Output

It is possible to output various timings on the port.

The initial setting of the port to be output is as follows, so change it as necessary.

4.5.1 Vector Control Software Processing Time

It is possible to output the software processing time of vector control.

To enable this function, please enable the following definition in ipdefine.h file.

```
#define    __MOTOR_DBGOUT_VECTOR_TIME_INT
```

Table 4.1 Output port

Motor Channel	Output port
CH0	PA bit5

H: Under calculation

4.5.2 Current Detection State

It is possible to output the current detection state.

To enable this function, please enable the following definition in ipdefine.h file.

```
#define    __MOTOR_DBGOUT_IDET
```

Table 4.2 Output port

Motor Channel	Output Port
CH0	PA bit6

L: Normal detection state, H: False detection state

4.5.3 Debug Output Function

PMD Debug Output Function is possible to output the signal (From PMD, ADC, VE).

Enable the following definition in the file "ipdefine.h" to enable this function.

```
#define    __MOTOR_PMDDBG
```

Table 4.3 Output port

Motor Channel	Output Port
CH0	PC bit4

Modify the DBGOUTCR register settings in the IP_PMD_init() function of the file "mcuip_drv.c". By default, the output signal is set to the AD conversion timing monitor signal.

For detailed information, refer to the section "PMD Debug Output Function" in the datasheet.

4.6 Stage history

By leaving the history of the main stage, it is possible to check from which state an abnormal condition has come.

The history of the stage is stored in the following variables.

stage_his[]

To enable this function, please enable the following definition in ipdefine.h.

```
#define __MOTOR_DEBUG
```

4.7 Overcurrent Detection

In shift PWM2 mode, overcurrent detection is not performed because Vd/Vq output limitation is applied. When determining the Vd/Vq output limit values, performing overcurrent detection is possible.

Activate the following definition in the file "ipdefine.h" to enable this feature.

```
#define __MOTOR_OVC_CHECK_SHIFT2
```

4.8 User Interface

The following functions are provided as the user interface:

<<User Interface>>

1. Rotation Direction Switching

By switching SW(S_SW1) while the motor is stopped,
Switching the motor's rotation is enabled.

Off: CW on: CCW

2. Speed Adjustment/Simulated Temperature Adjustment

By switching SW(S_SW3) while the motor is stopped,
Switching VR1 operation

Between motor speed adjustment and pseudo temperature adjustment is enabled.

Off: motor speed adjustment on: pseudo temperature adjustment

3. DAC display update

By pressing SW(U_SW1),
displaying the latest DAC status is enabled.

4. DAC No. changeover

The DAC No. are changed over according to the table below by pressing the SW (USW2).

Table 4.4 DAC Display

No.	DAC Display
1	A: Ia B: Ib C: Ic D: theta.half[1]
2	A: Id_ref B: Id C: Iq_ref D: Iq
3	A: omega_com.half[1] B: omega.half[1] C: omega_ref D: Iq_ref
4	A: Ia B: Iq_ref C: Id_ref D: omega.half[1]

5. Variable resistor

By operating VR1,

Motor Rotational speed adjustment/Pseudo temperature is enabled.

For using pseudo temperature, enable following D_Para.h define.

```
#define __USE__FAKETEMP
```

Pseudo temperature: -20°C to 100°C

Rotational speed adjustment: 0, cHz_MIN to 200Hz

Fake Temperature Adjustment is performed by operating VR1.

To use Fake Temperature Adjustment, enable the following definition in D_Para.h.

```
#define __USE__FAKETEMP
```

6. “LED Display”

The motor error status is checked by the LED.

For hardware EMG in the STOP stage, the LED is not lit.

When Motor CH0 is driving (LED4)

1. Error Status LED

No EMG: Lights OFF

EMG exists: Lights ON

The EMG status is canceled by the rest button.

7. Status display through UART connection

The settings, motor rotation speed, and EMG status are displayed on the PC.

The initial status can be checked once after releasing the reset.

For details, refer to [9.1.7 Status Check Monitor](#).

5. Module Configuration

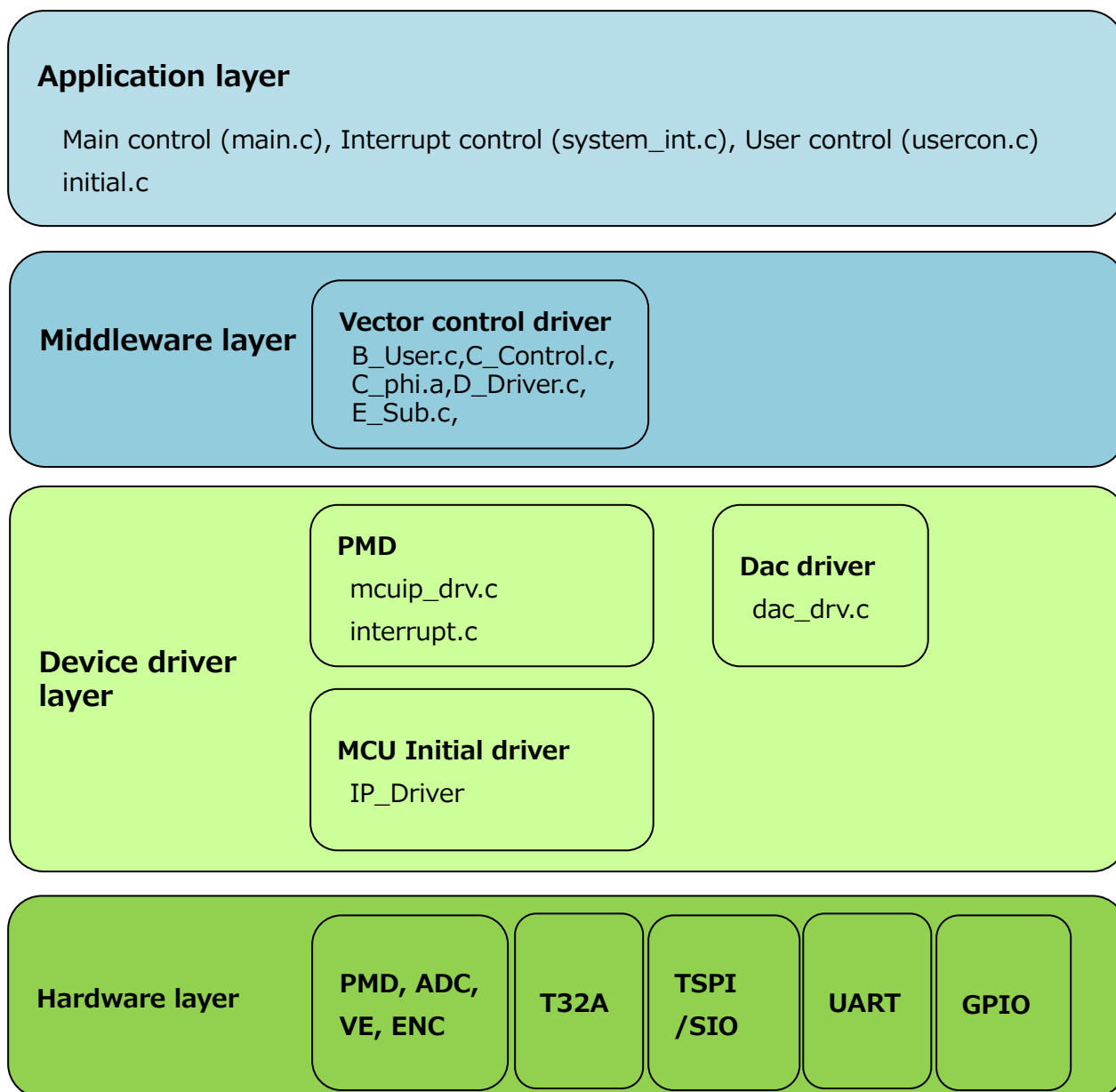


Figure 5.1 Module Configuration

6. Microcontroller Hardware Assignment

6.1 IP

Table 6.1 IP

IP		Control	Remarks
T32A	channel 0	4 kHz Interruption	Timer A
	channel 1	Not Used	
	channel 2	Not Used	
	channel 3	Not Used	
	channel 4	Not Used	
	channel 5	Not Used	
TSPI	channel 0	Not Used	
	channel 1	DAC IC Control	SIO Mode
	channel 2	Not Used	
UART	channel 0	PC Connection	
	channel 1	Not Used	
	channel 2	Not Used	
	channel 3	Not Used	
	channel 4	Not Used	
	channel 5	Not Used	
ADC	Unit A	Motor CH0 Acquisition of Coil Current, Power Supply Voltage VR1, TEMP0 Voltage Value Acquisition	
	Unit B	Not Used	
A-PMD2	channel 0	Motor CH0 Control	
A-VE2	channel 0	Motor CH0 Control	
A-ENC2	channel 0	Motor CH0 Encoder Signal Control	
COMP	channel 0	U-phase motor current (positive) reference voltage input	
	channel 1	U-phase motor current (negative) reference voltage input	
	channel 2	V-phase motor current (positive) reference voltage input	
	channel 3	V-phase motor current (negative) reference voltage input	

	channel 4	W-phase motor current (positive) reference voltage input	
	channel 5	W-phase motor current (negative) reference voltage input	
DAC	channel 0	Motor current (positive) reference voltage output	
	channel 1	Motor current (negative) reference voltage output	

6.2 Interruption

Table 6.2 Interruption

Cause	Process	Priority	Function
INTT32A00AC_IRQn	4 kHz Interval Timing Generation	5	INTT32A00AC_IRQHandler
INTVCN0_IRQn	Vector Control Software Processing for CH0 (For vector control using VE)	3	INTVCN0_IRQHandler
INTADAPDA_IRQn	Vector Control Software Processing for CH0 (For Vector Control Using Software)	3	INTADAPDA_IRQHandler
INTUART0TX_IRQn	UART Transmission Complete Interruption Processing	6	INTUART0TX_IRQHandler
INTT1TX_IRQn	DAC IC Control	6	INTT1TX_IRQHandler

The priority of interruption may be changed using the following constants for ipdefine.h.

```

/* High    Low */
/*  0 ---- 7 */

INT4KH_LEVEL      5      /* 4kH interval timer interrupt */
INT_VC_LEVEL      3      /* VE interrupt */
INT_ADCA_LEVEL     3      /* ADC A interrupt */
INT_DAC_LEVEL     6      /* SIO interrupt for Dac */
INT_UART_LEVEL    6      /* SIO interrupt for UART */

```

7. General Flowchart

7.1 Main Routine (main)

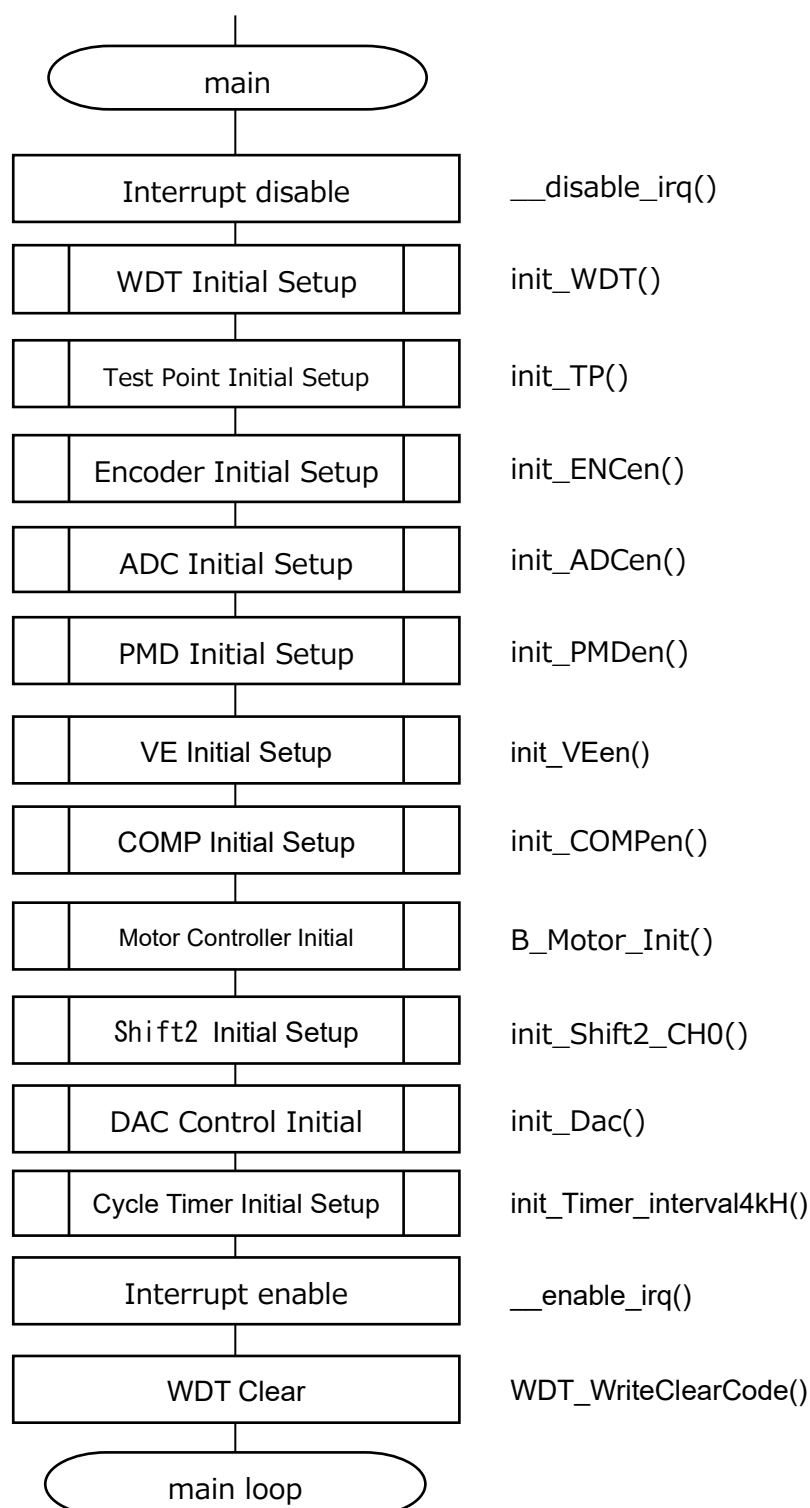


Figure 7.1 Main Routine (main)

7.2 Main Loop (main_loop)

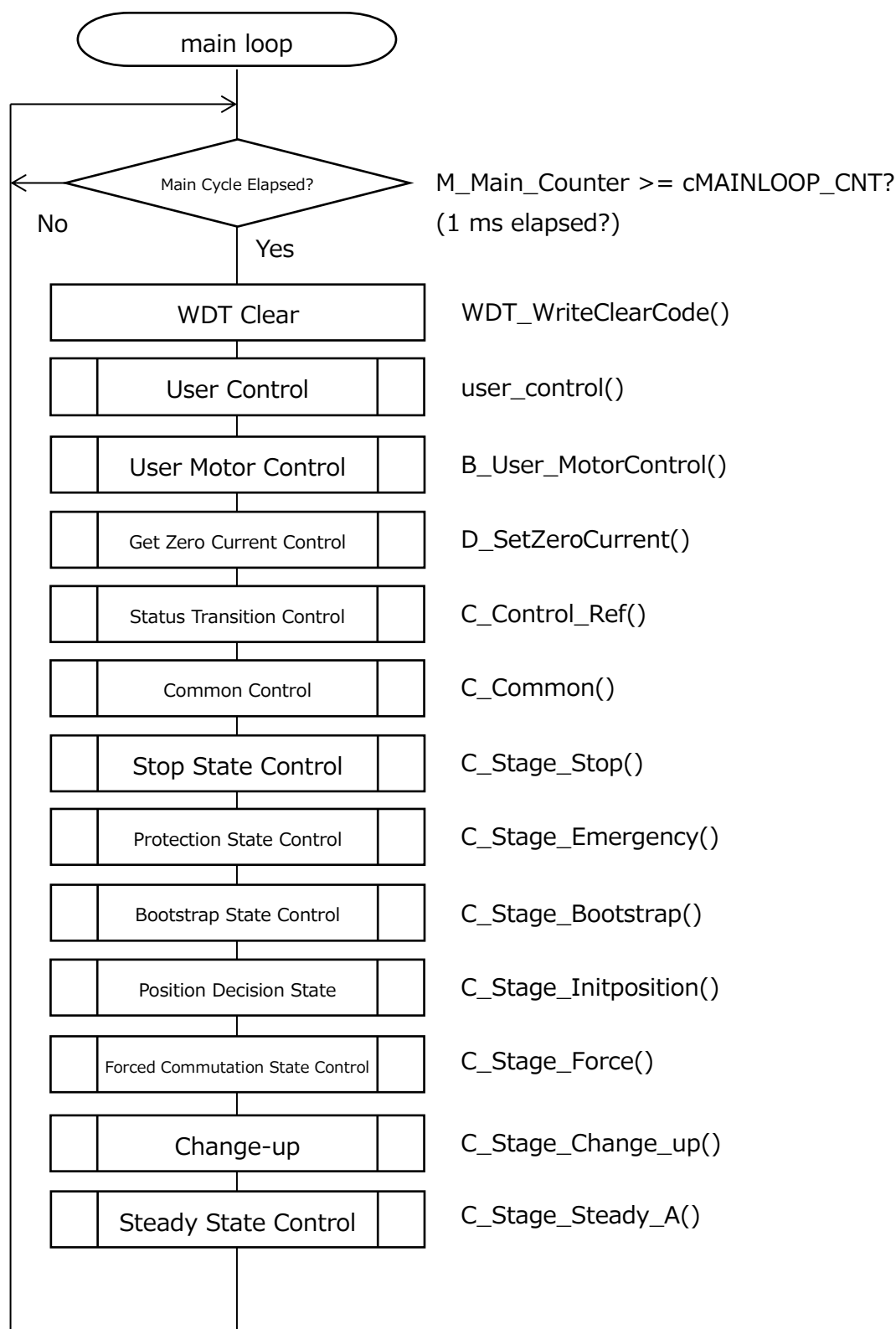
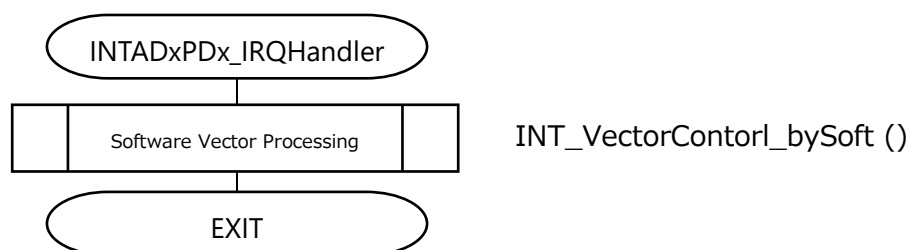


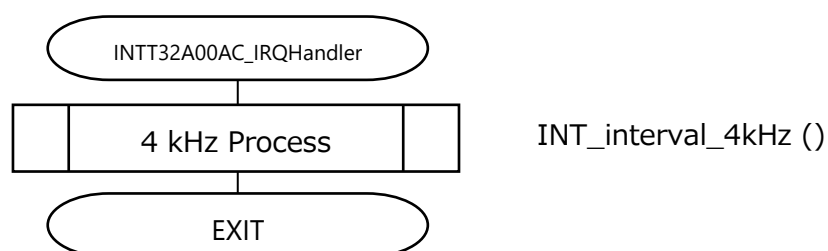
Figure 7.2 Main Loop (main_loop)

7.3 Interruption

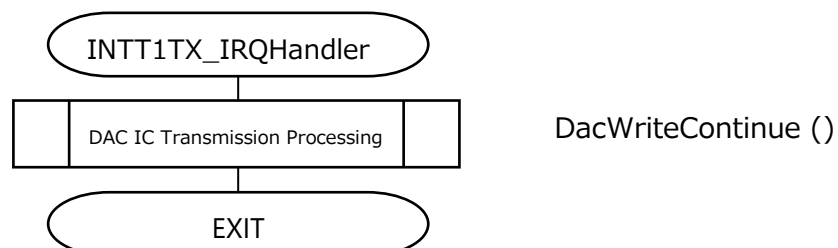
AD Conversion Complete Interrupt (x = A,B)



Every 4 kHz cycle



DAC Communication 24-bit Transmission Complete



UART 8-bit Transmission Complete

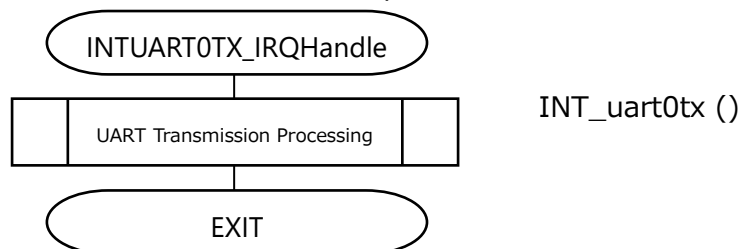


Figure 7.3 Interruption

7.3.1 VE Vector Processing (INT_VectorControl_byVE)

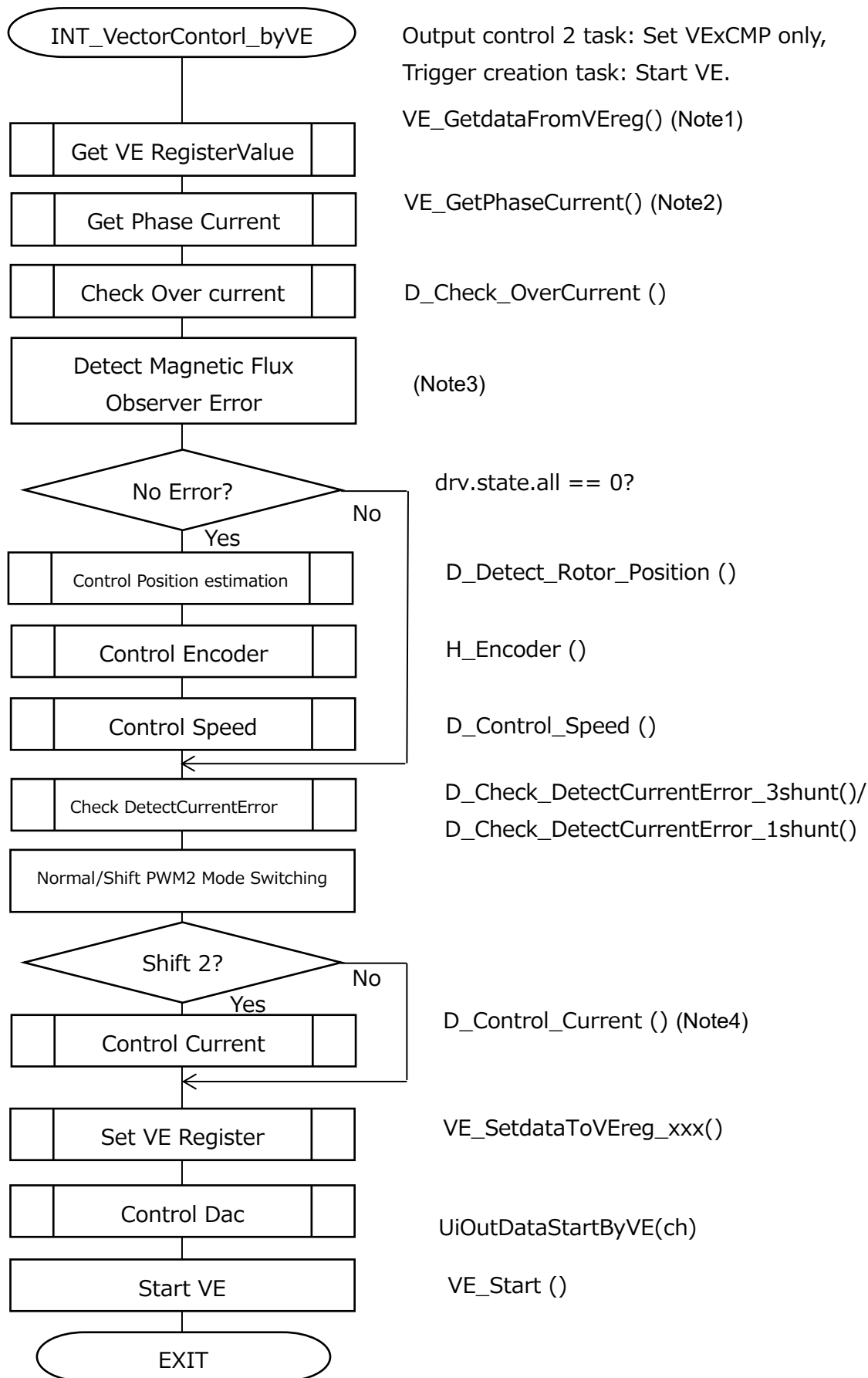


Figure 7.4 VE Vector Processing (INT_VectorControl_byVE)

Note1: When using the magnetic flux observer method, get V_α/V_β by VE register.

Note2: When using the magnetic flux observer method, get I_α/I_β by VE register.

Note3: When using the magnetic flux observer method.

Note4: No processing during switching Shift 2 $\leftrightarrow$ Normal

7.3.2 Software Vector Processing (INT_VectorControl_bySoft)

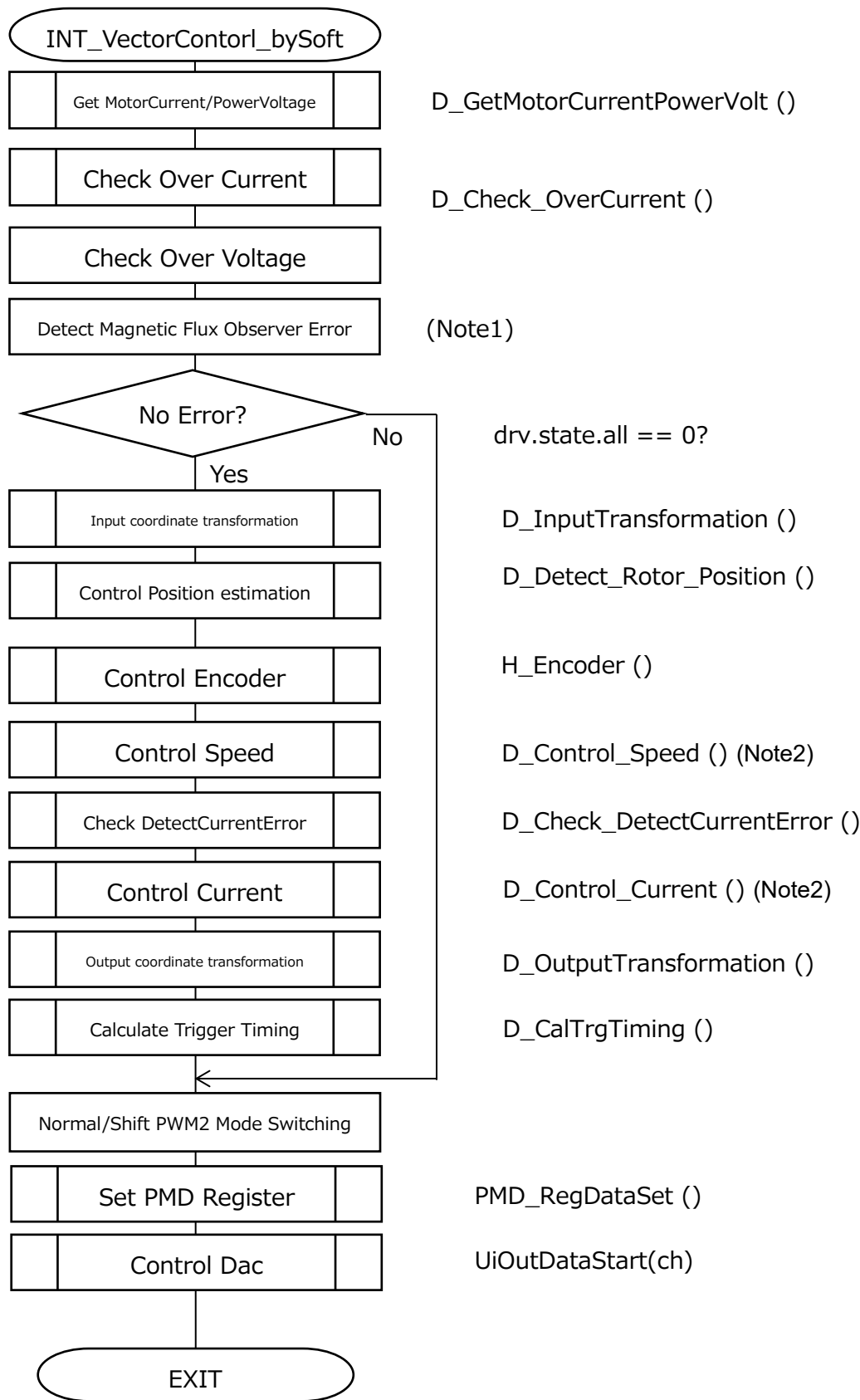


Figure 7.5 Software Vector Processing (INT_VectorControl_bySoft)

Note1: When using the magnetic flux observer method.

Note2: No processing during switching Shift 2 $\leftrightarrow$ Normal

8. Status Transition

8.1 Sensor-less

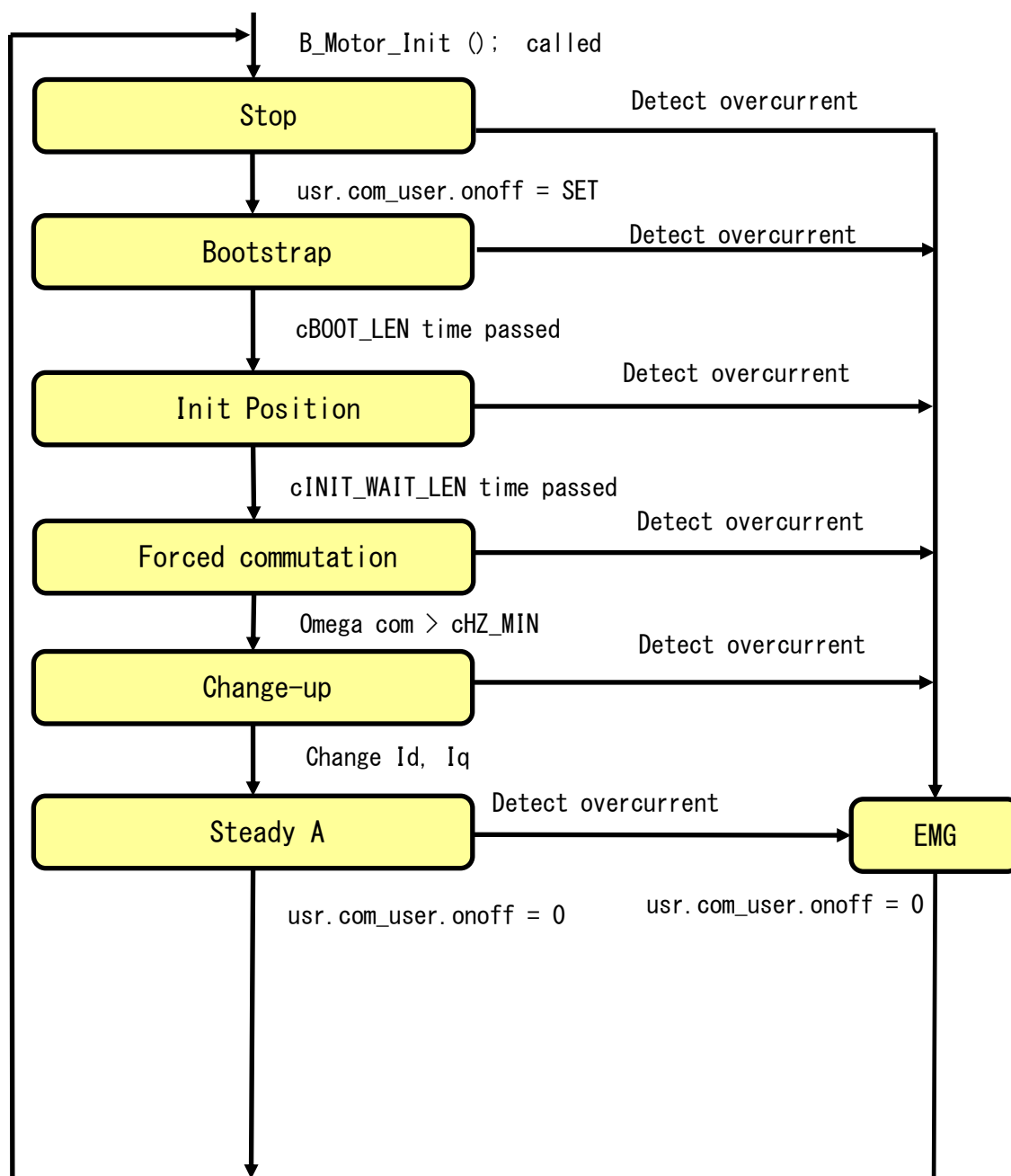


Figure 8.1 Sensor-less

8.2 Encoder

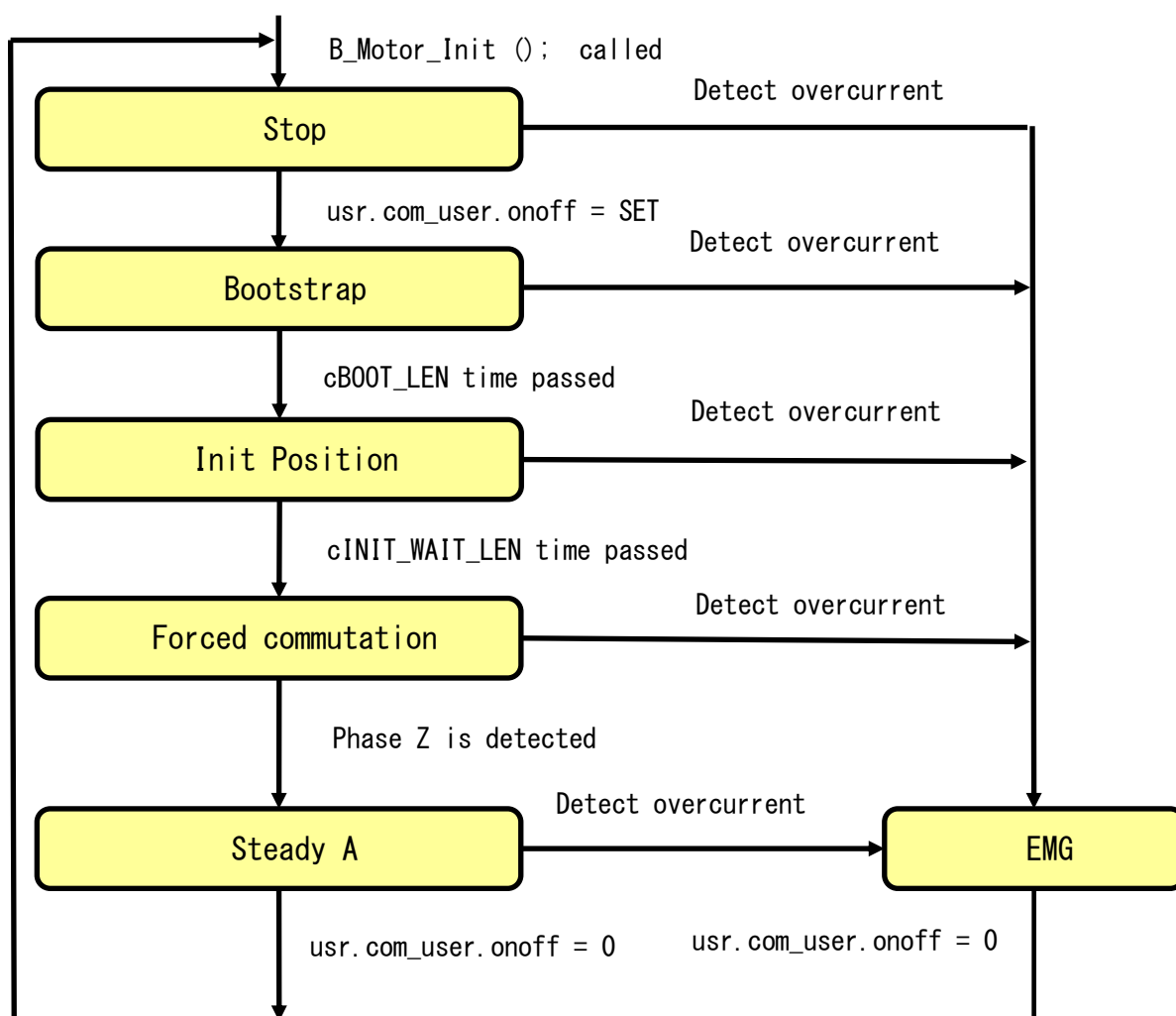


Figure 8.2 Encoder

8.3 Encoder and Hall Sensor

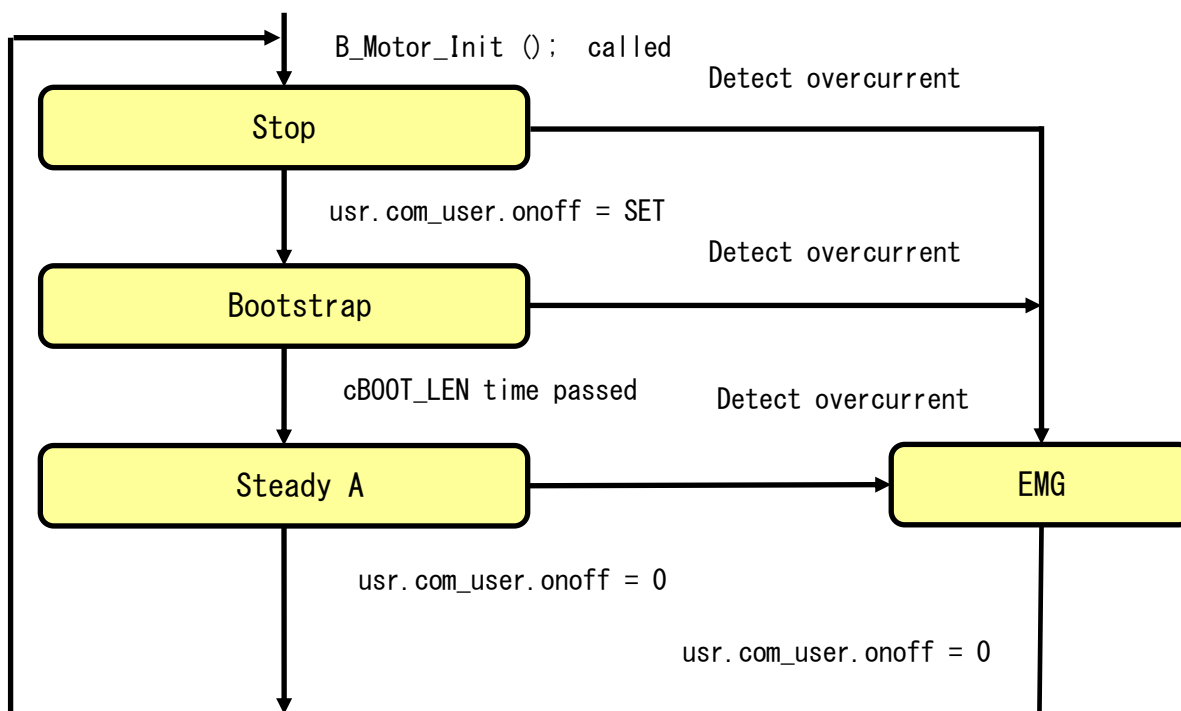


Figure 8.3 Encoder and Hall Sensor

9. User Application

9.1 User Control

Each of user application is processed once every lapse of main cycle (1 ms).

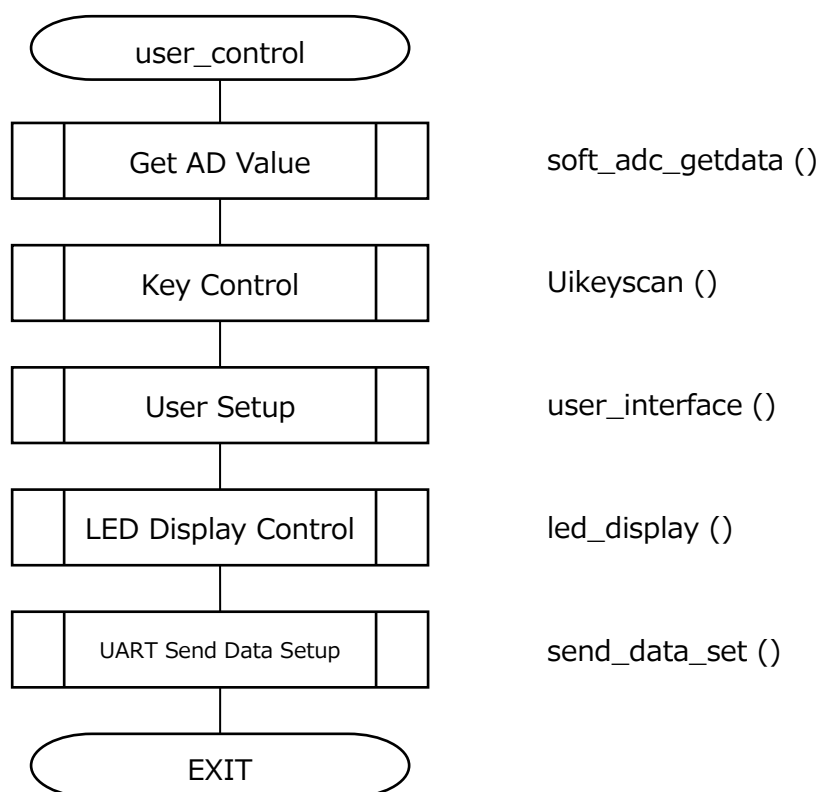


Figure 9.1 User Control

9.1.1 Get AD Value (soft_adc_getdata)

Get AD values (12 bits) of Fake Temperature (VR1) and Motor ch0Inverter Temperature with the individual conversion setup.

After values are obtained 10 times, for values obtained 8 times excluding the max and min values, the average value for each temperature will be calculated and stored in `ad_temp0.avedat`, `ad_temp1.avedat` as the effective value under the following conditions:

- When pseudo temperature(`__USE_FAKETEMP`) is enabled and `S_SW3` is ON,
The value of VR1 is stored in `ad_vr.avedat`.
- When pseudo temperature(`__USE_FAKETEMP`) is disable,
The inverter temperature of motor ch0 is stored in `ad_temp0.avedat`.
- When `S_SW3` is OFF,
The value of VR1 is stored in `ad_vr.avedat`.

9.1.2 Key Control (Uikeyscan)

Process the key scan for `S_SW1`, `S_SW2`, `S_SW3`, `S_SW4`, `USW1`, `USW2`, and `USW3`.

Each set of the key data will be finalized when an identical value is continuously acquired 20 times, and for `S_SW1`, `S_SW2`, `S_SW3`, and `S_SW4`, data will be stored in `sswdata`, and for `USW1`, `USW2`, and `USW3` data is stored in `uswdata`.

9.1.3 User Setup (user_interface)

Set up the following according to the SW input by the user operation.

1. Rotation Direction Switching

The process is executed when the motor is stopped. (When the motor's main stage is in the stop state.)

According to the value of `sswdata.bit.sw1`, `rota_dir` is switched.

When `sswdata.bit.sw1` is 1, on: CCW

When `sswdata.bit.sw1` is 0, off: CW

2. Rotational speed adjustment/Pseudo temperature Switching

Switch when the motor is stopped. (When the motor's main stage is in the stop state.)

According to the value of `sswdata.bit.sw3`, `spd_temp_chg` is switched.

When `sswdata.bit.sw3` is 1, on: Pseudo temperature

When `sswdata.bit.sw3` is 0, off: Rotational speed adjustment

Note: During switching pseudo temperature→Rotational speed adjustment, the motor remains stopped until VR1 is lowered to its minimum position.

3. DAC Display Update

Whenever `uswdata.bit.sw1` is 1, the latest DAC display is updated.

4. DAC No Switching

Whenever uswdata.bit.sw2 is 1, the dac.select is updated.

5. Motor Speed Control

When performing rotational speed adjustment, ad_vr.avedat is converted to 8bit, the value is as below.

Less than 0x10: 0Hz

More than 0xF0: 200Hz(Maximum Speed)

0x10 to 0xEF: 40Hz to 199Hz

9.1.4 LED Display Control (led_display)

Control LED4 according to the EMG status.

See [4.7 User Interface](#) for details.

9.1.5 UART Transmitting Data Setup (send_data_set)

Set up the motor initial settings, current rotation speed, and EMG status monitoring data.

The setups for communication are, 115,200 bps, data 8-bit, stop bit 1 bit, without parity and without flow control.

9.1.6 Temperature Measurement (temp_check)

Obtain the AD values of VR1 TEMP0.

Computed to one decimal place between temperatures using a linear equation by referring to the values in the table.

Example: When Temp (12bitAD) = 1790

30°C AD Judgment Value = 1858 (table) / 40°C AD Judgment Value = 1507 (table)

1858–1507 = 351 (fixed gradient within 30°C to 40°C)

1858–1790 = 68 (deviation from 30°C)

Interpolation $10^{\circ}\text{C} \times 68 / 351 = 1.9^{\circ}\text{C}$ (1.9373...)

$30^{\circ}\text{C} + 1.9^{\circ}\text{C} = 31.9^{\circ}\text{C}$

- Temperature range

The temperature range is from -20°C to 100°C, and an error is displayed when the temperature is outside the range.

9.1.7 Status Check Monitor

Monitoring of current rotation speed, etc. on the TeraTerm is provided.

- TeraTerm Communication Setting

115,200 bps, data 8-bit, stop bit 1-bit, without parity and without flow control.

- Details of Initial Display

The initial status below is transmitted one time after releasing the reset.

Control ch = CH0

Carrier frequency = xxxxx Hz

Dead time = x.x μ s

Gate active = H/H or L/L, etc.

Position Detection = 1-shunt (with/without SPWM) or 3-shunt

VDC Voltage = xx.x V (Note1)

Board Temperature = xx.x $^{\circ}$ C (Note2) (Note3)

U,V,W Voltage = x.xx V, x.xx V, x.xx V

DAC Use = Yes/No

Built-in Amplifier Use = Yes/No

Rotation Direction = CW or CCW

Modulation Type = two-phase modulation or three-phase modulation

Rotation Speed Command = Variable Resistor S or Push SW

Note1: Calculated by loading AD(VDC)

Note2: Calculated by loading AD(VR1,TEMP0)

Note3: When SW3 enables the pseudo temperature constant for rotational speed adjustment, "--" is displayed.

- Details Displayed after Initial Display

After a motor speed command is generated, display the current rotation speed of the control ch, every 1 second.

e.g.)

40 Hz

60 Hz

80 Hz

:

- Details of Displayed EMG

When entering the EMG state,

the EMG status of the control ch is displayed every 1 second.

For hardware EMG in the STOP stage, the EMG status is not displayed.

EMG_S

Control ch = CH or CH

Carrier frequency = xxxxx Hz

Dead time = x.x μ s

Gate active = H/H or L/L, etc.

Position Detection = 1-shunt (with/without SPWM) or 3-shunt

VDC Voltage = xx.x V (Note1)

Board Temperature = xx.x °C (Note2) (Note3)

U,V,W Voltage = x.xx V, x.xx V, x.xx V

DAC Use = Yes/No

Built-in Amplifier Use = Yes/No

Rotation Direction = CW or CCW

Modulation Type = two-phase modulation or three-phase modulation

Rotation Speed Command = Variable Resistor SW or Push SW

Note1: Calculated by loading AD(VDC)

Note2: Calculated by loading AD(VR1,TEMP0)

Note3: When SW3 enables the pseudo temperature constant for rotational speed adjustment, "--" is displayed.

10. Functions

The following are the interface between the application and the motor controller, and the motor controller and the motor driver.

10.1 Control Commands

The control commands are listed as below:

10.1.1 Control Method (usr.com_user)

- Motor start and stop
 - Encoder equipped or not
 - Modulation Type (two-phase modulation, three-phase modulation)
 - Shift PWM ON/OFF
- (Shift1: Valid only when VE is used, and only in the case of 1-shunt and two-phase modulation.
Shift2: Valid only in the case of 1-shunt and three-phase modulation.)

```
typedef struct {
    uint16_t reserve:12;    /* reserve */
    uint16_t spwm:1;        /* PWM Shift          0=off, 1=on */
    uint16_t modul:1;       /* PWM Modulation     0=3phase modulation, 1=2phase modulation */
    uint16_t encoder:1;     /* Position detect     0=Current, 1=Encoder */
    uint16_t onoff:1;       /* PWM output          0=off, 1=on */
} command_t;
```

command_t com_user;

usr.com_user is set up as a control command in the application.

10.1.2 Control Target Speed

q31_u usr.omega_user; /* [Hz/maxHz] Target omega by user */

usr.omega_user is set up as a control target speed in the application.

10.1.3 Starting Current

q15_t Id_st_user; /* [A/maxA] Start d-axis current by user */

q15_t Iq_st_user; /* [A/maxA] Start q-axis current by user */

usr.Id_st_user and usr.Iq_st_user are set up as the start current references in the application.

10.2 Drive Command

Drive Commands are listed as below:

10.2.1 Driving Method (drv.command)

```
command_t    command;
```

The application will transfer the driving method to the motor control driver side via the drv.command.

10.2.2 Vector Control Command (drv.vector_cmd)

A command for executing vector control computation and it administers the stage by stage processing.

```
typedef struct {
    uint16_t reserve:9;          /* reserve */
    uint16_t F_vcomm_theta:1;    /* Omega to Theta    0=command value, 1=Calculate the theta from omega. */
    uint16_t F_vcomm_omega:1;    /* Omega by          0=command value, 1=Result of Estimation position */
    uint16_t F_vcomm_current:1;  /* Current by        0=command value, 1=Result of Speed Control */
    uint16_t F_vcomm_volt:1;     /* Voltage by        0=command value, 1=Result of Current Control (unuse)*/
    uint16_t F_vcomm_Edetect:1;  /* Position detect   0=off, 1=on */
    uint16_t F_vcomm_Idetect:1;  /* Current detect    0=off, 1=on (unuse)*/
    uint16_t F_vcomm_onoff: 1;   /* Motor output      0=off 1=on */
} vectorcmd_t;
```

The vector control drive command (drv.vector_cmd) is set up as below in each stage and a command is given to the motor drive.

Table 10.1 Vector Control Command

cmd \ Stage	theta	omega	current	volt	Edetect	Idetect	onoff
StopcForce	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR
Bootstrap	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	SET
InitPosition	CLEAR	CLEAR	CLEAR	SET	CLEAR	SET	SET
Forced	SET	CLEAR	CLEAR	SET	SET	SET	SET
Change_up	SET	SET	CLEAR	SET	SET	SET	SET
Steady	SET	SET	SET	SET	SET	SET	SET
Emergency	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR	CLEAR

1) F_vcomm_theta

For the rotor position estimation computation, the estimated value is adopted as the rotor position when SET. The reference value is adopted as the rotor position when CLEAR.

2) F_vcomm_omega

For the rotor position estimation computation, the estimated value is adopted as the speed ω when SET. The reference value is adopted as the speed ω when CLEAR.

3) F_vcomm_current

For the speed control, gives a command for the calculation method for the standard values of d- and q-axis currents.

The value acquired using the speed deviation through the PI control is adopted as a standard value when SET. The PI control is not executed when CLEAR but the reference value is directly adopted as a standard value.

4) F_vcomm_volt

For the current control, the calculation methods for the d- and q-axis voltage standard values are given as a command.

The value acquired using the current deviation through the PI control is adopted as a standard value when SET. The PI control is not executed when CLEAR but the reference value is directly adopted as a standard value.

5) F_vcomm_Edetect

The induced voltage computation is executed when SET, and the rotor position estimation computation is executed. The induced voltage computation is not executed when CLEAR, but the induced voltage is set to 0 and the reference value is adopted as the rotor position.

6) F_vcomm_Idetect

The Input coordinate axis conversion computation is executed when SET. The computation is not executed when CLEAR, but the value is cleared.

7) F_vcomm_onoff

The motor output waveform is turned ON when SET. The motor output waveform is turned OFF when CLEAR.

10.3 Driver Status

10.3.1 Error Status (drv.state)

```
typedef union {
    struct {
        uint16_t reserve:10;          /* reserve */
        uint16_t Loss_sync:1;         /* 0:normal, 1: Loss of synchronism*/
        uint16_t emg_DC:1;            /* 0:normal, 1: Overvoltage (Vdc)*/
        uint16_t emg_I:1;             /* 0:normal, 1: Current detection error */
        uint16_t emg_S:1;             /* 0:normal, 1: Overcurrent (Software) */
        uint16_t emg_H:1;             /* 0:normal, 1: Overcurrent (Hardware) */
        uint16_t emg_F:1;             /* 0:normal, 1: Flux observer error*/
    } flg;
    uint16_t all;
} state_t;
```

Loss_sync	Step-Out Detection SET when a step-out is detected. (Not implemented)
emg_DC	Abnormal Voltage Detection SET when an abnormal voltage is detected.
emg_I	Current Detection Abnormality SET when a current detection abnormality is detected. (Not implemented)
emg_S	Software Overcurrent Detection SET when an overcurrent is detected during software processing.
emg_H	Hardware Overcurrent Detection SET when an overcurrent is detected in the microcontroller hardware function.
emg_F	Flux Observer Error Detection This is set when Flux Observer operates abnormally or reverses. (Flux Observer Method)

10.4 Motor Control Structure

Motor Control Structure (vector_t) is defined in the ipdefine.h. The variables are declared per motor channel as below:

e.g.)
vector_t Motor_ch0; /* Motor data for ch0 */

10.4.1 List of Variables

Table 10.2 List of Variables

Type	Code	Description	Q Forma t	Remarks
main_stage_e	stage.main	Main Stage	---	cStop cBootstrap cInitposition cForce cChange_up cSteady_A cEmergency
sub_stage_e	stage.sub	Sub Stage	---	cStep0 cStep1 cStep2 cStep3 cStepEnd
itr_stage_e	stage.itr	Interruption Stage	---	ciStop ciBootstrap ciInitposition_i ciInitposition_v ciForce_i ciForce_v ciChange_up ciSteady_A ciEmergency
q31_u	drv.omega_com	Driving Speed Reference Value	Q31	
q31_u	drv.omega	Estimated Speed	Q31	
q15_t	drv.omega_dev	Speed Deviation	Q15	
q31_u	drv.ld_com	d-Axis Current Reference Value	Q31	
q31_u	drv.lq_com	q-Axis Current Reference Value	Q31	
q15_t	drv.ld_ref	d-Axis Current Standard Value	Q15	
q15_t	drv.lq_ref	q-Axis Current Standard Value	Q15	
q15_t	drv.ld	d-Axis Current	Q15	

q15_t	drv.lq	q-Axis Current	Q15	
q31_u	drv.lq_ref_l	q-Axis Current Integrated Value	Q31	
uint16_t	drv.theta_com	Electrical Angle Reference Value	Q0	
uint32_u	drv.theta	Rotor Position	Q0	
q15_t	drv.Vdc	Power Supply Voltage	Q15	
q31_u	drv.Vdc_ave	DC Voltage Average Value	Q31	
q31_u	drv.Vd	d-Axis Voltage	Q31	
q31_u	drv.Vq	q-Axis Voltage	Q31	
q15_t	drv.Vdq	dq-Axis Voltage	Q15	
q31_u	drv.Vdq_ave	dq-Axis Voltage Average Value	Q31	
q31_t	drv.Vd_out	Output Voltage	Q31	
q15_t	drv.Ed	d-Axis Induced Voltage	Q15	
q15_t	drv.Eq	q-Axis Induced Voltage	Q15	
q31_t	drv.Ed_l	d-Axis Induced Voltage Integrated Value	Q31	
q31_t	drv.Ed_PI	d-Axis Induced Voltage PI Value	Q31	
state_t	drv.state	Motor Abnormality Status	---	
command_t	drv.command	Driving Method	---	(Refer to 10.2.1.)
vectorcmd_t	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
uint16_t	drv.chkpls	Current Detection Protection Duty Width	Q0	
uint8_t	drv.idetect_error	Current Detection Status	---	0:Detection Enabled 1:Detection Disabled
q15_t	drv.la_raw	Phase-a Current (raw data)	Q15	
q15_t	drv.lb_raw	Phase-b Current (raw data)	Q15	
q15_t	drv.lc_raw	Phase-c Current (raw data)	Q15	
q15_t	drv.la	Phase-a Current (detection error protection)	Q15	
q15_t	drv.lb	Phase-b Current (detection error protection)	Q15	

q15_t	drv.lc	Phase-c Current (detection error protection)	Q15	
int32_t	drv.lao_ave	Phase-a Zero Current Average AD	Q0	
int32_t	drv.lbo_ave	Phase-b Zero Current Average AD	Q0	
int32_t	drv.lco_ave	Phase-c Zero Current Average AD	Q0	
uint8_t	drv.spdprd	Speed Control Cycle	Q0	
q15_t	drv.omega_enc	Encoder Speed	Q15	
q15_t	drv.omega_enc_raw	Encoder Speed (raw data)	Q15	
q31_u	drv.omega_enc_ave	Encoder Average Speed	Q31	
uint32_t	drv.theta_enc	Encoder Angle	Q0	
int16_t	drv.EnCnt	Encoder Counter Reading	Q0	
int16_t	drv.EnCnt1	Encoder Counter Previous Value	Q0	
int16_t	drv.EnCnt_dev	Encoder Counter Deviation	Q0	
uint8_t	drv.shift2_mode	Shift 2 Control Mode	---	cNoShift2 cShift2_Spee d cShift2_End cNormal_End
uint8_t	drv.shift2_mode_start	Initial Shift 2 Control Mode	---	cNoShift2 cShift2_Spee d
q15_t	drv.spwm2_threshold	Normal-to-Shift2 switching speed	Q15	For Shift 2
q15_t	drv.spwm2_threshold_hys	Normal-to-Shift2 switching speed Hysteresis	Q15	For Shift 2
uint8_t	drv.adtrg0_moduration_shift2	AD conversion trigger timing (1st)	---	For Shift 2
uint8_t	drv.adtrg1_moduration_shift2	AD conversion trigger timing (2nd)	---	For Shift 2
uint16_t	drv.adtrg_comp_shift2	AD conversion trigger timing correction value	---	For Shift 2
q15_t	drv.Ia_offset_shift2	U-phase current offset	Q15	For Shift 2

q15_t	drv.Ib_offset_shift2	V-phase current offset	Q15	For Shift 2
q15_t	drv.Ic_offset_shift2	W-phase current offset	Q15	For Shift 2
q31_u	drv.Vq_lim_shift2	q-axis voltage limit value	Q31	For Shift 2
q31_u	drv.Vd_lim_shift2	d-axis voltage limit value	Q31	For Shift 2
uint8_t	drv.shift2_change	Shift2 switching timing	---	For Shift 2
uint8_t	drv.shift2_change_bf	Previous Shift2 switching timing	---	For Shift 2
uint16_t	drv.deadtime	Deadtime	---	For Shift 2
q31_u	usr.omega_user	Controller Target Speed	Q31	
q15_t	usr.Id_st_user	Starting Id-Current	Q15	
q15_t	usr.Iq_st_user	Starting Iq-Current	Q15	
uint16_t	usr.lambda_user	Initial Rotor Position	Q0	
command_t	usr.com_user	Control Method	---	(Refer to 10.1.1.)
command_t	usr.com_user_1	Control Method Previous	---	
q15_t	usr.Id_st_user2	Startup Id current value2	Q15	Flux Observer Method
q15_t	para.omega_min	Forced Commutation End Speed	Q15	
q15_t	para.omega_v2i	Current Control Changeover Speed	Q15	
q15_t	para.spwm_threshold	Shift PWM switching speed	Q15	Only in 1-shunt mode
q15_t	para.spwm_threshold_hys	Shift PWM switching speed hysteresis	Q15	Only in 1-shunt mode
q15_t	para.spwm2_threshold	Shift PWM2 switching speed	Q15	Only in 1-shunt mode
q15_t	para.spwm2_threshold_hys	Shift PWM2 switching speed hysteresis	Q15	Only in 1-shunt mode
uint16_t	para.spwm2_rate_threshold_hys	Shift PWM2 Duty threshold hysteresis	Q0	For Shift 2
q31_t	para.vd_pos	Positioning Reference Voltage	Q31	

q15_t	drv.Ialpha	α -axis current	Q15	
q15_t	drv.Ibeta	β -axis current	Q15	
q15_t	drv.Id_dev	d-axis current deviation	Q15	
q15_t	drv.Iq_dev	q-axis current deviation	Q15	
q31_u	drv.Vd_com	d-axis voltage command value	Q31	
q31_u	drv.Vq_com	q-axis voltage command value	Q31	
q31_u	drv.Vd_I	d-axis voltage integral value	Q31	
q31_u	drv.Vq_I	q-axis voltage integral value	Q31	
q31_u	drv.Valpha	α -axis voltage	Q31	
q31_u	drv.Vbeta	β -axis voltage	Q31	
q31_u	drv.Valpha_pre	Previous α -axis voltage	Q31	
q31_u	drv.Vbeta_pre	Previous β -axis voltage	Q31	
q31_t	para.spd_coef	Output Voltage Factor	Q15	
q31_u	para.sp_ud_lim_f	Drive Speed Increase/Decrease Limit	Q31	
q31_u	para.sp_up_lim_s	Drive Speed Increase Limit	Q31	
q31_u	para.sp_dn_lim_s	Drive Speed Decrease Limit	Q31	
uint16_t	para.time.initpos	Positioning Time	Q0	
uint16_t	para.time.initpos2	Positioning Status Standby Time	Q0	
uint16_t	para.time.bootstp	Bootstrap Time	Q0	
uint16_t	para.time.go_up	Wait Time after Change-up	Q0	
q31_t	para.iq_lim	q-Axis Current Limit	Q31	
q31_t	para.id_lim	d-Axis Current Limit	Q31	
q15_t	para.err_ovc	Overcurrent Setup Value	Q15	
q31_t	para.pos.kp	Position Estimation Proportional Gain	Q15	Q12 Support
q31_t	para.pos.ki	Position Estimation Integration Gain	Q15	Q12 Support
int32_t	para.pos.ctrlprd	Position Estimation Control Cycle	Q16	

q31_t	para.spd.kp	Speed Control Proportional Gain	Q15	Q12 Support
q31_t	para.spd.ki	Speed Control Integration Gain	Q15	Q12 Support
uint8_t	para.spd.pi_prd	(Not Used)	Q0	
q31_t	para.crt.dkp	d-Axis Current Control Proportional Gain	Q15	Q12 Support
q31_t	para.crt.dki	d-Axis Current Control Integration Gain	Q15	Q12 Support
q31_t	para.crt.qkp	q-Axis Current Control Proportional Gain	Q15	Q12 Support
q31_t	para.crt.qki	q-Axis Current Control Integration Gain	Q15	Q12 Support
q31_t	para.motor.r	Motor Winding Resistance	Q15	
q31_t	para.motor.Lq	Motor q-Axis Inductance	Q15	
q31_t	para.motor.Ld	Motor d-Axis Inductance	Q15	
uint32_t	para.enc.pls2theta	Computation factor from the number of pulses to the angle	Q32	
q15_t	para.enc.pls2omega	Computation factor from the number of pulses to the speed	Q15	
int32_t	para.enc.plsnum	Number of encoder pulses	Q0	
int32_t	para.enc.ctrlprd	Encoder Control Cycle	Q16	
uint32_t	para.enc.deg_adjust	Electrical Angle Adjustment	Q0	
int32_t	para.delta_lambda	Current Changeover Phase for Change-up	Q0	
uint16_t	para.chkpls	Current Detection Protection Duty Width	Q0	
uint16_t	para.trgcomp0	Shift2 trigger timing0	---	
uint16_t	para.trgcomp1	Shift2 trigger timing1	---	
uint8_t	para.shift2	Shift PWM2 center selection	---	0:U-phase Center

				1:V-phase Center 2:W-phase Center
uint8_t	para.sensorless_method	Sensorless control method	---	0:Induced Voltage 1:Flux Observer
uint32_t	stage_counter	Stage Counter	Q0	
shunt_type_e	shunt_type	Shunt Type	---	c1shunt c3shunt
boot_type_e	boot_type	Starting Type	---	cBoot_i cBoot_v
q31_u	drv.phi_omega	Flux Observer Estimated Speed	Q31	Flux Observer Method
q31_u	drv.phi_omega_ave	Flux Observer Estimated Speed Average	Q31	Flux Observer Method
uint32_u	drv.phi_tq_ave2	Motor Output Torque Average2	Q31	Flux Observer Method
uint32_u	drv.theta_phi	Flux Observer Angle	Q0	Flux Observer Method
uint32_u	drv.theta_phi_ie	Previous Flux Observer Angle	Q0	Flux Observer Method
uint32_u	drv.theta_phi2	Corrected Flux Observer Angle	Q0	Flux Observer Method
uint32_t	drv.theta_phi_bf	Previous Flux Observer Angle	Q0	Flux Observer Method
uint16_t	drv.theta_phi_rate	Weighting between Forced Commutation and Sensorless Angle	Q0	Flux Observer Method
uint16_t	drv.force_rate	Forced Commutation Angle Ratio	Q0	Flux Observer Method
q15_t	drv.phi_omega_div	Previous and Current Flux Observer Speed Difference	Q15	Flux Observer Method
q31_u	drv.phi_omega_bf	Previous Flux Observer Speed	Q31	Flux Observer Method

uint8_t	drv.phi_omega_div_emg_f	EMG Flag for Flux Observer	---	Flux Observer Method
q31_t	drv.Id_com2	d-axis currentCommand Value2	Q31	Flux Observer Method
q15_t	drv.DutyU	U-phase PWM Duty ratio	Q15	
q15_t	drv.DutyV	V-phase PWM Duty ratio	Q15	
q15_t	drv.DutyW	W-phase PWM Duty ratio	Q15	
q15_t	drv.DutyU_bf	Previous U-phase PWM Duty ratio	Q15	
q15_t	drv.DutyV_bf	Previous V-phase PWM Duty ratio	Q15	
q15_t	drv.DutyW_bf	Previous W-phase PWM Duty ratio	Q15	
float32_t	para.phi.SOGI_G	SOGI GAIN	---	Flux Observer Method
float32_t	para.phi.SOGI_G_low_speed	SOGI GAIN(low-speed)	---	Flux Observer Method
float32_t	para.phi.SOGI_G_high	SOGI GAIN(high-speed)	---	Flux Observer Method
q15_t	para.phi.SOGI_G_Change_Hz	SOGI GAIN switching Speed	Q15	Flux Observer Method
float32_t	para.phi.theta_phi_adj_tq_th	Angle Adjustment Ratio	---	Flux Observer Method
float32_t	para.phi.Id_CH_ini	Id application multiplier at low speed	---	Flux Observer Method
q15_t	para.phi.Id_CH_ini_Hz	Id application speed at low speed	Q15	Flux Observer Method
float32_t	para.phi.phi_omega_div_emg	Speed Difference Error determination coefficient	---	Flux Observer Method
int32_t	para.phi.phi_CH_time	Id application period	---	Flux Observer Method

uint32_u	para.phi.theta_phi_adj	Angle correction value	---	Flux Observer Method
uint32_u	para.phi.theta_phi_adj_tq	Fixed angle correction value for the observer based on position compensation and load torque	---	Flux Observer Method
int32_t	para.phi.phi_prd	Flux Observer Control Period	---	Flux Observer Method
uint8_t	enable_theta_phi_adj	Angle adjustment enable flag	---	Flux Observer Method
q15_t	para.phi.omega_phi_force_end	Forced commutation phase2 end speed	Q15	Flux Observer Method
detect_state_omega_e	state_omega_type	Stage for Flux Observer Speed	---	Initposition_o Force_o Change_up_o Steady_F_o
detect_state_theta_e	state_theta_type	Stage for Flux Observer Angle	---	Initposition_t Force_t Change_up_t Steady_F_t
phi_t	Phi	Flux Observer Parameter	---	(エラー! 参照元が見つかりません。 for reference)
force2_onoff	force2	Forced commutation phase2 Specification Information	---	0: Forced commutation phase2 off 1: Forced commutation phase2 on

Table 10.3 Vector Control Using Software

Type	Code	Description	Q Format	Remarks
uint32_t*	drv.ADxREG0	AD Conversion Result Register Address	---	
uint32_t*	drv.ADxREG1	AD Conversion Result Register Address	---	
uint32_t*	drv.ADxREG2	AD Conversion Result Register Address	---	
uint32_t*	drv.ADxREG3	AD Conversion Result Register Address	---	
q15_t	drv.Vdc_adc	Power Supply Voltage Conversion Result	Q15	
q15_t	drv.Ia_adc	Phase-U Current Conversion Result	Q15	3-shunt only
q15_t	drv.Ib_adc	Phase-V Current Conversion Result	Q15	3-shunt only
q15_t	drv.Ic_adc	Phase-W Current Conversion Result	Q15	3-shunt only
q15_t	drv.Idc1_adc	Phase-1st Current Conversion Result	Q15	1-shunt only
q15_t	drv.Idc2_adc	Phase-2nd Current Conversion Result	Q15	1-shunt only
q31_u	drv.Idco_ave	Zero Current Average AD	Q0	1-shunt only
q15_t	drv.Ialpha	α -Axis Current	Q15	
q15_t	drv.Ibeta	β -Axis Current	Q15	
q15_t	drv.Id_dev	d-Axis Current Deviation	Q15	
q15_t	drv.Iq_dev	q-Axis Current Deviation	Q15	
q31_u	drv.Vd_com	d-Axis Voltage Reference Value	Q31	
q31_u	drv.Vq_com	q-Axis Voltage Reference Value	Q31	
q31_u	drv.Vd_I	d-Axis Voltage Integrated Value	Q31	
q31_u	drv.Vq_I	q-Axis Voltage Integrated Value	Q31	
q31_u	drv.Valpha	α -Axis Voltage	Q31	
q31_u	drv.Vbeta	β -Axis Voltage	Q31	
q15_t	drv.DutyU	Phase-U PWM Duty Ratio	Q15	
q15_t	drv.DutyV	Phase-V PWM Duty Ratio	Q15	
q15_t	drv.DutyW	Phase-W PWM Duty Ratio	Q15	
int32_t	drv.AdTrg0	AD Trigger Timing 0 Position	Q15	
int32_t	drv.AdTrg1	AD Trigger Timing 1 Position	Q15	
uint8_t	drv.Sector	Sector	Q0	0 to 5
uint8_t	drv.Sector1	Previous Sector	Q0	0 to 5
int16_t	para.TrigComp	Trigger Timing Compensation	Q15	
trgpos_e	para.TrgPosMd	Current Detection Position Mode	---	0:3-shunt 1:1-shunt (first half) 2:1-shunt (second half)
phcvmd_e	para.PhCvMd	Phase Conversion Mode	---	0: Spatial Vector 1: Inverse Clarke (not implemented)

10.5 Function Details

10.5.1 Encoder Initial Setup (init_ENCen)

10.5.1.1 Syntax

void init_ENCen(void)

Parameter:

No

Returned Value:

No

10.5.1.2 Process

Initial setup of encoder circuit

- Encoder circuit setup
- Port setup

10.5.2 ADC Initial Setup (init_ADCen)

10.5.2.1 Syntax

void init_ADCen(void)

Parameter:

No

Returned Value:

No

10.5.2.2 Process

Initial setup of ADC

- Motor AD Setup (trigger)
- ADC Permission

10.5.3 PMD Initial Setup (init_PMDen)

10.5.3.1 Syntax

void init_PMDen(void)

Parameter:

No

Returned Value:

No

10.5.3.2 Process

Initial Setup of PMD (programmable motor driver)

10.5.4 VE Initial Setting (init_VEen)

10.5.4.1 Syntax

void init_VEen(void)

Argument:

None

Return value:

None

10.5.4.2 Processing contents

Perform initial setting of the VE (Vector engine).

-VE interrupt setting

-VE setting

Program Schedule is set as following.

n	CODE	Task Name	<ADC>	<END>
0	0	Output Control1	0	0
1	1	Trigger Generation	1	0
2	2	Input Processing1	0	1
3	6	SIN/COS Calculation1	0	0
4	7	Output Coordinate Axis Transformation(Inverse Park Transform)	0	0
5	8	Output Phase Transformation 1 (Space Vector Transform)	0	0
6	0	Output Control1	0	0
7	1	Trigger Generation	1	0
8	2	Input Processing 1	0	0
9	3	Input Phase Transformation (Clark Transform)	0	0
10	4	Input Coordinate Axis Transformation (Park Transform)	0	1

11	5	Current Control	0	0
12	6	SIN/COS Calculation 1	0	0
13	7	Output Coordinate Axis Transformation (Inverse Park Transform)	0	0
14	8	Output Phase Transformation 1 (Space Vector Transform)	0	0
15	0	Output Control1	0	0
16	1	Trigger Generation	1	0
17	2	Input Processing 1	0	0
18	3	Input Phase Transformation (Clark Transform)	0	0
19	4	Input Coordinate Axis Transformation (Park Transform)	0	1
20	5	Current Control	0	0
21	6	SIN/COS Calculation 1	0	0
22	7	Output Coordinate Axis Transformation (Inverse Park Transform)	0	0
23	8	Output Phase Transformation 1 (Space Vector Transform)	0	0
24	9	Output Control 2	0	0
25	1	Trigger Generation	1	0
26	10	Input Processing 2	0	0
27	3	Input Phase Transformation (Clark Transform)	0	0
28	4	Input Coordinate Axis Transformation (Park Transform)	0	1
29	-	-	-	-
30	-	-	-	-
31	-	-	-	-

10.5.5 Shift2 Initial Setting(init_Shift2_CHx)

10.5.5.1 Syntax

void init_Shift2(void)

Argument:

None

Return Value:

None

10.5.5.2 Processing Details

Initialize the Shift PWM Mode2.

- AD setting
- VE setting(During VE setting)
- PMD setting

10.5.6 Comparator Initial Setting (init_COMPen)

10.5.6.1 Syntax

void init_COMPen(void)

Argument:

None

Return Value:

None

10.5.6.2 Processing Details

Initialize the built-in comparator for overcurrent detection.

-COMP setting

-DAC setting(Reference voltage for positive/negative current)

10.5.7 Motor Control Initial Setup (B_Motor_Init)

10.5.7.1 Syntax

void B_Motor_Init(void)

Parameter:

No

Returned Value:

No

10.5.7.2 Variable

Direction	Code	Description	Q Format	Remarks
Input/ Output	drv.shift2_mode_start	Initial Shift 2 Control Mode	---	
	usr.Id_st_user2	Startup Id current value2	Q15	Flux Observer Method
Output	shunt_type	Shunt Type	---	
	boot_type	Driver Type	---	
	usr.com_user.encoder	Encoder Control	---	
	stage.main	Main Stage	---	
	stage.sub	Sub Stage	---	
	drv.lao_ave	Phase-u Zero Current Average AD	Q0	
	drv.lbo_ave	Phase-v Zero Current Average AD	Q0	
	drv.lco_ave	Phase-w Zero Current Average AD	Q0	
	drv.ldco_ave	Zero Current Conversion Result	Q15	1-shunt only
	usr.lq_st_user	Starting lq-Current	Q15	

usr.id_st_user	Starting Id-Current	Q15	
usr.lambda_user	Initial Rotor Position	Q0	
para.motor.r	Motor Winding Resistance	Q15	
para.motor.Lq	Motor q-Axis Inductance	Q15	
para.motor.Ld	Motor d-Axis Inductance	Q15	
para.spwm_threshold	Shift PWM switching speed	Q15	Only in 1-shunt mode
para.spwm_threshold_hys	Shift PWM switching speed hysteresis	Q15	Only in 1-shunt mode
para.chkpls	Current Detection Protection Duty Width	Q0	
para.vd_pos	Positioning Reference Voltage	Q31	Voltage Start only
para.spd_coef	Output Voltage Factor	Q15	Voltage Start only
para.sp_ud_lim_f	Drive Speed Increase/Decrease Limit	Q31	
para.sp_up_lim_s	Drive Speed Increase Limit	Q31	
para.sp_dn_lim_s	Drive Speed Decrease Limit	Q31	
para.time.bootstp	Bootstrap Time	Q0	
para.time.initpos	Positioning Time	Q0	
para.time.initpos2	Positioning Status Standby Time	Q0	
para.time.go_up	Wait Time after Change-up	Q0	
para.omega_min	Forced Commutation End Speed	Q15	
para.omega_v2i	Current Control Changeover Speed	Q15	
para.delta_lambda	Current Changeover Phase for Change-up	Q0	
para.pos.ki	Position Estimation Integration Gain	Q15	Q12 Support
para.pos.kp	Position Estimation Proportional Gain	Q15	Q12 Support
para.pos.ctrlprd	Position Estimation Control Cycle	Q16	
para.spd.ki	Speed Control Integration Gain	Q15	Q12 Support
para.spd.kp	Speed Control Proportional Gain	Q15	Q12 Support
para.current.dki	d-Axis Current Proportional Gain	Q15	Q12 Support
para.current.dkp	d-Axis Current Integration Gain	Q15	Q12 Support
para.current.qki	q-Axis Current Proportional Gain	Q15	Q12 Support
para.current.qkp	q-Axis Current Integration Gain	Q15	Q12 Support
para.iq_lim	q-Axis Current Limit	Q31	
para.id_lim	d-Axis Current Limit	Q31	
para.err_ovc	Overcurrent Setup Value	Q15	
para.enc.pls2theta	Computation factor from the number of pulses to the angle	Q32	
para.enc.deg_adjust	Electrical Angle Adjustment	Q0	
para.enc.plsnum	Number of encoder pulses	Q0	
para.enc.pls2omega	Computation factor from the number of pulses to the speed	Q15	
para.enc.ctrlprd	Encoder Control Cycle	Q16	
para.shift2	Shift2 center phase setting	---	

para.spwm2_threshold	Normal-to-Shift2 switching speed	Q15	For Shift 2
para.spwm2_threshold_hys	Normal-to-Shift2 switching speed Hysteresis	Q15	For Shift 2
drv.Ia_offset_shift2	U-phase current offset	Q15	For Shift 2
drv.Ib_offset_shift2	V-phase current offset	Q15	For Shift 2
drv.Ic_offset_shift2	W-phase current offset	Q15	For Shift 2
usr.com_user.modul	Modulation method control command	---	2-phase/3-phase modulation
drv.adtrg0_moduration_shift2	AD CONVERSION TRIGGER TIMING(1st)	---	For Shift 2
drv.adtrg1_moduration_shift2	AD CONVERSION TRIGGER TIMING(2nd)	---	For Shift 2
drv.adtrg_comp_shift2	AD CONVERSION TRIGGER TIMING Correction value	---	For Shift 2
drv.deadtime	Deadtime	---	
drv.Vq_lim_shift2	q-axis voltage limit value	Q31	For Shift 2
drv.Vd_lim_shift2	d-axis voltage limit value	Q31	For Shift 2
para.TrgPosMd	Current Detection Position Mode	---	
para.TrgComp	Trigger Timing Compensation	Q15	
detect_type	Position Detection Method	---	Flux Observer Method
para.motor.Pole_pare	Number of motor poles	---	Flux Observer Method
para.phi.phi_omega_div_emg	Speed EMG judgment threshold for Flux Observer	Q0	Flux Observer Method
para.phi.phi_CH_time	Id application period	---	Flux Observer Method
para.phi.SOGI_G	SOGI Control GAIN	Q31	Flux Observer Method
para.phi.SOGI_G_low_speed	SOGI GAIN(low-speed)	---	Flux Observer Method
para.phi.SOGI_G_high	SOGI GAIN(high-speed)	---	Flux Observer Method
para.phi.SOGI_G_Change_Hz	SOGI GAIN switching Speed	Q15	Flux Observer Method
para.phi.theta_phi_adj_tq_th	Angle Adjustment ratio	---	Flux Observer Method
enable_theta_phi_adj	Angle adjustment enable flag	---	Flux Observer Method
para.phi.Id_CH_ini	Id application multiplier at low speed	---	Flux Observer Method
para.phi.Id_CH_ini_Hz	Id application speed at low speed	Q15	Flux Observer Method
para.phi.omega_phi_force_end	Forced commutation phase2 end speed	Q15	Flux Observer Method
para.phi.phi_prd	Flux Observer Control Period	Q0	Flux Observer Method
drv.Id_com2	d-axis current Command Value2	Q31	Flux Observer Method
force2	Forced commutation phase2 Usage status	---	Forced commutation phase2 is used or not

10.5.7.3 Process

Initializing the motor control parameters.

Setup of the variable whose setups are not changed during the control.

10.5.8 DAC Control Initial Setup (init_Dac)

10.5.8.1 Syntax

```
void init_Dac(TSB_TSPI_TypeDef* const TSPIx)
```

Parameter:

No

Returned Value:

No

10.5.8.2 Process

Initial Setup of DAC IC Control

SIO enabled

Port Initial Setup

SIO Initial Setup

DAC IC Initialization Communication

SIO Interruption Level Setup

SIO Interruption Suspension Clear

Transmission Interruption Permission

10.5.9 Cycle Timer Initial Setup (init_Timer_interval4kH)

10.5.9.1 Syntax

void init_Timer_interval4kH(void)

Parameter:

No

Returned Value:

No

10.5.9.2 Process

Initial setup of timer for generating the 4 kHz cycle timing.

10.5.10 User Control Initial Setup (init_user_control)

10.5.10.1 Syntax

void init_user_control(void)

Parameter:

No

Returned Value:

No

10.5.10.2 Process

Initial setting for command control from outside such as users.

Key Input Processing Initial Setup (init_Uikey)

Analog Voltage Input Processing Initial Setup (init_soft_adc)

LED Initial Setup (init_led)

UART Initial Setup (init_uart)

10.5.11 User Control (user_control)

10.5.11.1 Syntax

```
void user_control(void)
```

Parameter:

No

Returned Value:

No

10.5.11.2 Process

Detection of a command from an outside source, such as the user and execution of control according to the command.

- By S_SW1, switching the rotation
- By S_SW3, switching between rotation speed adjustment and pseudo temperature

adjustment

- By USW1, updating the DAC display contents
- By USW2, switching the DAC No
- By VR1, Adjusting the rotation speed/pseudo temperature
- Outputting configuration and rotation speed information via UART
- Displaying the internal state on LEDs

Note: The S_SW switches cannot be enabled unless motor operation is stopped beforehand.

- Acquisition of Analog Input Voltage

Acquisition and averaging of analog voltage values of fake temperature (VR1) and Motor ch0 inverter temperature(TEMP0).

- Digital Port Input

Processing of key chatter.

10.5.12 User Motor Control (B_User_MotorControl)

10.5.12.1 Syntax

```
void B_User_MotorControl(void)
```

Parameter:

No

Returned Value:

No

10.5.12.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	target_spd	Target Speed	---	User Command
	sswdata.sw	S_SW ON/OFF State	---	User Command
	uswdata.sw	USW ON/OFF State	---	User Command
Output	usr.omega_user	Controller Target Speed	Q31	
	usr.com_user.onoff	Motor ON/OFF	---	
	drv.state	Motor Abnormality Status	---	
	Detect_type	Position Detection Method	---	Flux Observer Method
	usr.lamixla_user	Initial Rotor Position	Q0	When Hall sensor and encoder control is available

10.5.12.3 Process

Processing of motor-related commands from the user.

- Overcurrent (Hardware) Status Check

Checking of the hardware overcurrent status to upgrade the motor abnormality status.

- Motor ON/OFF Command

Determination of Motor ON/OFF(usr.com_user.onoff) according to the key status.

- Normalization of Drive Speed, etc.

Normalization of the target speed.

10.6 Motor Control Function

Motor control processing is realized by the following functions that are called from inside the main loop of the main function. Motor operation is controlled as a state transition between the following stages: Stop, Bootstrap, Positioning, Forced Commutation, Change-up, Steady, Brake by Short-Circuit, and Protection.

In the main stages, transition is made by the motor operation start command in the following order: Positioning (Initposition), Forced Commutation (Force), Change-up (Change_up), and Steady (Steady_A). The sub-stages have steps starting from Step0 to StepEnd, and when the sub-stage is in StepEnd, the main stages transition and the sub-stages start with Step0. When a motor abnormality is detected, transition is made to Protection Stop Emergency.

10.6.1 Status Transfer Processing Function (C_Control_Ref_Model)

10.6.1.1 Syntax

void C_Control_Ref_Model(vector_t* const _motor) Without ENC_Z state transition

void C_Control_Ref_Model_ENC(vector_t* const _motor) With ENC_Z state transition

Parameter:

 _motor Motor Control Structure

Returned Value:

 No

10.6.1.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	usr.com_user.onoff	Control Command	---	
	drv.state.all	Error Status	---	
	drv.Z_detect	Z Pulse Detection	---	Used only for ENC_Z state transition
I/O	stage.main	Main Stage	---	
	stage.sub	Sub Stage	---	
	usr.com_user_1.onoff	Previous Control Command	---	
Output	drv.phi_omega_div_emg_f	EMG flag for Flux Observer	---	Flux Observer Method

10.6.1.3 Process

Monitor the control command given from the application and the current statuses and executes the status transferring. Each status is separated into the more detailed sub statuses. The transfer of substages is executed within the processing function for each stage instead of within the stage transfer processing function.

In the case of being with ENC_Z state transition, when a Z-pulse is detected, the stage transitions from Forced Commutation to Steady.

Note: ENC_Z state transition is made when the encoder is enabled, and 3-shunt is adopted.

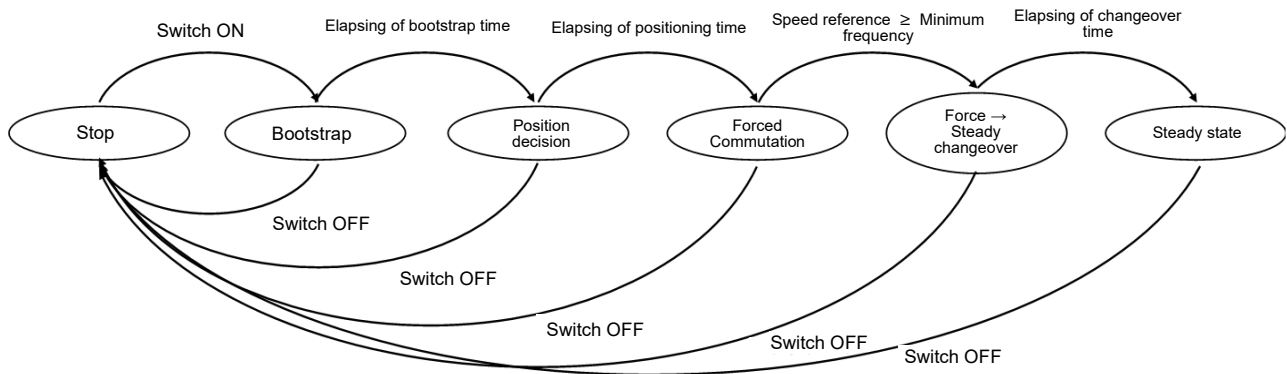


Figure 10.1 State transition chart of Motor control

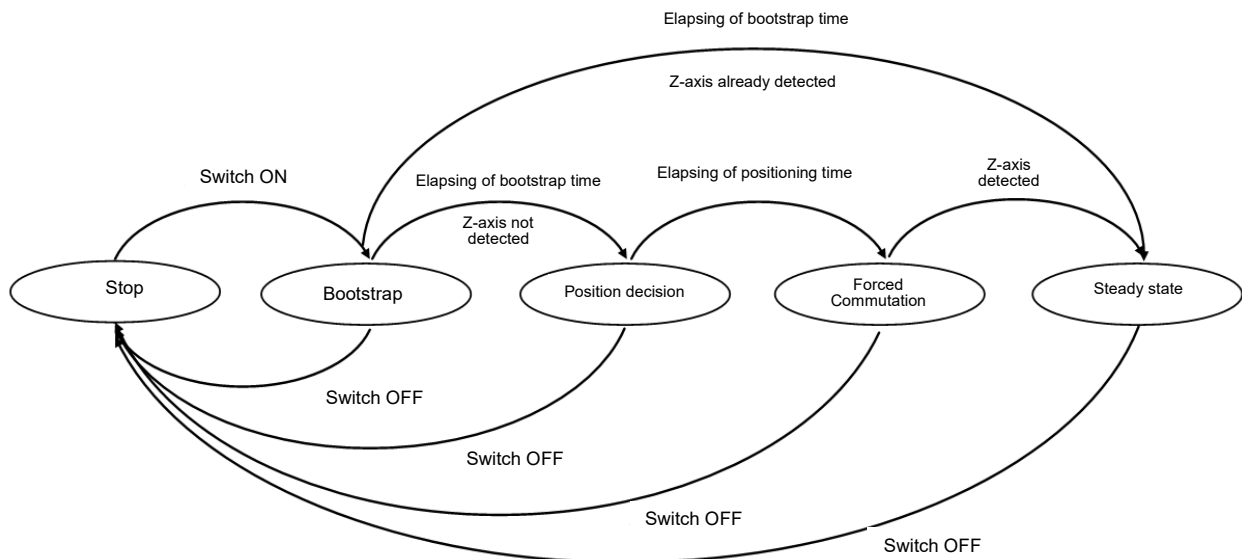


Figure 10.2 State transition chart of Motor control (Encoder Control)

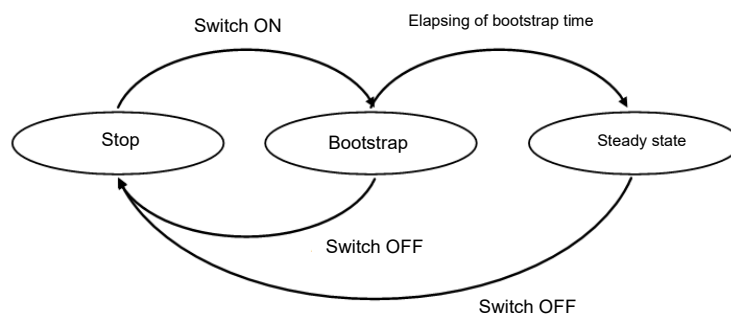


Figure 10.3 Stage transition of motor control (Hall sensor and encoder control)

10.6.2 Motor Control Common Processing Function (C_Common)

10.6.2.1 Syntax

```
void C_Common(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.2.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	usr.com_user.encoder	Encoder Control Command	---	
	usr.com_user.modul	Modulation Method Control Command	---	Two-phase or Three-phase Modulation
	para.chkpls	Current Detection Protection Duty Width Setup Value	---	
	drv.Vd	d-Axis Voltage	Q32	
	drv.Vq	q-Axis Voltage	Q32	
	drv.Vdc	Power Supply Voltage	Q15	
Output	drv.command.encoder	Encoder Drive Command	---	
	drv.command.modul	Modulation Method Drive Command	---	Two-phase or Three-phase Modulation
	drv.chkpls	Current Detection Protection Duty Width	---	
	drv.Vdq_per	Ratio of dq-Axis Voltage against Power Supply Voltage	---	[%]

10.6.2.3 Process

A common process to various motor control statuses is executed.

Perform Shift PWM Control(C_ShiftPWM_Control).

Vdq calculation (Cal_Vdq) is performed to compute the ratio of Vdq against Vdc.

10.6.3 Stop Stage Function (C_Stage_Stop)

10.6.3.1 Syntax

```
void C_Stage_Stop(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.3.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	drv.shift2_mode_start	Initial Shift2 Control mode	---	
	Phi	Flux Observer Structure	---	Flux Observer Method
I/O	stage.sub	Sub Stage	---	
Output	stage.itr	Interruption Stage	---	
	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
	drv.theta_com	Electrical Angle Reference Value	Q0	
	drv.theta	Rotor Position	Q0	
	drv.omega_com	Driving Speed Reference Value	Q31	
	drv.omega	Speed	Q31	
	drv.Vd_com	d-Axis Voltage Reference Value	Q31	Only Vector Control Using Software
	drv.Vq_com	q-Axis Voltage Reference Value	Q31	Only Vector Control Using Software
	drv.Id_com	d-Axis Current Reference Value	Q31	
	drv.Iq_com	q-Axis Current Reference Value	Q31	
	drv.theta_phi_rate	Weighting between Forced Commutation and Sensorless Angle	Q0	Flux Observer Method
	drv.force_rate	Forced Commutation Angle Ratio	Q0	Flux Observer Method
	drv.phi_tq_ave2	Motor Output Torque Average2	Q31	Flux Observer Method
	drv.phi_omega_ave	Flux Observer Estimated Speed Average	Q31	Flux Observer Method
	drv.shift2_change	Shift2 switching timing	---	For Shift 2
	drv.Vd_I	d-axis voltage integral value	Q31	
	drv.Vq_I	q-axis voltage integral value	Q31	

10.6.3.3 Process

Stops the motor. (Stops the PWM output)

10.6.4 Bootstrap Stage Function (C_Stage_Bootstrap)

10.6.4.1 Syntax

```
void C_Stage_Bootstrap(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.4.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	para.time.bootstp	Bootstrap Time	Q0	* MainLoopPrd(s)
I/O	stage.sub	Sub Stage	---	
	stage_counter	Stage Counter	Q0	* MainLoopPrd(s)
Output	stage.itr	Interruption Stage	---	
	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)

10.6.4.3 Process

Outputs the waveform of upper phase All OFF and Lower phase All ON and charges the bootstrap capacitor.

Continues this process for the Bootstrap Time. Determines the charging amount for the capacitor based on the Bootstrap Time

Controls the bootstrap status by separating it into the following sub-stages.

a) Initial Status

Initial setup of bootstrap status.

b) Time Lapse Standby Stage

Wait for the lapse of specified bootstrap time and transfers to the positioning stage.

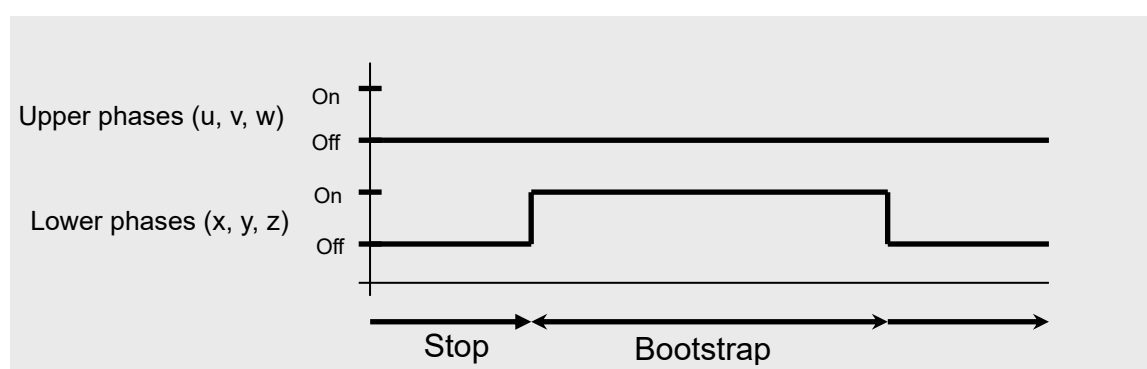


Figure 10.4 Bootstrap Time

10.6.5 Positioning Stage Function (C_Stage_Initposition)

10.6.5.1 Syntax

```
void C_Stage_Initposition(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.5.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	boot_type	Starting Type	---	
	usr.Id_st_user	Starting Id-Current	Q15	
	usr.lambda_user	Initial Rotor Position	Q0	
	drv.shift2_mode_start	Initial Shift2 Control mode	---	For Shift 2
	para.vd_pos	Positioning Reference Voltage	Q31	
	para.time.initpos	Positioning Time	Q0	* MainLoopPrd(s)
	para.time.initpos2	Positioning Status Standby Time	Q0	* MainLoopPrd(s)
I/O	stage.sub	Sub Stage	---	
	stage_counter	Stage Counter	Q0	* MainLoopPrd(s)
	drv.Vd_out	Output Voltage	Q31	Enabled only during voltage drive
	drv.Id_com	d-Axis Current Reference Value	Q31	
Output	stage.itr	Interruption Stage	---	
	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
	drv.lq_com	q-Axis Current Reference Value	Q31	
	drv.omega_com	Driving Speed Reference Value	Q31	
	drv.theta_com	Electrical Angle Reference Value	Q0	
	drv.shift2_mode	Shift2 Control mode	---	
	usr.com_user.modul	Modulation method control command	---	2 or 3-phase modulation

10.6.5.3 Process

Fixes the rotor to the initial position.

While fixing θ to the Initial Position, ω to 0 and I_q to 0, gradually increases I_d from 0. Continues this process during the Positioning Time and finally I_d reaches the Start Id Current. Determines in advance the increment of I_d per unit time based on the Positioning Time and the Start Id Current. After I_d reaches the Start Id Current and after the lapse of Positioning Standby Time, the stage will be transferred to the next.

When Initial Shift2 Control Mode is Shift2 Mode Setting, initial the setting for Shift PWM2.

The positioning stages will be separated into the following sub stages for controlling.

a) Initial Status

Initial setup of positioning stages.

b) Id Increasing Stage

Id will be gradually increased to the setup value.

10.6.6 Forced Commutation Stage Function (C_Stage_Force)

10.6.6.1 Syntax

```
void C_Stage_Force(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.6.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	boot_type	Starting Type	---	Current or Voltage
	usr.Id_st_user	Starting Id-Current	Q15	
	usr.omega_user	Controller Target Speed	Q31	
	para.omega_v2i	Current Control Changeover Speed	Q15	Enabled only during voltage drive
	para.spd_coef	Output Voltage Factor	Q15	Enabled only during voltage drive
	para.vd_pos	Positioning Output Voltage	Q31	Enabled only during voltage drive
	para.omega_min	Forced Commutation End Speed	Q15	
	para.sp_ud_lim_f	Drive Speed Increase/Decrease Limit	Q31	
I/O	stage.sub	Sub Stage	---	
	drv.omega_com	Driving Speed Reference Value	Q31	
Output	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
	stage.itr	Interruption Stage	---	
	drv.lq_com	q-Axis Current Reference Value	Q31	
	drv.Id_com	d-Axis Current Reference Value	Q31	
	drv.Vd_out	Output Voltage	Q31	Enabled only during voltage drive

10.6.6.3 Process

Starts the rotation of rotor. In this stage, a rotation magnetic field is forcibly applied instead of the feedback processing with vector control, and the rotor will follow it and be rotated.

The drive speed reference, ω_{com} , will be gradually increased while fixing the I_d to Start I_d Current and I_q to 0. Acquire θ from ω_{com} ($\theta = \omega_{com} t$). This process will be continued until ω reaches the Forced Commutation End Speed.

The Drive Target Speed will be increased with a constant increment for approaching Control Target Speed. The Estimated Speed reaches ω .

10.6.7 Forced Steady Changeover Stage Function (C_Stage_Change_up)

10.6.7.1 Syntax

```
void C_Stage_Change_up(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.7.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	usr.Id_st_user	Starting Id-Current	Q15	
	usr.lq_st_user	Starting lq-Current	Q15	
	usr.omega_user	Controller Target Speed	Q31	
	para.delta_lambda	Current Changeover Phase for Change-up	Q0	
	para.sp_ud_lim_f	Drive Speed Increase/Decrease Limit	Q31	
	para.time.go_up	Wait Time after Change-up	Q0	* MainLoopPrd(s)
	drv.Id_com2	d-axis current Command Value2	Q31	Flux Observer Method
I/O	stage.sub	Sub Stage	---	
	stage_counter	Stage Counter	Q0	* MainLoopPrd(s)
	drv.omega_com	Driving Speed Reference Value	Q31	
Output	stage.itr	Interruption Stage	---	
	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
	drv.Id_com	d-Axis Current Reference Value	Q31	
	drv.lq_com	q-Axis Current Reference Value	Q31	

10.6.7.3 Process

Decreases Id to 0 and increases lq to Start lq Current and controls the orientation of magnetic field so that the magnetic field and the rotor form a right angle.

In other words, generates the torque component.

Acquire ω and θ through the position estimation computation. The Driving Speed Reference Value will be increased with a constant increment for approaching Control Target Speed However, the Estimated Speed will not be used for control because the speed control is not conducted in this stage.

The forced steady changeover stage will be controlled by separating it into the following substages.

a) Initial Status

Initial setup of forced steady changeover stages.

b) Id and Iq Changeover Stages

Gradually decreases Id to 0 and gradually increases Iq to the specified value simultaneously. The increasing/decreasing curves are not linear but follows the triangular function curve. After the completion of changeover, the stage will be transferred to the time lapse standby.

c) Time Lapse Standby Stage

Waits for the lapse of the specified forced steady changeover time and transfers to the steady stage.

10.6.8 Steady Stage Function (C_Stage_Steady_A)

10.6.8.1 Syntax

```
void C_Stage_Steady_A(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.6.8.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
	usr.omega_user	Controller Target Speed	Q31	
	para.sp_up_lim_s	Drive Speed Increase Limit	Q31	
	para.sp_dn_lim_s	Drive Speed Decrease Limit	Q31	
	drv.shift2_mode_start	Initial Shift2 Control mode	Q0	For Shift 2
	para.spwm2_threshold	Normal-to-Shift2 switching speed	Q15	
	para.spwm2_threshold_hys	Normal-to-Shift2 switching speed Hysteresis	Q15	For Shift 2
	para.spwm2_rate_threshold	Shift PWM2 modulation rate threshold	Q0	For Shift 2
	para.spwm2_rate_threshold_hys	Shift PWM2 modulation rate thresholdHysteresis	Q0	For Shift 2
	detect_type	Position Detection Method	---	Flux Observer Method
	para.phi.Id_CH_ini	Id application multiplier at low speed	---	Flux Observer Method
	para.phi.Id_CH_ini_Hz	Id application speed at low speed	Q15	Flux Observer Method
	para.phi.SOGI_G_low_speed	SOGI GAIN(low-speed)	---	Flux Observer Method
	para.phi.SOGI_G_high	SOGI GAIN(high-speed)	---	Flux Observer Method

	para.omega_min	End of forced commutation Speed	Q15	Flux Observer Method
	para.omega_min2	Steady-state forced commutation switching speed	Q15	Flux Observer Method
	drv.Id_com2	d-axis current Command Value2	Q31	Flux Observer Method
	usr.Id_st_user2	Starting current	Q15	Flux Observer Method
	usr.lam1la_user	Initial Rotor Position	Q0	When the hall sensor and encoder control are enabled.
I/O	stage.sub	Sub Stage	---	
	drv.omega_com	Driving Speed Reference Value	Q31	
	para.phi.SOGI_G	SOGI Control GAIN	Q31	Flux Observer Method
	drv.shift2_mode	Shift 2 Control Mode	---	For Shift 2
Output	drv.vector_cmd	Vector Control Command	Q0	(Refer to 10.2.2.)
	stage.itr	Interruption Stage	---	
	drv.Id_com	d-Axis Current Reference Value	Q31	
	drv.shift2_change	Shift2 switching timing	---	For Shift 2

10.6.8.3 Process

Executes the process of steady stage.

The Driving Speed Reference Value will be increased with a constant increment for approaching Control Target Speed.

(1 shunt)

When the switching setting is Speed detection:

If the drive speed command value > (Normal to Shift2 switching speed), the motor is driven with Normal PWM.

If the drive speed command value ≤ (Normal to Shift2 switching speed), the motor is driven with Shift PWM2.

Note: Switching of Normal PWM and Shift PWM, use the description of Shift PWM Control(C_ShiftPWM_Control) for reference.

10.6.9 Protection Stage Function (C_Stage_Emergency)

10.6.9.1 Syntax

```
void C_Stage_Emergency(vector_t* const _motor)
```

Parameter:

 _motor Motor Control Structure

Returned Value:

 No

10.6.9.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	stage.main	Main Stage	---	
I/O	stage.sub	Sub Stage	---	
Output	drv.vector_cmd	Vector Control Command	---	(Refer to 10.2.2.)
	stage.itr	Interruption Stage	---	

10.6.9.3 Process

When an overcurrent occurs, the stage will be transferred to this.

When a hardware overcurrent is detected, the motor drive outputs u, v, w, x, y, and z are all Hi-z.

When a software overcurrent is detected, the motor drive outputs u, v, w, x, y, and z are all OFF.

The rotor will be rotated by the inertia.

This stage will be maintained until the overcurrent status restoration process is executed.

10.6.10 Shift PWM Control (C_ShiftPWM_Control)

10.6.10.1 Syntax

```
static void C_ShiftPWM_Control(vector_t* const _motor)
```

Argument:

_motor Motor control structure

Return value:

None

10.6.10.2 Variables

Direction	Name	Meaning	Q Format	Note
Input	shunt_type	Shunt type	---	
	stage.itr	Interrupt stage	---	
	usr.com_user.spwm	Shift PWM control method	---	
	drv.omega_com	Drive speed command value	Q31	
	para.spwm_threshold	Shift PWM switching speed	Q15	
	para.spwm_threshold_hys	Shift PWM switching speed hysteresis	Q15	
Output	drv.command.spwm	Shift PWM drive command	---	

10.6.10.3 Processing contents

This control is valid only when the VE and the 1-shunt resistor method are used.

This function controls the ON/OFF of the Shift PWM mode.

The Shift PWM drive method is determined by the Shift PWM control method, the Interrupt stage, and the target speed. Table shows each condition in the sample software.

Table 10.4 Shift PWM drive condition (Switching setting: speed)

Shift PWM Control usr.com_user.spwm	Interrupt Stage stage.itr	Target Speed drv.omega_com	Shift PWM Drive drv.command.spwm
OFF (0)	All	All	OFF (0)
ON (1)	Stop	All	OFF (0)
	Emergency	All	OFF (0)
	ciInitposition_i Force_i Change_up Steady_A	Target speed >= Shift switching speed drv.omega_com >= para.spwm_threshold	OFF (0)
		Target speed >= Shift switching speed drv.omega_com < para.spwm_threshold	ON (1)

10.7 Motor Drive Function

10.7.1 Explanation of Terms

10.7.1.1 3-phase Modulation

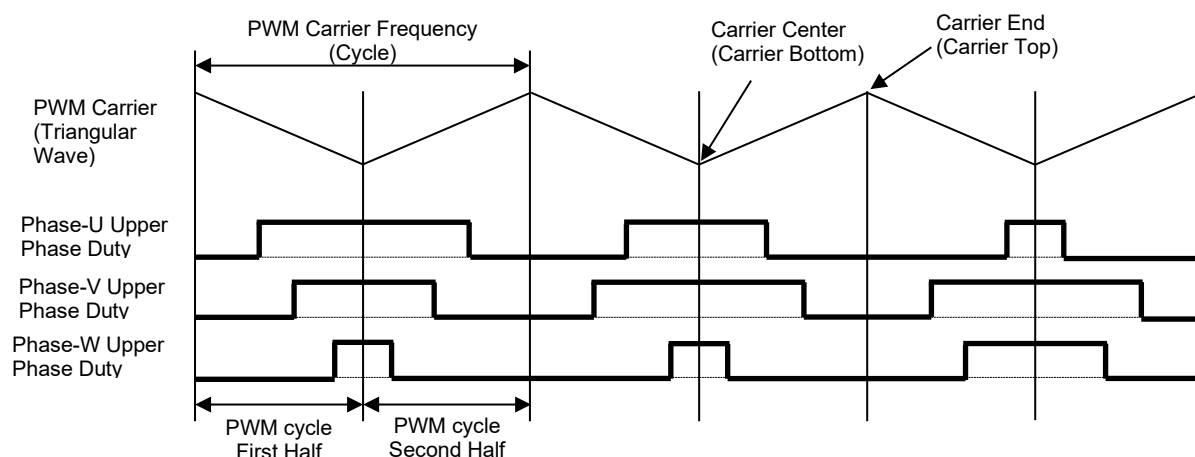


Figure 10.5 3-phase Modulation

10.7.1.2 2-phase Modulation

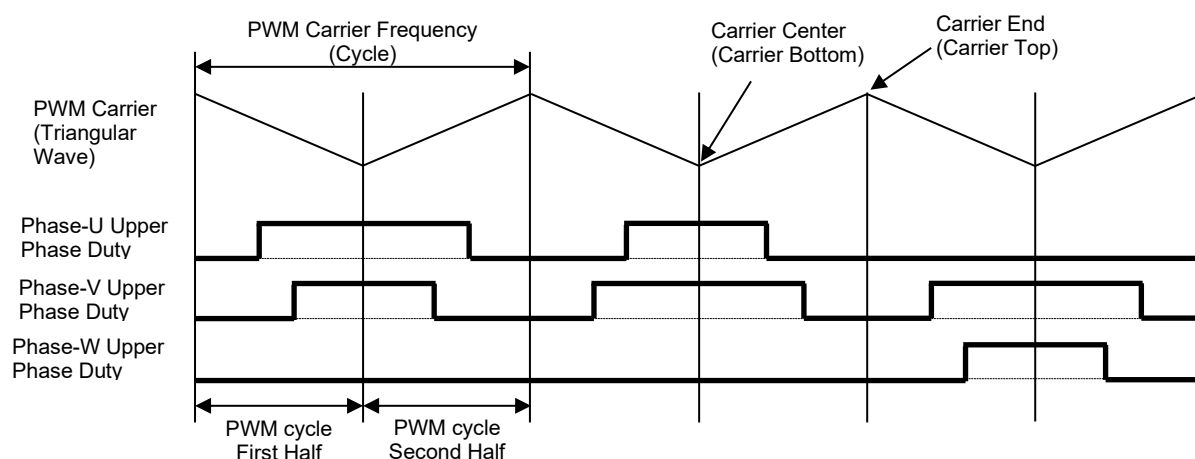


Figure 10.6 2-phase Modulation

10.7.2 Acquisition of Motor Current, Power Supply Voltage (D_GetMotorCurrentPowerVolt)

10.7.2.1 Syntax

```
void D_GetMotorCurrentPowerVolt (vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.7.2.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.Sector1	Previous Sector	Q0	0 to 5
	para.TrqPosMd	Current Detection Position Mode	---	3-shunt 1-shunt first half 1-shunt second half
	drv.ADxREG0	AD Conversion Result Register Address	---	
	drv.ADxREG1	AD Conversion Result Register Address	---	
	drv.ADxREG2	AD Conversion Result Register Address	---	
	drv.ADxREG3	AD Conversion Result Register Address	---	
	drv.lao_ave	Phase-U Zero Current Average	Q15	3-shunt only
	drv.lbo_ave	Phase-V Zero Current Average	Q15	3-shunt only
	drv.lco_ave	Phase-W Zero Current Average	Q15	3-shunt only
	drv.lco_ave	Zero Current Average	Q15	1-shunt only
	stage.itr	Interruption Stage	---	
	drv.idetect_error	Current Detection Status	---	
	drv.shift2_mode	Shift 2 Control Mode	---	
	drv.shift2_change_bf	Previous Shift2 switching timing	---	
I/O	drv.la_raw	Phase-U Current (raw data)	Q15	
	drv.lb_raw	Phase-V Current (raw data)	Q15	
	drv.lc_raw	Phase-W Current (raw data)	Q15	
Output	drv.la	Phase-U Current (detection error protection)	Q15	
	drv.lb	Phase-V Current (detection error protection)	Q15	
	drv.lc	Phase-W Current (detection error protection)	Q15	
	drv.la_adc	Phase-U Current Conversion Result	Q15	3-shunt only
	drv.lb_adc	Phase-V Current Conversion Result	Q15	3-shunt only
	drv.lc_adc	Phase-W Current Conversion Result	Q15	3-shunt only
	drv.ldc1_adc	Phase-1st Current Conversion Result	Q15	1-shunt only
	drv.ldc2_adc	Phase-2nd Current Conversion Result	Q15	1-shunt only
	drv.Vdc	Power Supply Voltage	Q15	
	drv.Vdc_adc	Power Supply Voltage Conversion Result	Q15	

10.7.2.3 Process

Acquires the AD conversion result and computes the power supply voltage and the motor current.

1. Checks the completion of AD conversion with the PMD trigger and when the conversion is complete, acquires the conversion results according to the table below.

When the conversion is not complete, continues standing by until the completion of conversion.

(Never occurs under normal conditions, but as a failsafe process, the standby process is executed.)

But when operating with Shift PWM2 in 1-shunt configuration, the value is calculated by adding an offset, and no acquisition or computation is performed at the timing of switching between Normal PWM and Shift PWM2.

2. Computes the power supply voltage and the motor current based on the acquired AD conversion results.

● Power Supply Voltage

Power Supply Voltage Conversion Result drv.Vdc_adc	AD Conversion Result 3 ADxREG3
---	-----------------------------------

As the power supply voltage is unsigned, the AD conversion result is right shifted by 1 bit and converted to the Q15 format variable.

```
drv.Vdc_adc = (q15_t)((*_motor->drv.ADxREG3 & 0xFFF0) >> 1)
```

```
drv.Vdc_adc = drv.Vdc_adc
```

● Motor Current

<Current Detection Mode: 3-shunt>

	Sector					
	0	1	2	3	4	5
Phase-U Current Conversion Result drv.la_adc	AD Conversion Result 2 ADxREG2	AD Conversion Result 1 ADxREG1	AD Conversion Result 1 ADxREG1	AD Conversion Result 0 ADxREG0	AD Conversion Result 0 ADxREG0	AD Conversion Result 2 ADxREG2
Phase-V Current Conversion Result drv.lb_adc	AD Conversion Result 0 ADxREG0	AD Conversion Result 2 ADxREG2	AD Conversion Result 2 ADxREG2	AD Conversion Result 1 ADxREG1	AD Conversion Result 1 ADxREG1	AD Conversion Result 0 ADxREG0
Phase-W Current Conversion Result drv.lc_adc	AD Conversion Result 1 ADxREG1	AD Conversion Result 0 ADxREG0	AD Conversion Result 0 ADxREG0	AD Conversion Result 2 ADxREG2	AD Conversion Result 2 ADxREG2	AD Conversion Result 1 ADxREG1

The AD conversion result when the motor is stopped is regarded as the zero current and stored in the following variables.

Phase-U Zero Current Conversion Result drv.lao_ave	Phase-U Current Conversion Result drv.la_adc
Phase-V Zero Current Conversion Result drv.lbo_ave	Phase-V Current Conversion Result drv.lb_adc
Phase-W Zero Current Conversion Result drv.lco_ave	Phase-W Current Conversion Result drv.lc_adc

The values of three-phase current will be computed in accordance with the following table based on the AD conversion result with zero current (motor stop) and the phase current conversion result.

	Sector					
	0	1	2	3	4	5
Phase-U Current drv.la	-lb- <i>lc</i>	<i>lao_ave</i> - <i>la_adc</i>	<i>lao_ave</i> - <i>la_adc</i>	<i>lao_ave</i> - <i>la_adc</i>	<i>lao_ave</i> - <i>la_adc</i>	-lb- <i>lc</i>
Phase-V Current drv.lb	<i>lbo_ave</i> - <i>lb_adc</i>	-la- <i>lc</i>	-la- <i>lc</i>	<i>lbo_ave</i> - <i>lb_adc</i>	<i>lbo_ave</i> - <i>lb_adc</i>	<i>lbo_ave</i> - <i>lb_adc</i>
Phase-W Current drv.lc	<i>lco_ave</i> - <i>lc_adc</i>	<i>lco_ave</i> - <i>lc_adc</i>	<i>lco_ave</i> - <i>lc_adc</i>	-la- <i>lb</i>	-la- <i>lb</i>	<i>lco_ave</i> - <i>lc_adc</i>

<Current Detection Mode: 1-shunt First Half and the Second Half>

Current Detection Mode: During the first half of 1-shunt, the AD conversion result is acquired at the position of the first half of the PWM cycle.

Current Detection Mode: During the second half of 1-shunt, the AD conversion result is acquired at the position of the second half of the PWM cycle.

Current Acquisition Position Conversion Result	PWM Cycle Second Half	PWM Cycle First Half
Current Conversion Result 1 drv.ldc1_adc	AD Conversion Result 0 ADREG0	AD Conversion Result 1 ADREG1
Current Conversion Result 2 drv.ldc2_adc	AD Conversion Result 1 ADREG1	AD Conversion Result 0 ADREG0

The AD conversion result when the motor is stopped is regarded as the zero current and stored in the following variables.

Zero Current Conversion Result drv.ldc0_ave	Current Conversion Result 1 drv.ldc1_adc
--	---

The values for the three-phase current are computed in accordance with the table below based on the AD conversion result, Zero Current Conversion Result, during the zero current (motor stop) and the AD conversion results at the two timings.

	Sector					
	0	1	2	3	4	5
Phase-U Current drv.la	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)	-lb- <i>lc</i>	<i>ldco_ave</i> - <i>ldc1_adc</i>	<i>ldco_ave</i> - <i>ldc1_adc</i>	-lb- <i>lc</i>	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)
Phase-V Current drv.lb	-la- <i>lc</i>	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)	-la- <i>lc</i>	<i>ldco_ave</i> - <i>ldc1_adc</i>	<i>ldco_ave</i> - <i>ldc1_adc</i>
Phase-W Current drv.lc	<i>ldco_ave</i> - <i>ldc1_adc</i>	<i>ldco_ave</i> - <i>ldc1_adc</i>	-la- <i>lb</i>	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)	-(<i>ldco_ave</i> - <i>ldc2_adc</i>)	-la- <i>lb</i>

10.7.3 Input Coordinate Conversion (D_InputTransformation)

10.7.3.1 Syntax

```
void D_InputTransformation(vector_t* const _motor)
```

Parameter:

`_motor` Motor Control Structure

Returned Value:

No

10.7.3.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.vector_cmd.F_vcomm_Idetect	Current Detection Command	---	
	drv.la	Phase-U Current	Q15	
	drv.lb	Phase-V Current	Q15	
	(drv.lc)	Phase-W Current	Q15	
	drv.theta	Rotor Position	Q0	[deg/360]
	para.pos.ctrlprd	Vector Control Cycle	Q0	
	drv.omega	Estimated Speed	Q15	
	drv.idetect_error	Current Detection Status	---	0:Detection Enabled 1:Detection Disabled
	drv.shift2_change_bf	Previous Shift2 switching timing	---	For Shift 2
	drv.shift2_mode	Shift 2 Control Mode	---	For Shift 2
Output	drv.lalpha	α -Axis Current	Q15	
	drv.lbeta	β -Axis Current	Q15	
	drv.ld	d-Axis Current	Q15	
	drv.lq	q-Axis Current	Q15	

10.7.3.3 Process

Three-phase currents (Ia, Ib, Ic) are converted to dq-axis currents.

- Through 10.7.4 Clarke Transformation, three-phase currents (Ia, Ib, Ic) are converted to two-phase currents (I_α , I_β).
- Through 10.7.5 Park Transformation, two-phase currents (I_α , I_β), which are static coordinates, are converted to dq-axis conversions, which are rotational coordinates.

For the rotor position used for Park Transformation, since the actual rotor position is advanced in relation to the time it was computed in the position estimation processing, θ_{est} predicted based on the speed ω and computing cycle is used. $\theta_{est} = \theta + \text{speed } \omega \times \text{Vector Control Cycle}$

When the current cannot be detected correctly or when switching between Nomarl PWM and Shift PWM2, no conversion is performed and Id and Iq are not updated.

10.7.4 Clarke Transformation (E_Clarke)

10.7.4.1 Syntax

```
void E_Clarke( q15_t _iu,
               q15_t _iv,
               q15_t _iw,
               q15_t* _ialpha,
               q15_t* _ibeta)
```

Parameter:

_iu	Phase-U Current
_iv	Phase-V Current
_iw	Phase-W Current
_ialpha	α-Axis Current Storage Address
_ibeta	β-Axis Current Storage Address

Returned Value:

No

10.7.4.2 Process

The three-phase currents (I_u , I_v , I_w) are converted to two-phase (I_α , I_β).

I_α and I_β are computed using the following computation formulas:

$$I_\alpha = \frac{2}{3} \times (I_u \times \cos 0 + I_v \times \cos 120 + I_w \times \cos 240) = \frac{2}{3} \times \left(I_u - \frac{1}{2} I_v - \frac{1}{2} I_w \right)$$

$$I_\beta = \frac{2}{3} \times (I_u \times \sin 0 + I_v \times \sin 120 + I_w \times \sin 240) = \frac{2}{3} \times \left(\frac{\sqrt{3}}{2} I_v - \frac{\sqrt{3}}{2} I_w \right)$$

Since the amplitude becomes 3/2 time bigger when converting the 3 phase currents to the 2 phase $\alpha\beta$ axis currents, 2/3 is a coefficient to equalize the amplitude.

The sum of the three phase currents is 0 ($I_u + I_v + I_w = 0$). Then,

$$I_\alpha = I_u$$

$$I_\beta = (I_u + 2I_v)/\sqrt{3}$$

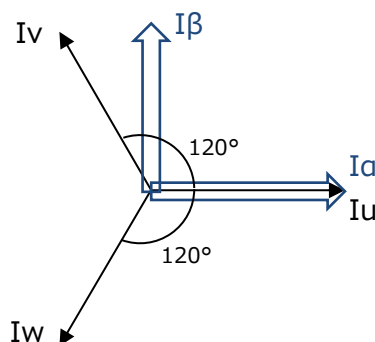


Figure 10.7 Clarke Transformation

10.7.5 Park Transformation (E_Park)

10.7.5.1 Syntax

```
void E_Park( q15_t _ialpha,
            q15_t _ibeta,
            uint16_t _theta,
            q15_t* _id,
            q15_t* _iq)
```

Parameter:

_ialpha	α -Axis Current I_α
_ibeta	β -Axis Current I_β
_theta	Rotor Position θ : $0 \leq \text{Position} < 360^\circ$ (0 to 0xffff)
_id	d-Axis Current I_d Storage Address
_iq	q-Axis Current I_q Storage Address

Returned Value:

No

10.7.5.2 Process

Conversion from the static coordinate of $\alpha\beta$ -axes to the dq-axes of rotational coordinate.

I_d and I_q are computed using the following computation formulas:

$$I_d = I_\alpha \times \cos\theta + I_\beta \times \sin\theta$$

$$I_q = I_\alpha \times (-\sin\theta) + I_\beta \times \cos\theta$$

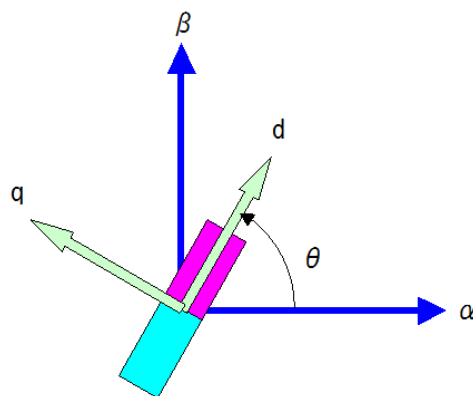


Figure 10.8 Park Transformation

10.7.6 Induced voltage Position Estimation Function (D_Detect_Rotor_Position)

10.7.6.1 Syntax

```
void D_Detect_Rotor_Position(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.7.6.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.command.encoder	Encoder Drive Command	---	
	drv.vector_cmd.F_vcomm_Edetect	Induced Voltage Control Command	---	
	drv.vector_cmd.F_vcomm_omega	Estimated Speed Control Command	---	
	drv.vector_cmd.F_vcomm_theta	Estimated Rotor Position Control Command	---	
	drv.Id	d-Axis Current	Q15	
	drv.Iq	q-Axis Current	Q15	
	drv.omega_com	Driving Speed Reference Value	Q31	
	drv.theta_com	Electrical Angle Reference Value	Q0	
	drv.Vd	d-Axis Voltage	Q31	
	para.motor.Lq	Motor q-Axis Inductance	Q12	
	para.motor.r	Motor Winding Resistance	Q12	
	para.pos.ctrlprd	Position Estimation Control Cycle	Q0	
	para.pos.ki	Position Estimation Integration Gain	Q15	Q12 Support
	para.pos.kp	Position Estimation Proportional Gain	Q15	Q12 Support
I/O	drv.Ed	d-Axis Induced Voltage	Q15	
	drv.Ed_I	d-Axis Induced Voltage Integrated Value	Q31	
	drv.Ed_PI	d-Axis Induced Voltage PI Value	Q31	
	drv.omega	Estimated Speed	Q31	
Output	drv.theta	Rotor Position	Q0	

10.7.6.3 Process

The PI control is executed by regarding the estimate speed west of motor drive signal as the amount of operation and the d-axis induced voltage E_d as the amount of control.

For information, the target value for E_d is always 0. Accordingly, the deviation is $-E_d$.

The rotor position θ (angle) is acquired by integrating the estimated speed ω_{est} acquired through the PI control.

For the estimated speed ω_{est} , when F_vcomm_omega is CLEAR, the driving speed reference value ω_{com} is used.

The equivalent circuit equation with regard to the d-axis of motor is expressed as below:

$$V_d = R I_d + L_d \times p I_d - \omega_{est} \times L_q \times I_q + E_d$$

($p = d/dt$, $I_d \approx \text{constant}$, then regarded as $p I_d = 0$)

V_d : Motor Applied Voltage I_d, I_q : Motor Current

ω_{est} : Estimated Angular Speed

R : Resistance L_d, L_q : Inductance

Consequently, the induced voltage E_d of the d-axis is acquired using the following computation formula:

$$E_d = V_d - R \times I_d + \omega_{est} \times L_q \times I_q$$

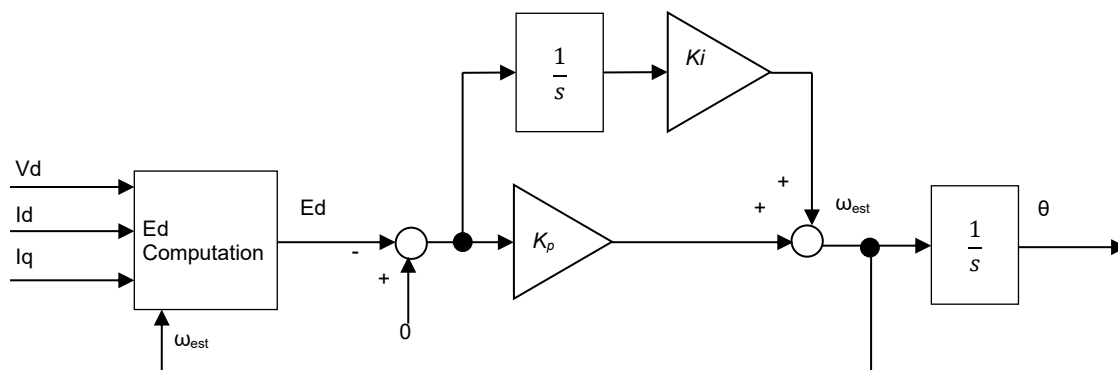


Figure 10.9 Position Estimation Block Diagram based on Induced Voltage E_d of the d-Axis

10.7.7 Flux Observer Position Estimation Function (D_Detect_Flux_Rotor_Position)

10.7.7.1 Syntax

```
void D_Detect_Flux_Rotor_Position (vector_t* const _motor)
```

Argument:

`_motor` Motor Control Structure

Return Value:

None

10.7.7.2 Variable

Direction	Name	Details	Q Format	Notes
Input	drv.idetect_error	Current Detection Status	---	0:Detectable 1:Not Detectable
	drv.shift2_change_bf	Previous Shift2 switching timing	---	
	drv.omega_com	Speed command value	Q31	
	para.phi.phi_prd	Flux Observer Control Period	Q0	
	drv.vector_cmd.F_vcomm_Edetect	Induced Voltage Control Command	---	
	drv.vector_cmd.F_vcomm_omega	Estimated Speed Control Command	---	
	drv.command.encoder	Encoder Drive Command	---	
	para.phi.phi_omega_div_emg	Speed EMG judgment threshold for Flux Observer	Q0	
	drv.vector_cmd.F_vcomm_theta	Estimated Rotor Position Control Command	---	
	para.phi.enable_theta_phi_adj	Angle adjustment enable flag	---	
	para.phi.theta_phi_adj_tq_th	Angle Adjustment ratio	---	
	para.phi.omega_phi_force_end	Forced commutation phase2 end speed	Q15	
In/output	drv.phi_omega_bf	Previous Flux Observer Speed	Q31	
	drv.theta_phi	Flux Observer Angle	Q0	
	drv.phi_omega	Flux Observer Estimated Speed	Q31	
	drv.phi_omega_ave	Flux Observer Estimated Speed Average	Q31	
	drv.phi_omega_div	Previous and Current Flux Observer Speed Difference	Q15	
	drv.phi_tq_ave2	Motor Output Torque Average2	Q31	
	drv.theta_phi2	Corrected Flux Observer Angle	Q0	
	drv.theta_phi_rate	Weighting between Forced Commutation and Sensorless Angle	Q0	
	drv.force_rate	Forced Commutation Angle Ratio	Q0	
Output	drv.theta_phi_bf	Previous Flux Observer Angle	Q0	
	drv.theta_phi_ie	Previous Flux Observer Angle	Q0	
	drv.omega	Estimated Speed	Q31	
	state_omega_type	Stage for Flux Observer Speed	---	
	drv.phi_omega_div_emg_f	EMG flag for Flux Observer	---	
	state_theta_type	Stage for Flux Observer Angle	---	

10.7.7.3 Processing Details

Using Flux Observer control, the estimated angle and estimated speed are calculated. If the motor phase currents cannot be detected, the angle is calculated from the previous speed average and the control period. Additionally, the estimated angle is corrected using the torque angle generated by the load torque (this correction can be enabled or disabled).

10.7.8 Encoder Control Function (H_Encoder)

10.7.8.1 Syntax

```
void H_Encoder(vector_t* const _motor, TSB_EN_TypeDef* const ENx)
```

Parameter:

<code>_motor</code>	Motor Control Structure
<code>ENx</code>	ENC Address

Returned Value:

No

10.7.8.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.command.encoder	Encoder Drive Command	---	
	drv.vector_cmd.F_vcomm_omega	Estimated Speed Control Command	---	
	drv.vector_cmd.F_vcomm_theta	Estimated Rotor Position Control Command	---	
	drv.omega_com	Driving Speed Reference Value	Q31	
	drv.theta_com	Electrical Angle Reference Value	Q0	
	para.enc.ctrprd	Encoder Control Cycle	Q16	
	para.enc.deg_adjust	Electrical Angle Adjustment	Q0	
	para.enc.pls2omega	Computation factor from the number of pulses to the speed	Q15	
	para.enc.pls2theta	Computation factor from the number of pulses to the angle	Q32	
	para.enc.plsnum	Number of encoder pulses	Q0	
I/O	drv.EnCnt	Encoder Counter Reading	Q0	
	drv.EnCnt_dev	Encoder Counter Deviation	Q0	
	drv.EnCnt1	Encoder Counter Previous Value	Q0	
	drv.omega_enc	Encoder Speed	Q15	
	drv.omega_enc_ave	Encoder Average Speed	Q31	
	drv.omega_enc_raw	Encoder Speed	Q15	
	drv.theta_enc	Encoder Angle	Q0	
Output	drv.omega	Speed	Q31	
	drv.theta	Rotor Position	Q0	

10.7.8.3 Process

Reads the number of incremental encoder pulses and processes the calculation of rotor position (angle) θ and speed ω .

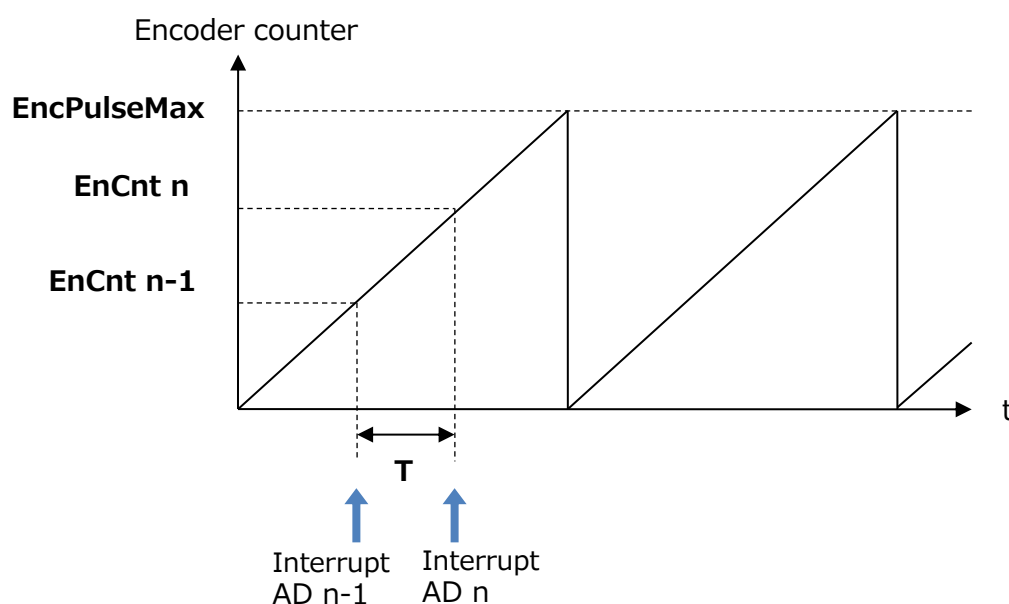


Figure 10.10 Computation of Position and Speed using Encoder Pulse

Reads the number of pulses at every AD conversion completion interrupt and computes the following:

Computes θ using the formula below based on the current encoder pulse counter reading.

$$\theta = EnCnt_n \times (360^\circ / EncPulseMax) \times (Pole/2)$$

Computes the speed ω using the formula below based on the difference of the encoder pulse counter reading of previous (n-1) and current (n).

$$\omega = \{(EnCnt_n - EnCnt_{n-1}) \times (360^\circ / (EncPulseMax / (Pole/2)))\} / T$$

EnCntn	Current Encoder Counter Reading
EnCntn-1	Previous Encoder Counter Reading
EncPulseMax	Number of Encoder Pulses [ppr] x Multiplier (4)
Pole	Number of poles
θ	Angle [deg.]
ω	Speed [Hz]
T	Speed Computing Cycle [s]

10.7.9 Hall sensor and Encoder control function (H_HallCon H_Hall_Encoder)

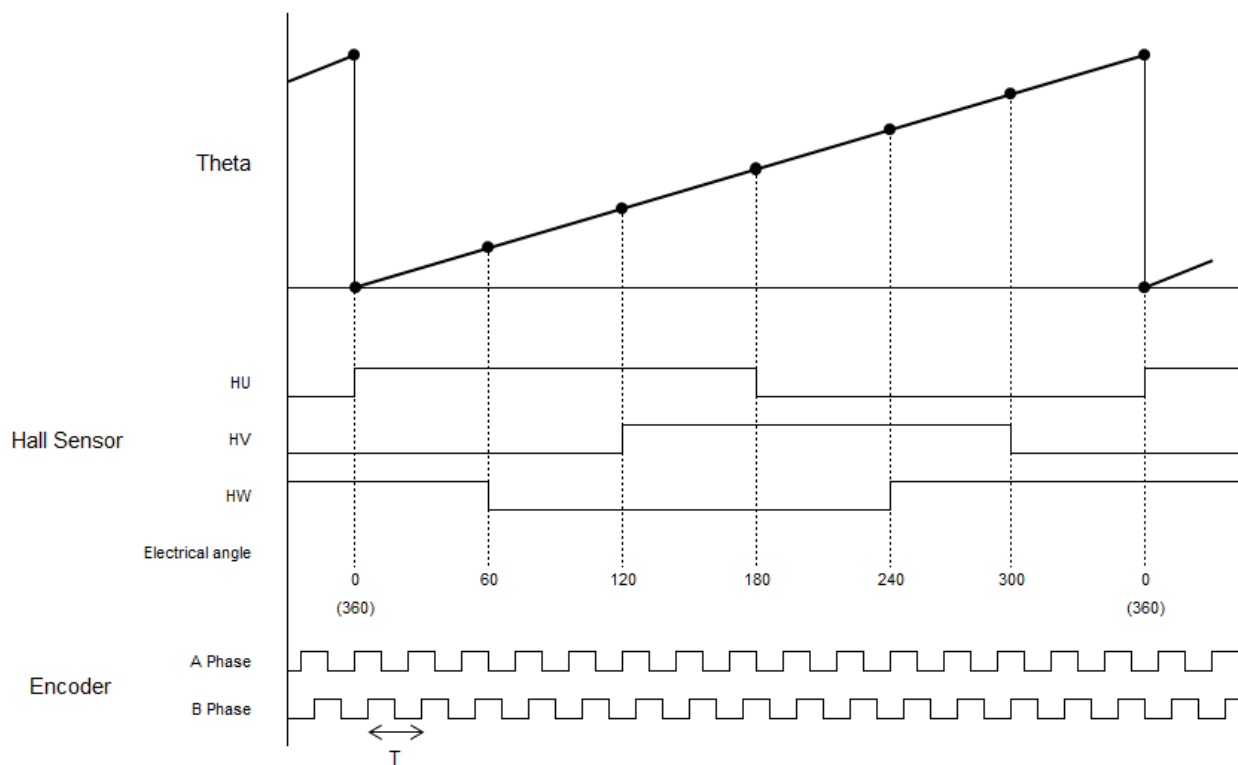


Figure 10.11 Angle detection control before detection encoder Z-signal

1. When the reset of MCU is released, a motor angle is detected by the hall IC. (Every 60 [deg])
2. Until the encoder's Z phase is detected, a motor angle is complemented by the encoder's A and B phases between hall IC signals.
3. After the Z phase of the encoder is detected, a motor angle is detected by the encoder's A, B and Z phases.

10.7.9 Speed Control Function (D_Control_Speed)

10.7.9.1 Syntax

```
void D_Control_Speed(vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.7.9.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.vector_cmd.F_vcomm_current	Current Reference Control Command	---	
	drv.id_com	d-Axis Current Reference Value	Q31	
	drv.iq_com	q-Axis Current Reference Value	Q31	
	drv.omega	Estimated Speed	Q31	
	drv.omega_com	Driving Speed Reference Value	Q31	
	para.id_lim	d-Axis Current Limit	Q31	
	para.iq_lim	q-Axis Current Limit	Q31	
	para.spd.ki	Speed Control Integration Gain	Q15	Q12 Support
I/O	para.spd.kp	Speed Control Proportional Gain	Q15	Q12 Support
	drv.iq_ref_i	q-Axis Current Integrated Value	Q31	
Output	drv.omega_dev	Speed Deviation	Q15	
	drv.id_ref	d-Axis Current Standard Value	Q15	
	drv.iq_ref	q-Axis Current Standard Value	Q15	

10.7.9.3 Process

Executes the PI control by regarding the output frequency ω as the controlled amount and the q-axis current I_q as the operated amount.

Determines the d-axis and q-axis current standard values based on the deviation of the speed reference and the actual speed.

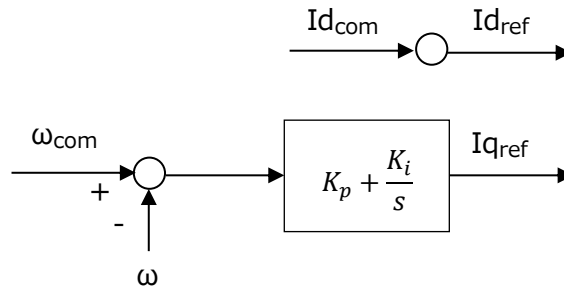


Figure 3.12 Speed Control Block Diagram

10.7.10 Current Control Function (D_Control_Current)

10.7.10.1 Syntax

```
void D_Control_Current(vector_t* const _motor)
```

Parameter:

`_motor` Motor Control Structure

Returned Value:

No

10.7.10.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.vector_cmd.F_vcomm_volt	Voltage Reference Control Command	---	
	stage.itr	Interruption Stage	---	
	drv.Id_ref	d-Axis Current Standard Value	Q15	
	drv.Iq_ref	q-Axis Current Standard Value	Q15	
	drv.Id	d-Axis Current	Q15	
	drv.Iq	q-Axis Current	Q15	
	drv.Vd_com	d-Axis Voltage Reference Value	Q31	
	drv.Vq_com	q-Axis Voltage Reference Value	Q31	
	drv.Vd_out	Output Voltage		Enabled only during voltage drive
	para.crt.dkp	d-Axis Current Control Proportional Gain	Q15	Q12 Support
	para.crt.dki	d-Axis Current Control Integration Gain	Q15	Q12 Support
	para.crt.qkp	q-Axis Current Control Proportional Gain	Q15	Q12 Support
	para.crt.qki	q-Axis Current Control Integration Gain	Q15	Q12 Support
	drv.shift2_mode	Shift 2 Control Mode	---	
	drv.Vd_lim_shift2	d-axis voltage limit value	Q31	
	drv.Vq_lim_shift2	q-axis voltage limit value	Q31	
I/O	drv.Vd_I	d-Axis Voltage Integrated Value	Q31	
	drv.Vq_I	q-Axis Voltage Integrated Value	Q31	
Output	drv.Vd	d-Axis Voltage	Q31	
	drv.Vq	q-Axis Voltage	Q31	

10.7.10.3 Process

Determines the d-axis and q-axis voltages based on the deviation of the current reference and the measured current. When the Voltage Reference Control Command is SET, calculates the d-Axis Voltage and q-Axis Voltage through the following PI control, and when it is CLEAR, adopts the d-Axis Voltage Integrated and q-Axis Voltage Integrated Values as the reference values. Executes the PI control by regarding q-axis current I_q as the controlled amount and the q-axis voltage V_q as the operated amount.

Note: In Shift 2 mode, a limit is applied.

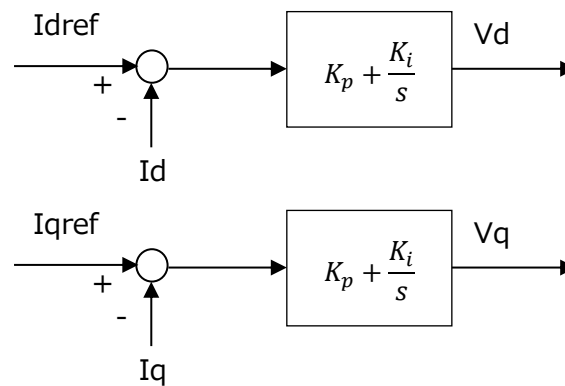


Figure 4 Current Control Block Diagram

10.7.11 Output Coordinate Conversion (D_OutputTransformation)**10.7.11.1 Syntax**

```
void D_OutputTransformation (vector_t* const _motor)
```

Parameter:

`_motor` Motor Control Structure

Returned Value:

No

10.7.11.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.vector_cmd.F_vcomm_onoff	Motor Output Control Command	---	
	drv.Vd	d-Axis Voltage	Q31	
	drv.Vq	q-Axis Voltage	Q31	
	drv.Vdc	Power Supply Voltage	Q15	
	drv.theta	Rotor Position	Q0	[deg/360]
	drv.PhCvMd	Phase Conversion Mode	---	0: Spatial Vector 1: Inverse Clarke
I/O	drv.Sector	Sector	---	
	drv.DutyU	U-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
	drv.DutyV	V-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
	drv.DutyW	W-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
Output	drv.Valpha	α -Axis Voltage	Q31	
	drv.Vbeta	β -Axis Voltage	Q31	
	drv.DutyU_bf	Previous U-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
	drv.DutyV_bf	Previous V-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
	drv.DutyW_bf	Previous W-phase PWM Duty ratio	Q15 (unsigned)	0.0 to 1.0
	drv.Sector1	Previous Sector	---	

10.7.11.3 Process

Converts dq-axis voltages (Vd, Vq) to three-phase PWMDuty ratios (DutyU, DutyV, DutyW).

1. Through 10.7.12 Inverse Park Transformation, converts dq-axis voltages (Vd, Vq) to $\alpha\beta$ -axis voltages (V_α , V_β).
2. Computes the current Sector based on the $\alpha\beta$ -axis voltages (V_α , V_β). Saves the Sector before computation to "Previous Sector", so that it is used for motor current acquisition.
3. Through 10.7.13 Spatial Vector Modulation or 10.7.13 Inverse Clarke Transformation, converts $\alpha\beta$ -axis voltages (V_α , V_β) to three-phase Duty ratios (DutyV, DutyW, DutyU).

10.7.12 Inverse Park Transformation (E_InvPark)

10.7.12.1 Syntax

```
void E_InvPark( q31_t _d,
               q31_t _q,
               uint16_t _theta,
               q31_t* _alpha,
               q31_t* _beta)
```

Parameter:

_d	d-Axis
_q	q-Axis
_theta	Rotor Position θ : $0 \leq \text{Position} < 360^\circ$ (0 to 0xffff)
_alpha	α -Axis Storage Address
_beta	β -Axis Storage Address

Returned Value:

No

10.7.12.2 Process

Converts from the dq-axes of rotational coordinate to the $\alpha\beta$ -axes of static coordinate.

V_α and V_β are computed using the following computation formulas:

$$V_\alpha = V_d \times \cos\theta - V_q \times \sin\theta$$

$$V_\beta = V_d \times \sin\theta + V_q \times \cos\theta$$

10.7.13 Sector Calculation (D_CalSector)

10.7.13.1 Syntax

```
uint8_t D_CalSector( q31_t _valpha,
                    q31_t _vbeta)
```

Parameter:

_valpha	α -Axis Voltage
_vbeta	β -Axis Voltage

Returned Value:

Sector

10.7.13.2 Process

Computes the sector based on the $\alpha\beta$ -axis voltage.

Stores the previous sector values and determines the current sector values using the conditional formula below:

Table 10.5 Sector Calculation

Condition		Sector Value
Condition 1	Condition 2	
$(V_{\alpha} \geq 0) \& (V_{\beta} \geq 0)$	$V_{\alpha} \geq (V_{\beta}/\sqrt{3})$	0
	$V_{\alpha} < (V_{\beta}/\sqrt{3})$	1
$(V_{\alpha} < 0) \& (V_{\beta} \geq 0)$	$ V_{\alpha} < (V_{\beta}/\sqrt{3})$	1
	$ V_{\alpha} \geq (V_{\beta}/\sqrt{3})$	2
$(V_{\alpha} < 0) \& (V_{\beta} < 0)$	$ V_{\alpha} \geq (V_{\beta} /\sqrt{3})$	3
	$ V_{\alpha} < (V_{\beta} /\sqrt{3})$	4
$(V_{\alpha} \geq 0) \& (V_{\beta} < 0)$	$V_{\alpha} < (V_{\beta} /\sqrt{3})$	4
	$V_{\alpha} \geq (V_{\beta} /\sqrt{3})$	5

10.7.14 Inverse Clarke Transformation (E_InvClarke)

Not implemented in this software.

10.7.14.1 Syntax

```
void E_InvClarke( q31_t _valpha,
                  q31_t _vbeta,
                  uint16_t* _p_vu,
                  uint16_t* _p_vv,
                  uint16_t* _p_vw)
```

Parameter:

_valpha	α -Axis V_α
_vbeta	β -Axis V_β
_p_vu	Phase-U Voltage V_u Storage Address
_p_vv	Phase-V Voltage V_v Storage Address
_p_vw	Phase-W Voltage V_w Storage Address

Returned Value:

No

10.7.14.2 Process

Converts two-phase (V_α , V_β) to three-phase (V_u , V_v , V_w) voltages.

V_u , V_v , and V_w are computed using the following computation formulas:

$$V_u = V_\alpha \times \cos 0^\circ + V_\beta \times \sin 0^\circ = V_\alpha$$

$$V_v = V_\alpha \times \cos 120^\circ + V_\beta \times \sin 120^\circ = -\frac{1}{2}V_\alpha + \frac{\sqrt{3}}{2}V_\beta$$

$$V_w = V_\alpha \times \cos 240^\circ + V_\beta \times \sin 240^\circ = -\frac{1}{2}V_\alpha - \frac{\sqrt{3}}{2}V_\beta$$

10.7.15 Spatial Vector Modulation (D_SVM)

10.7.15.1 Syntax

```
void D_SVM( q31_t _valpha,  
            q31_t _vbeta,  
            q15_t _vdc,  
            uint8_t _sector,  
            uint8_t _modul,  
            uint16_t* _p_vu,  
            uint16_t* _p_vv,  
            uint16_t* _p_vw)
```

Parameter:

_valpha	α -Axis V_α
_vbeta	β -Axis V_β
_vdc	Power Supply Voltage
_sector	Sector
_modul	Modulation
_p_vu	Phase-U Duty Ratio DutyU Storage Address
_p_vv	Phase-V Duty Ratio DutyV Storage Address
_p_vw	Phase-W Duty Ratio DutyW Storage Address

Returned Value:

No

10.7.15.2 Process

Acquires the duty ratio of the three-phase PWM from the two-phase $\alpha\beta$ -axis voltages.

Acquires the PWM duty ratio of each phase using the spatial vector modulation.

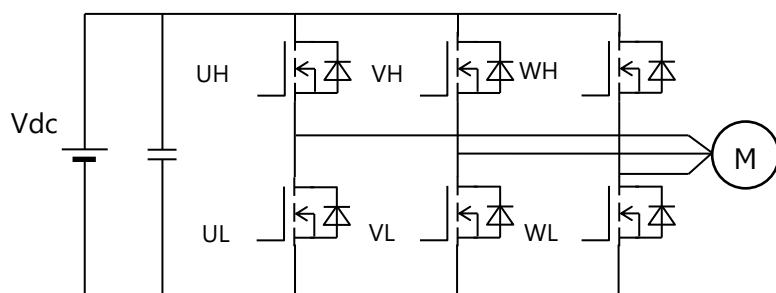
● What is the Spatial Vector Modulation?

As the switching elements in the inverter drive circuit are in the statuses where the elements of the upper phase are ON or OFF and those of the lower phase are in the inverse status (the dead time is ignored), there are eight patterns as shown in Table 0.6.

Where these eight patterns are defined as V0 thru V7, and the vectors V0 and V7 are located at the origin due to no line voltage, if graphically expressed, with the remaining six vectors (V1 thru V6) being expressed at every 60 degrees as shown in Figure 6.

By combining the neighboring two vectors together, an arbitrary output voltage vector V is acquired.

How to compute PWM Duty when the output voltage vector V exists at Sector 0 will be shown in subsequent pages.



UH: Phase-U Upper Phase Switching Element
UL: Phase-U Lower Phase Switching Element
VH: Phase-V Upper Phase Switching Element
VL: Phase-V Lower Phase Switching Element
WH: Phase-W Upper Phase Switching Element
WL: Phase-W Lower Phase Switching Element
Vdc: Power Supply Voltage

Table 10.6 Inverter Switching Status

U	V	W	Vector
0	0	0	V0 (0 0 0)
1	0	0	V1 (1 0 0)
1	1	0	V2 (1 1 0)
0	1	0	V3 (0 1 0)
0	1	1	V4 (0 1 1)
0	0	1	V5 (0 0 1)
1	0	1	V6 (1 0 1)
1	1	1	V7 (1 1 1)

0: Upper Phase OFF, Lower Phase ON

1: Upper Phase ON, Lower Phase OFF

Figure 5 Inverter Drive Circuit

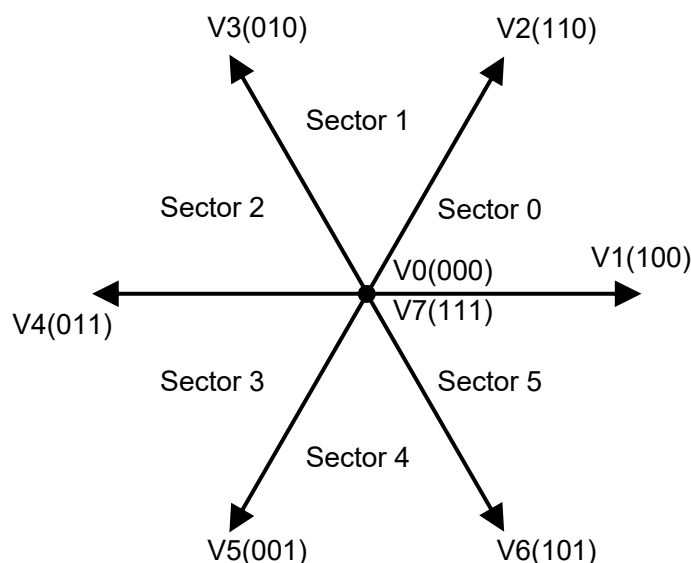


Figure 6 Spatial Vector

- When the output voltage vector V is in Sector 0

For example, in Figure 7, the composite vector V of V_α and V_β is located at the sector 0; accordingly, it is acquired as a composite vector of $V1'$ and $V2'$ acquired by multiplying the voltage vectors $V1$ and $V2$ with factors $t1$ and $t2$, respectively. If they are expressed in the PWM waveform, an output voltage vector V is composed by generating $V1$ and $V2$ for the duration of $t1$ and $t2$, respectively, in the half cycle of PWM as shown in Figure 8.

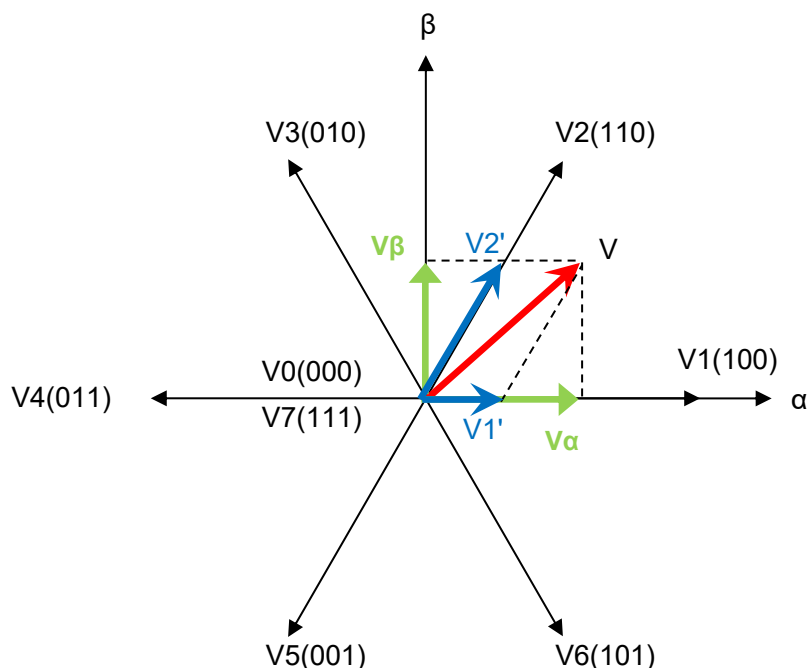


Figure 7 Voltage Vector at Sector 0

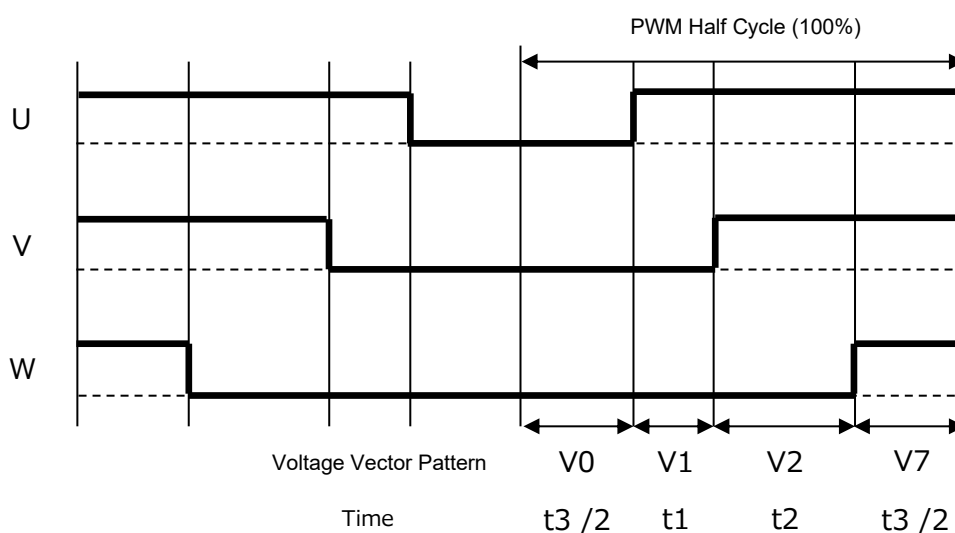


Figure 8 three-phase Modulation PWM Waveform

From Figure 10.16 Voltage Vector at Sector 0, V_α and V_β can be expressed as follows:

$$V_\alpha = V1' \times \cos 0^\circ + V2' \times \cos 60^\circ = V1' + \frac{V2'}{2}$$

$$V_\beta = V1' \times \sin 0^\circ + V2' \times \sin 60^\circ = \frac{\sqrt{3}}{2} \times V2'$$

Consequently, $V1'$ and $V2'$ are as below:

$$V2' = \frac{2}{\sqrt{3}} V_\beta$$

$$V1' = V_\alpha - \frac{V2'}{2} = V_\alpha - \frac{1}{\sqrt{3}} V_\beta$$

Where the motor power supply voltage is V_{dc} , $V1'$ and $V2'$ are as below:

$$V1' = t1 \times V_{dc}$$

$$V2' = t2 \times V_{dc}$$

Consequently, the ratio between $t1$, $t2$, and $t3$ is as below:

$$t1 = k \times \frac{V_\alpha - \frac{1}{\sqrt{3}} V_\beta}{V_{dc}}$$

$$t2 = k \times \frac{\frac{2}{\sqrt{3}} V_\beta}{V_{dc}}$$

$$t3 = 100\% - t1 - t2$$

where, k is a conversion factor for bringing the size to a certain level when converting from three-phase to two-phase, and its value is $3/2$.

The definition of occurrence duration for vectors $V0$ and $V7$ as $t3/2$ respectively is the three-phase modulation, whereas the definitions of occurrence duration for vector $V0$ as $t3$ and that for $V7$ as 0 are the two-phase modulation.

Consequently, the duties for the three phases are acquired using the following calculations from $t1$, $t2$ and $t3$.

$$\text{Phase-U Duty} = t1 + t2 + (t3/2)$$

$$\text{Phase-V Duty} = t2 + (t3/2)$$

$$\text{Phase-W Duty} = t3/2$$

Similarly, for every sector of the output voltage, the OFF Duty $D0$, the Duty $D1$ when only one phase is ON and the Duty $D2$ when two phases are ON are computed using Table 10.6 Formulas for Duty On Duration per Sector.

Table 10.7 Formulas for Duty On Duration per Sector

Sector	Duty when only one of the phases is ON. D1	Duty when two phases are ON D2	OFF Duty D0
0	$k \times \frac{V\alpha - \frac{1}{\sqrt{3}}V\beta}{Vdc}$	$k \times \frac{\frac{2}{\sqrt{3}}V\beta}{Vdc}$	100% – D1 – D2
1	$k \times \frac{-V\alpha + \frac{1}{\sqrt{3}}V\beta}{Vdc}$	$k \times \frac{V\alpha + \frac{1}{\sqrt{3}}V\beta}{Vdc}$	
2	$k \times \frac{\frac{2}{\sqrt{3}}V\beta}{Vdc}$	$k \times \frac{-V\alpha - \frac{1}{\sqrt{3}}V\beta}{Vdc}$	
3	$-k \times \frac{\frac{2}{\sqrt{3}}V\beta}{Vdc}$	$k \times \frac{-V\alpha + \frac{1}{\sqrt{3}}V\beta}{Vdc}$	
4	$k \times \frac{-V\alpha - \frac{1}{\sqrt{3}}V\beta}{Vdc}$	$k \times \frac{V\alpha - \frac{1}{\sqrt{3}}V\beta}{Vdc}$	
5	$k \times \frac{V\alpha + \frac{1}{\sqrt{3}}V\beta}{Vdc}$	$-k \times \frac{\frac{2}{\sqrt{3}}V\beta}{Vdc}$	

where, k is a factor 3/2 for making the amplitudes before and after conversion to a certain level.

The duties for U, V and W phases are computed from D0, D1 and D2 using the formulas in Table 10.7.

Table 10.8 Relationship of Sectors and Duties of Phases

Sector	three-phase Modulation			two-phase Modulation		
	Phase-U Duty	Phase-V Duty	Phase-W Duty	Phase-U Duty	Phase-V Duty	Phase-W Duty
0	D1+D2+(D0/2)	D2+(D0/2)	D0/2	D1+D2	D2	0
1	D2+(D0/2)	D1+D2+(D0/2)	D0/2	D2	D1+D2	0
2	D0/2	D1+D2+(D0/2)	D2+(D0/2)	0	D1+D2	D2
3	D0/2	D2+(D0/2)	D1+D2+(D0/2)	0	D2	D1+D2
4	D2+(D0/2)	D0/2	D1+D2+(D0/2)	D2	0	D1+D2
5	D1+D2+(D0/2)	D0/2	D2+(D0/2)	D1+D2	0	D2

10.7.16 Trigger Timing Calculation (D_CalTrgTiming)

10.7.16.1 Syntax

```
void D_CalTrgTiming(vector_t* const _motor)
```

Parameter:

`_motor` Motor Control Structure

Returned Value:

No

10.7.16.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	drv.DutyU	Phase-U PWM Duty Ratio	Q15	0.0 to 1.0
	drv.DutyV	Phase-V PWM Duty Ratio	Q15	0.0 to 1.0
	drv.DutyW	Phase-W PWM Duty Ratio	Q15	0.0 to 1.0
	drv.command.modul	Modulation	---	two-phase or three-phase Modulation
	drv.TrgPosMd	Current Detection Position Mode	---	3-shunt 1-shunt (first half) 1-shunt (second half)
	para.TrgComp	Trigger Timing Compensation	Q15	-1.0 to 1.0
Output	drv.AdTrg0	AD Trigger Timing 0 (TRG0)	Q15	-1.0 to 1.0
	drv.AdTrg1	AD Trigger Timing 1 (TRG1)	Q15	-1.0 to 1.0

10.7.16.3 Process

Computes the trigger timing to acquire AD conversion values of motor current and power supply voltage Vdc.

The trigger position is different for 3-shunt or 1-shunt.

● For 3-shunt

The basic trigger position is -100% (carrier-end). When a positive value is entered for the trigger timing compensation, the value is compensated backward from the basic trigger position. When a negative value is entered, the position is -100% without compensation.

Modulation	Trigger Timing (TRG) Motor Currents UVW, Power Supply Voltage Vdc
two-phase Modulation	100%
three-phase Modulation	100%

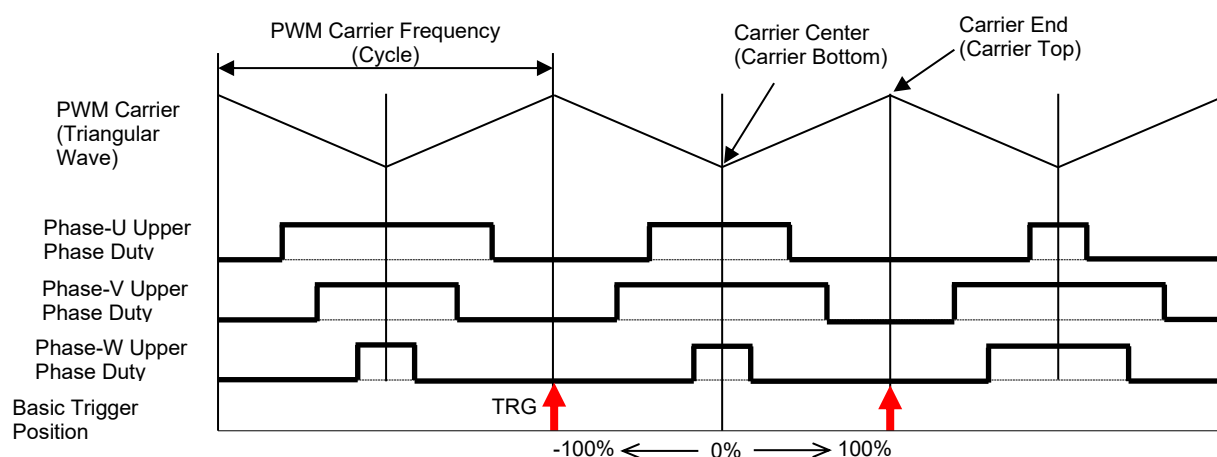


Figure 10.18 Trigger Position for 3-shunt

● For 1-shunt

Computes the basic trigger position from the PWM Duty values in Phases U, V, and W.

When a value other than 0 is entered for the trigger timing compensation, the value is compensated from the computed trigger position.

The Power Supply Voltage Vdc trigger position is fixed to the position of the carrier end. (Set up at initial setup, and not processed by this function.)

	Modulation	Trigger Timing 0 (TRG0) Motor Current	Trigger Timing 1 (TRG1) Motor Current	Trigger Timing 2 (TRG2) Power Supply Voltage Vdc
PWM Cycle Second Half	three-phase Modulation	Duty Median	Duty Max	Fixed to Carrier End
	two-phase Modulation	Duty Median	Duty Max	Fixed to Carrier End
PWM Cycle First Half	three-phase Modulation	-Duty Median	-Duty Min	Fixed to Carrier End
	two-phase Modulation	-Duty Median	Duty Median	Fixed to Carrier End

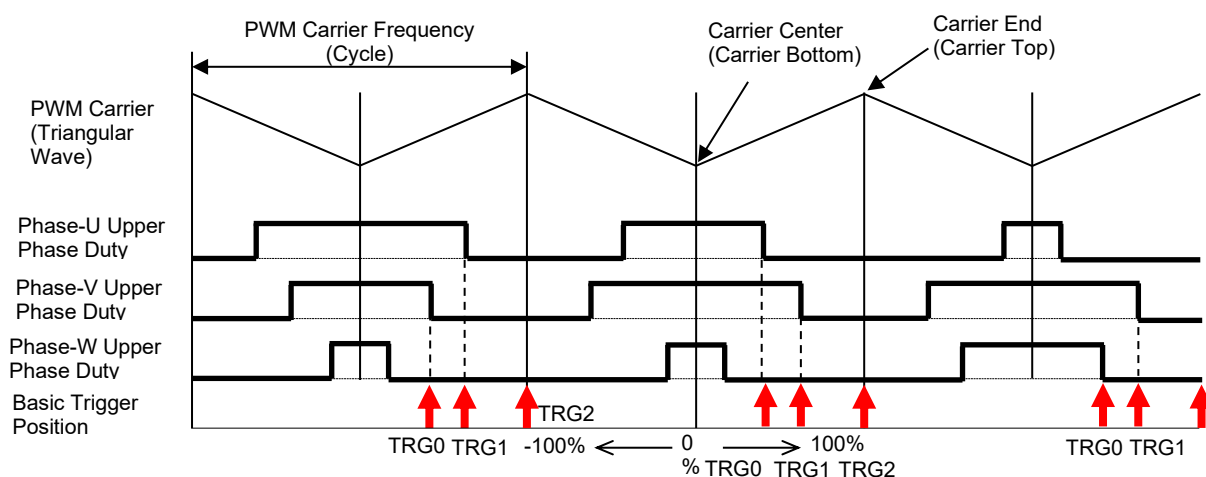


Figure 10.19 Trigger Position for 1-shunt, PWM Cycle Second Half, Three-phase Modulation

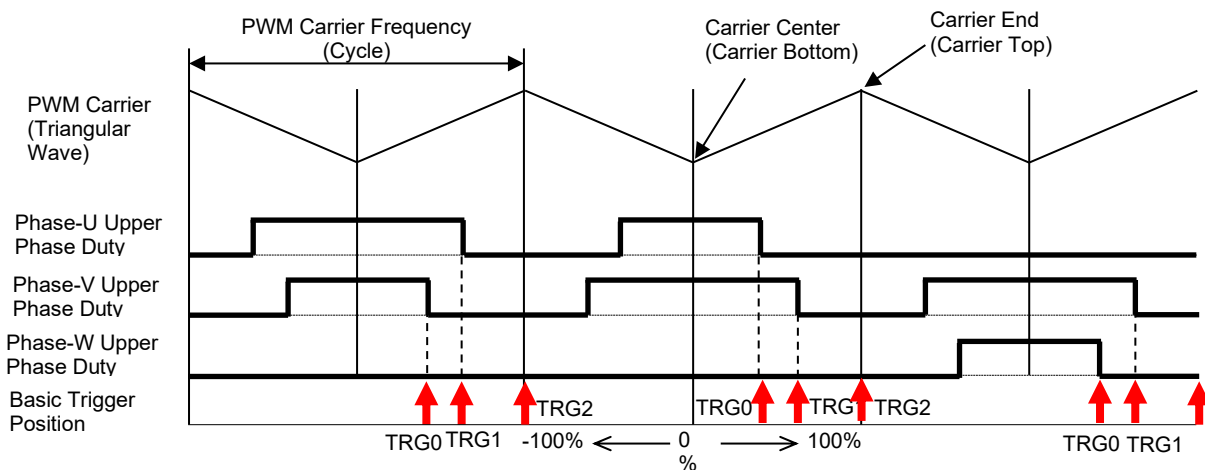


Figure 10.20 Trigger Position for 1-shunt, PWM Cycle Second Half, Two-phase Modulation

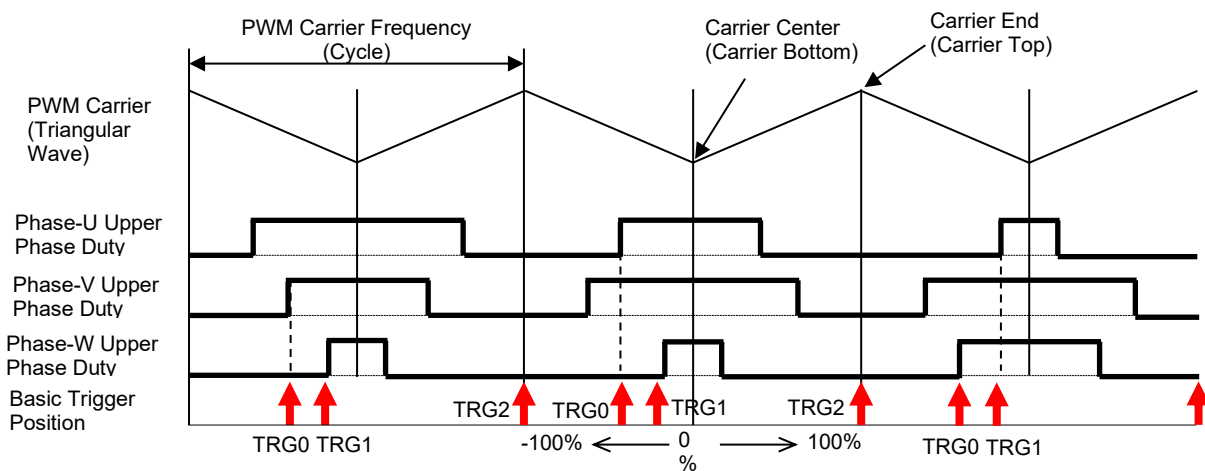


Figure 10.21 Trigger Position for 1-shunt, PWM Cycle First Half, Three-phase Modulation

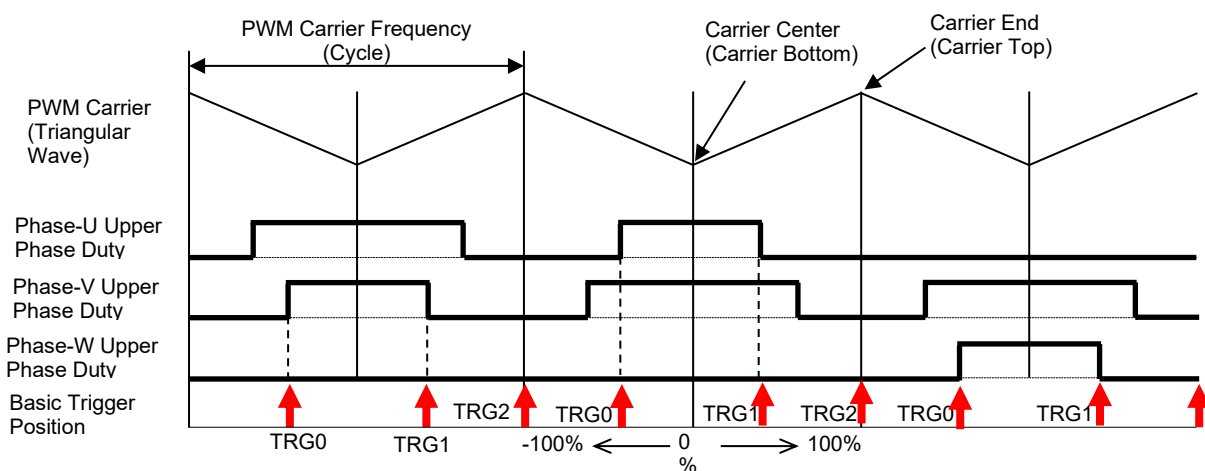


Figure 10.22 Trigger Position for 1-shunt, PWM Cycle First Half, Two-phase Modulation

10.7.17 PWM Register Setup (PMD_RegDataSet)

10.7.17.1 Syntax

```
void PMD_RegDataSet(TSB_PMD_TypeDef* const PMDx,
                    uint16_t duty_u,
                    uint16_t duty_v,
                    uint16_t duty_w,
                    q15_t adtrg0,
                    q15_t adtrg1)
```

Parameter:

PMDx	PMD Register Address
duty_u,	Phase-U PWM Duty Ratio
duty_v,	Phase-V PWM Duty Ratio
duty_w,	Phase-W PWM Duty Ratio
adtrg0,	AD Trigger Timing 0 Position
adtrg1	AD Trigger Timing 1 Position

Returned Value:

No

10.7.17.2 Process

Sets up the three-phase PWM Duty and trigger timing values to the register.

Sets up the entered parameters to the PMD register by executing the following computation.

$$\text{TRGCMP0} = (\text{adtrg0} + 32768) / 2$$

$$\text{TRGCMP1} = (\text{adtrg1} + 32768) / 2$$

$$\text{CMPU} = \text{duty_u}$$

$$\text{CMPV} = \text{duty_v}$$

$$\text{CMPW} = \text{duty_w}$$

10.7.18 Current Detection Error Detection Function (D_Check_DetectCurrentError)

10.7.18.1 Syntax

```
void D_Check_DetectCurrentError (vector_t* const _motor)
```

Parameter:

_motor Motor Control Structure

Returned Value:

No

10.7.18.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	para.chkpls	Pulse Check Width	---	
	shunt_type	Shunt Type	---	1:1-shunt 3:3-shunt
	drv.command.modul	Modulation Method Drive Command	---	two-phase or three-phase Modulation
	drv.DutyU	Phase-U PWM Duty Ratio	Q15	0.0 to 1.0
	drv.DutyV	Phase-V PWM Duty Ratio	Q15	0.0 to 1.0
	drv.DutyW	Phase-W PWM Duty Ratio	Q15	0.0 to 1.0
Output	drv.idetect_error	Current Detection Status	---	0:Detection Enabled 1:Detection Disabled

10.7.18.3 Process

From the PWM Duty width, detects that it is the time when the current is not detectable.

For 3-shunt, detects that the Duty Median is greater than the setup value.

For 1-shunt, detects that the minimum Duty width and Duty width difference each are smaller than the setup values. Note that the minimum Duty width for 1-shunt and two-phase modulation becomes the middle Duty width among the three-phase Duty widths.

However, current detection is not performed in Shift 2PWM mode.

Note: Enable the macro and then enable the over current detection to check the Vd/Vq output limitation values.

This function checks that the current is not detectable by the relevant duty width, and for current detection processing, uses the previous value without using the detected value, so as to eliminate turbulence in control caused by current detection errors.

- For 3-shunt

Since an AD conversion value for current detection in the PWM maximum phase is not used in computation, when the current detection value in the PWM median phase becomes greater than the setup value, it is judged as not detectable.

- For 1-shunt

When the width of PWM Duty itself, or the width of the PWM Duty difference becomes smaller than the setup value, it is judged as not detectable.

10.7.19 3-shunt Current Mis-detection Detection Function
(D_Check_DetectCurrentError_3shunt)

10.7.19.1 Syntax

```
int D_Check_DetectCurrentError_3shunt (uint32_t _duty, uint16_t _chkplwidth)
```

Argument:

<code>_duty</code>	Intermediate Duty Value
<code>_chkplwidth</code>	Pulse Width Check Range

Return Value:

Current Detection Status

10.7.19.2 Variable

Direction	Name	Details	Q Format	Notes
Input	<code>_duty</code>	Intermediate PWM Duty Ratio	Q15	0.0 to 1.0
	<code>_chkplwidth</code>	Pulse Width Check Range	---	
Output	<code>drv.idetect_error</code>	Current Detection Status	---	0: Detectable 1: Not Detectable

10.7.19.3 Processing Details

Detect the timing at which the current cannot be measured due to the PWM duty width. Also detect when the intermediate duty value becomes greater than the configured threshold. This function verifies whether the duty width is in a range where current measurement is not possible, and in such cases, it prevents the use of the measured current value in the current-sensing process. Instead, it uses the previous value to avoid control disturbances caused by erroneous current detection.

Since the ADC conversion value of the current detected at the PWM maximum phase is not used in calculations, the system determines a detection failure (NG) when the measured current value of the PWM middle phase exceeds the configured threshold.

10.7.20 1-shunt Current Mis-detection Function (D_Check_DetectCurrentError_1shunt)

10.7.20.1 Syntax

```
int D_Check_DetectCurrentError_1shunt (uint32_t _pwma, uint32_t _pwmb,
                                         uint32_t _pwmc, uint16_t _chkplwidth,
                                         int _sfhpwm, int _modu, int _sector,
                                         uint32_t _mdprd, uint16_t _trgcmp0,
                                         uint16_t _trgcmp1, uint16_t _shift2)
```

Argument:

_pwma	U-phase PWM Duty ratio
_pwmb	V-phase PWM Duty ratio
_pwmc	W-phase PWM Duty ratio
_chkplwidth	Pulse Width Check Range
_sfhpwm	Shift PWM Mode State
_modu	Modulation method
_sector	Sector information
_mdprd	PWM period
_trgcmp0	Shift2 trigger timing0
_trgcmp1	Shift2 trigger timing1
_shift2	Shift PWM2 center selection

Return Value:

Current Detection Status

10.7.20.2 Variable

Direction	Name	Details	Q Format	Notes
Input	_pwma	U-phase PWM Duty ratio	Q15	0.0 to 1.0
	_pwmb	V-phase PWM Duty ratio	Q15	0.0 to 1.0
	_pwmc	W-phase PWM Duty ratio	Q15	0.0 to 1.0
	_chkplwidth	Pulse Width Check Range	---	
	_sfhpwm	Shift PWM Mode State	---	
	_modu	Modulation method drive control command	---	2-phase/3-phase modulation
	_sector	Sector information	---	
	_mdprd	PWM period	---	
	_trgcmp0	Shift2 trigger timing0	---	
	_trgcmp1	Shift2 trigger timing1	---	
	_shift2	Shift PWM2 center selection	---	0:No Shift PWM 1:U-phase Center 2:V-phase Center 3:W-phase Center

Output	---	Current Detection Status	---	0:Detectable 1:Undetectable
--------	-----	--------------------------	-----	--------------------------------

10.7.20.3 Processing Details

This function detects conditions where the current cannot be measured due to insufficient PWM duty width.

It monitors whether the minimum duty width or the duty-width difference falls below the configured threshold. For a 1-shunt configuration using 2-phase modulation, the minimum duty width corresponds to the middle duty among the 3-phase duties.

When the function determines that the current cannot be reliably measured, the current-detection routine suppresses the use of the sampled value and instead uses the previous current value. This prevents control disturbances caused by false current readings.

If either the PWM duty width itself or the difference between PWM duties becomes smaller than the specified threshold, the function flags the condition as detection NG.

However, in Shift-PWM Mode 2, if the duty conditions deviate from the rules described below, the condition shall also be treated as detection NG.

-A Evaluation:

If the PWM output pulse width of the U-phase becomes the minimum, that width shall be at least twice the time required for current detection.

-B Evaluation:

If the PWM output pulse width of either the V-phase or W-phase becomes the minimum, that width shall be equal to or greater than the time required for current determination.

-C Evaluation:

If the PWM output pulse width of either the V-phase or W-phase becomes less than or equal to the difference between the PWM period and the time required for current detection.

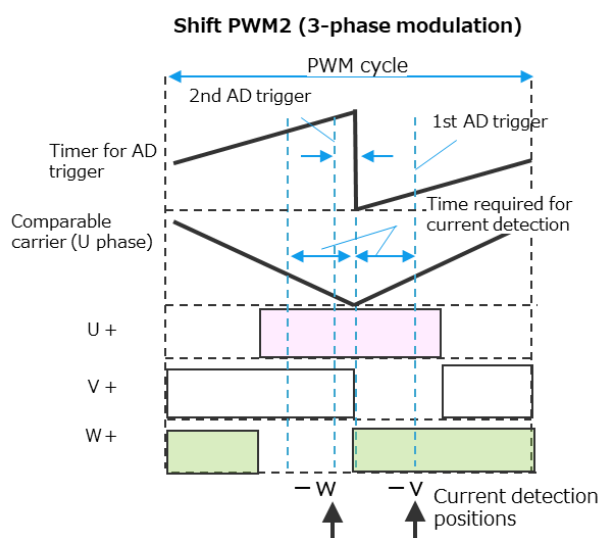


Figure10.23: Shift PWM2 (3-phase modulation)

10.7.21 Inverter Output Voltage Calculation Function (Cal_Vdq)

10.7.21.1 Syntax

q15_t Cal_Vdq (q15_t _vd, q15_t _vq)

Parameter:

_vd d-Axis Voltage

_vq q-Axis Voltage

Returned Value:

Inverter Output Voltage (Vdq)

10.7.21.2 Variable

Direction	Code	Description	Q Format	Remarks
Input	_vd	d-Axis Voltage	Q15	0.0 to 1.0
	_vq	q-Axis Voltage	Q15	0.0 to 1.0
Output	---	Inverter Output Voltage (Vdq)	Q15	0.0 to 1.0

10.7.21.3 Process

Computes Inverter Output Voltage (Vdq).

$$Vdq = \sqrt{3} \times \sqrt{vd^2 + vq^2}$$

11. Special Function Description

11.1 Flux Observer Based Position Detection Method

In sensorless position estimation control using a Flux Observer, the motor flux is computed primarily from the α/β axis currents and voltages. From the estimated flux, the electrical angle, torque, and speed are subsequently calculated.

The motor operating waveforms corresponding to each stage transition are shown below.

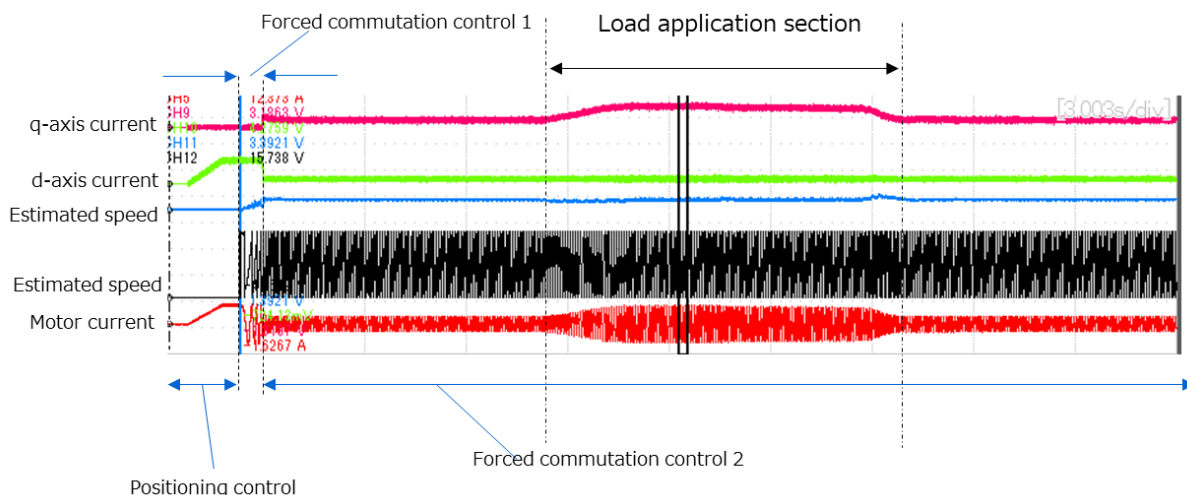


Figure11.1: Motor operating waveforms for the forced-commutation method in which d-axis current is applied according to the estimated motor-flux angle.

After entering Forced Commutation Control 1, the commanded speed is gradually increased. When the commanded speed exceeds Speed Threshold 1, the control transitions to Forced Commutation Control 2. In Forced Commutation Control 2, the estimated electrical angle is used while keeping i_{dref} fixed at a constant value, and i_{qref} is driven by the result of the speed controller. This allows the motor current to follow the load conditions appropriately.

When the commanded speed exceeds Speed Threshold 2, the control switches to sensorless operation, and i_{dref} is set to zero.

All related processing is managed within the library files.

11.1.1 Function Specification

11.1.1.1 Flux Observer Control Initialization Function (Cal_phi_theta_ini)

Syntax :

```
q31_t Cal_phi_theta_ini ( phi_t* const _phi )
```

Argument:

_phi Flux Observer Structure

Return Value:

None

Processing Details:

Flux Observer Based Position Detection Method Initialization

11.1.1.2 Voltage Deviation Calculation Function (cal_sogi1_alpha_voltage, cal_sogi1_beta_voltage)

Syntax:

```
q31_t cal_sogi1_alpha_voltage (phi_t* const _phi,
                               q31_t _voltage,
                               q15_t _current)
q31_t cal_sogi1_beta_voltage (phi_t* const _phi,
                              q31_t _voltage,
                              q15_t _current)
```

Argument :

_phi Flux Observer Structure
_voltage α -axis(β -axis)Voltage Previous Value
_current α -axis(β -axis)Current

Return Value:

The α -axis (β -axis) voltage deviation, and the value obtained by subtracting the α -axis (β -axis) SOGI intermediate value from the α -axis (β -axis) voltage deviation.

Variable:

Direction	Name	Details	Q Format	Notes
Input	_phi.phi_r	Motor winding resistance	Q15	
	_voltage	α -axis(β -axis) current	Q31	
	_current	α -axis(β -axis) current	Q15	
	_phi.alpha_SOGI4, beta_SOGI4	α -axis(β -axis) SOGI axisintermediate value	Q31	
Output	_phi.volt_dev_a, volt_dev_b	α -axis(β -axis) Voltage deviation	Q15	

Processing Details:

The function calculates the α -axis (β -axis) voltage deviation, as well as the value obtained by subtracting the α -axis (β -axis) SOGI intermediate value from the α -axis (β -axis) voltage deviation.

By applying the SOGI gain to the latter value, the α -axis (β -axis) SOGI intermediate value used for flux-observer-based position estimation can be obtained.

11.1.1.3 Estimated Angle Calculation Function (Cal_phi_theta)

Syntax :

```
q31_t Cal_phi_theta (phi_t* const _phi,
                    q31_t _omega_com,
                    int32_t _ctrlprd,
                    q15_t _Ialpha,
                    q15_t _Ibeta,
                    q15_t _omega)
```

Argument :

_phi	Flux Observer Structure
_omega_com	Drive Speed command value
_ctrlprd	Position Estimation Control Period
_Ialpha	α -axis current
_Ibeta	β -axis current
_omega	Estimated Speed

Return Value:

Flux Observer Estimation Angle

Variable:

Direction	Name	Details	Q Format	Notes
Input	_phi.phi_r	Motor winding resistance	Q15	
	_phi.Lm	Mutual inductance value	Q31	
	_phi.volt_dev_a	α -axis voltage deviation	Q15	
	_phi.alpha_SOGI1	α -axisSOGI axisintermediate value	Q31	
	_phi.alpha_SOGI4	Previous α -axisSOGI axisintermediate value	Q31	
	_phi.alpha_SOGI5	Previous α -axisSOGI axisintermediate value	Q31	
	_phi.volt_dev_b	β -axis voltage deviation	Q15	
	_phi.beta_SOGI1	β -axisSOGI axisintermediate value	Q31	
	_phi.beta_SOGI4	Previous β -axisSOGI axisintermediate value	Q31	
	_phi.beta_SOGI5	Previous β -axisSOGI axisintermediate value	Q31	
	_Ialpha	α -axis current	Q15	
	_Ibeta	β -axis current	Q15	
	_omega_com	Speed control command	Q31	
	_ctrlprd	Position Estimation Control Period	Q0	
	_SOGI_G	SOGI Control GAIN	Q31	
Output	_phi_th	Flux Observer Estimation Angle	Q0	

	_phi.alpha_SOGI4	α-axisSOGI axisintermediate value	Q31	
	_phi.alpha_SOGI5	α-axisSOGI axisintermediate value	Q31	
	_phi.beta_SOGI4	β-axisSOGI axisintermediate value	Q31	
	_phi.beta_SOGI5	β-axisSOGI axisintermediate value	Q31	

Processing Details:

This function computes $\varphi_{\alpha/\beta}$ from $I_{\alpha/\beta}$, $V_{\alpha/\beta}$, and calculates the electrical angle.

Note: _SOGI_G value is variable according to the speed control command, because it is unstable in the position estimation process under high-speed and high load conditions.

The calculation formulas and block diagrams are shown below.

$$\begin{aligned}\varphi_{\alpha} &= \int (V_{\alpha} - R^* I_{\alpha}) dt - L_M I_{\alpha} \\ \varphi_{\beta} &= \int (V_{\beta} - R^* I_{\beta}) dt - L_M I_{\beta}\end{aligned}$$

$$\begin{aligned}\text{SOGI}_{\alpha 1} &= (V_{\alpha} - R^* I_{\alpha}) - \text{SOGI}_{\alpha 4}^{*1} \\ \text{SOGI}_{\alpha 2} &= \text{SOGI}_{\alpha 1} * G - \text{SOGI}_{\alpha 5}^{*1} * \omega_{\text{com}}^{*2} \\ \text{SOGI}_{\alpha 3} &= \text{SOGI}_{\alpha 2} * \omega_{\text{com}} \\ \text{SOGI}_{\alpha 4} &= \int (\text{SOGI}_{\alpha 3}) dt \\ \text{SOGI}_{\alpha 5} &= \int (\text{SOGI}_{\alpha 4}) dt \\ \varphi_{\alpha} &= \text{SOGI}_{\alpha 5} - L_M I_{\alpha}\end{aligned}$$

$$\begin{aligned}\text{SOGI}_{\beta 1} &= (V_{\beta} - R^* I_{\beta}) - \text{SOGI}_{\beta 4} \\ \text{SOGI}_{\beta 2} &= \text{SOGI}_{\beta 1} * G - \text{SOGI}_{\beta 5} * \omega_{\text{com}} \\ \text{SOGI}_{\beta 3} &= \text{SOGI}_{\beta 2} * \omega_{\text{com}} \\ \text{SOGI}_{\beta 4} &= \int (\text{SOGI}_{\beta 3}) dt \\ \text{SOGI}_{\beta 5} &= \int (\text{SOGI}_{\beta 4}) dt \\ \varphi_{\beta} &= \text{SOGI}_{\beta 5} - L_M I_{\beta} \\ \Theta &= \text{ATAN}(\varphi_{\beta} / \varphi_{\alpha})\end{aligned}$$

* 1: Previous Value

* 2: Absolute Value

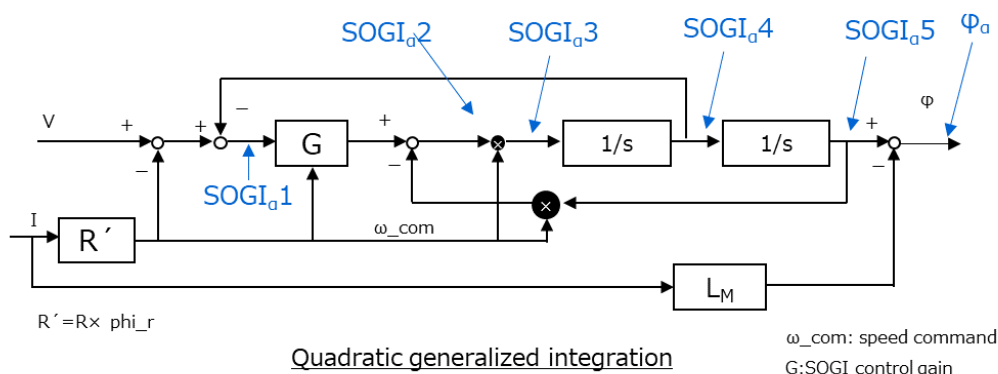


Figure11.2: Quadratic generalized integration

11.1.1.4 Angle Correction Calculation Function (Cal_theta_adj)

Syntax :

```
q31_t Cal_theta_adj (phi_t* const _phi,
                    q31_t _ld,
                    q31_t _lq,
                    q15_t _id,
                    q15_t _iq,
                    q15_t _omega)
```

Argument:

_phi	Flux Observer Structure
_ld	Motor d-axis Inductor
_lq	Motor q-axis Inductor
_id	d-axis current
_iq	q-axis current
_omega	Estimated Speed

Return Value:

Angle correction value

Variable:

Direction	Name	Details	Q Format	Notes
Input	_phi.Phi	Magnet Flux	Q31	
	_ld	Motor q-axis inductance	Q31	
	_lq	Motor d-axis inductance	Q31	
	_id	d-axis current	Q15	
	_iq	q-axis current	Q15	
Output	theta_adj	Angle correction value	Q31	

Processing Details:

The estimated angle is corrected based on the torque angle generated by the load torque.

$$\delta = \tan^{-1}((_lq * _iq) / (_ld * _id + \phi_a))$$

ϕ_a : Magnet Flux[Wb]

Idea of estimated angle in the flux observer

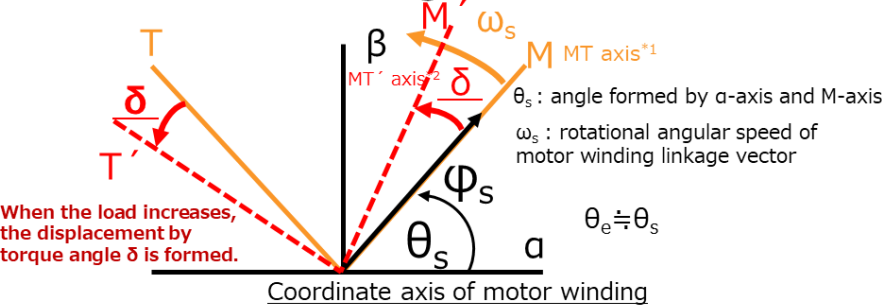
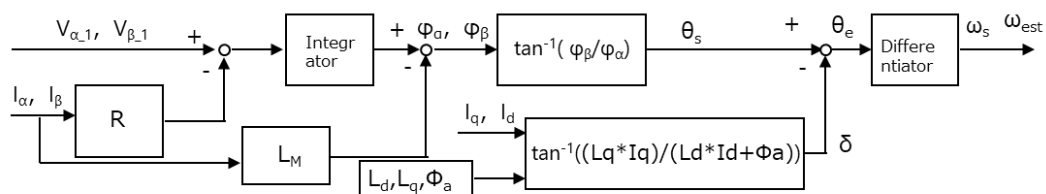


Figure11.3: Coordinate axis of motor winding



Flux observer block diagram

Figure11.4: Flux observer block diagram

11.1.1.5 Estimated Speed Computation Function (Cal_phi_omega)

Syntax :

```
q31_t Cal_phi_omega (phi_t* const _phi,
                    q31_t _theta_phi2,
                    q31_t _theta_phi_bf,
                    uint8_t _omegaphi_ave,
                    int32_t _ctrlprd)
```

Argument:

_phi	Flux Observer Structure
_theta_phi2	Flux Observer Based Estimated Angle Current Value
_theta_phi_bf	Flux Observer Based Estimated Angle Previous Value
_omegaphi_ave	Flux Observer Previous and Current Angle deviation
	Computation, Filter coefficient for Estimated Speed
_ctrlprd	Position Estimation Control Period

Return Value:

Flux Observer Estimated Motor Speed

Variable:

Direction	Name	Details	Q Format	Notes
Input	_theta_phi_bf	Flux Observer Angle Previous Value	Q31	
	_theta_phi2	Flux Observer Angle	Q31	
	_omegaphi_ave	Flux Observer Previous and Current Angle deviation computation, Filter coefficient for Estimated Speed	Q0	
	_ctrlprd	Position Estimation Control Period	Q0	
I/O	Phi.theta_phi_div_ave	Previous and Current Angle deviation	Q31	
Output	Phi.phi_om	Flux Observer Estimated Speed	Q31	

Processing Details:

The estimated speed is computed using the current estimated angle and the estimated angle from 1 PWM cycle earlier.

11.1.2 Data Structure

11.1.2.1 phi_t

Data Fields:

q31_u **alpha_SOGI4**: [---] α -axisSOGI intermediate variables
q31_u **alpha_SOGI5**: [---] α -axisSOGI intermediate variables
q31_u **beta_SOGI4**: [---] β -axisSOGI intermediate variables
q31_u **beta_SOGI5**: [---] β -axisSOGI intermediate variables
q31_u **theta_phi_div_ave**: [deg] Previous and Current Angle deviation
q31_t **phi_om**: [Hz] Flux Observer Estimated Speed
q31_t **phi_al**: [Wb] α -axis flux
q31_t **phi_be**: [Wb] β -axis flux
q31_t **phi_th**: [deg] Flux Observer Estimated Angle
q31_t **Lm**: [Vs/A] Mutual inductance(computed from Ld and Lq.)
q31_t **Phi**: [Wb] Magnet Flux
q31_t **phi_r**: [ohm] Motor winding resistance
q15_t **volt_dev_a, volt_dev_b**: [V] Voltage deviation
q31_u **alpha_SOGI1**: [---] α -axisSOGI intermediate variables
q31_u **beta_SOGI1**: [---] β -axisSOGI intermediate variables

11.1.3 Parameter

Parameter	Details
phi_theta_time_CHx	Angle correction switching time step during Flux Observer switching.
	unit[s]
	phi_CH_theta = 1, be enabled.
	Recommended value: 0.001 to 0.01
phi_SOGI_G_Chx	Parameter for SOGI
	--
	Set the responsiveness adjustment value for the Flux Observer.
	Recommended value: 2 to 5
phi_SOGI_G_high_CHx	Parameters for SOGI at High-Speed Operation
	--
	Set the adjustment values for the Flux Observer response when operating at high speed.
phi_SOGI_G_high_Hz_CHx	Speed for switching SOGI parameters
	Unit[Hz]
	Set the Speed at which the SOGI parameters are switched.
theta_phi_adj_CHx	Position Estimation Error Compensation When Using Flux Observer
	--
	Configure whether to enable compensation for the Position Estimation error when the Flux Observer is applied.
	0: No angle correction considering torque

	1: Angle correction enabled considering torque
phi_EMG_CHx	Flux Observer EMG Threshold
	--
	Set the EMG judgment threshold. If the Estimated Speed of the Flux Observer changes sharply, it is judged as EMG when Estimated Speed $\geq$ omega_com * phi_EMG. A smaller value increases the likelihood of false detection.
phi_r_CHx	Correction Value for Resistance Used in Flux Observer Calculation
	--
	Set the correction value for the resistance used in Flux Observer computation. When using PTS, because wiring and inverter resistance are included, set 0.7 to 0.9. When directly measuring motor winding resistance, set to 1.0.
phi_Id_ini_value_CHx	Id application multiplier at low speed
	--
	Set the multiplier for Id application during low-speed operation. A larger value improves stability but causes slower response. Recommended value: 0.5 to 1.0
phi_Id_ini_Hz_CHx	Id application speed at low speed
	[Hz]
	Set the frequency at which Id is applied during low-speed operation. Id is applied at: Sensorless switching frequency + phi_Id_CH_ini_Hz
theta_phi_adj_tq_CHx	Flux Observer Phase Adjustment ratio
	--
	theta_phi_adj_CH = 1, be Enabled. Recommended value: 0.5 to 2.0

12. Explanation of Definitions for Constants

12.1 Motor Driver Setting Parameter Common (D_Para.h)

12.1.1 Motor Control Channel Selection

__CONTROL_MOTOR_CH0 Define when controlling the CH0

12.1.2 Selecting a DAC Output

__USE_DAC Define when executing the DAC control for outputting the variables for evaluation.

12.1.3 Fake Temperature Adjustment Selection

__USE_FAKETEMP Define when executing Fake Temperature Adjustment

12.1.4 Selection of Unit for Command Speed

__TGTSPD_UNIT Selection of unit for command speed
0: Hz of Electrical angle
1: RPS of Mechanical angle
2: RPM of Mechanical angle

12.1.5 Selection of Special Control

__USE_PHI_DETECT_MOTOR_POSITION Define this when you conduct flux observer control.

12.1.6 Common Parameter List

Parameter Name	Description
cMAINLOOP_PRD	Main Cycle Setup
	Unit [s] Resolution 4 kHz
	Set up the main cycle time.
cIXO_AVE	Zero Current Filtering Factor
	--
	Set up the filtering factor. The setup of larger value will stabilize but will delay the response.
cVDQ_AVE	Filtering Factors for Power Supply Voltage Vdc and Output Voltage Vdq
	--
	Set up the filtering factor. The setup of larger value will stabilize but will delay the response.
cOMEGAENC_AVE	Filtering Factor for Speed Detection Value using the Number of Encoder Pulses
	--
	Set up the filtering factor for speed detection values. Use a larger value when the number of encoder pulses is small. However, when the value for the filtering factor becomes larger, the detection

	value will cause a delay. Set up a value so that delay becomes tolerable.
cMEGAPI_AVE	Filter Coefficient for Flux Observer Previous and Current Angle Deviation Calculation and Estimated Speed
	--
	Set the filter coefficient. A larger value increases stability but slows the response. Recommended value: 2 to 4
cTORQUE_AVE	Filter Coefficient for Flux Observer Torque Load Compensation
	--
	Set the filter coefficient. A larger value increases stability but slows the response. Recommended value: 2 to 4

12.2 Motor Driver Setting Parameter by Motor Channel (D_Para_Chx.h) x=0

Various motors are driven by changing the parameters in the motor driver.

12.2.1 Selection of Control

12.2.1.1 Sensorless / Sensor Selection

__USE_ENCODER_CH0	Define when encoder control is performed.
__USE_HALL_CH0	Define when hall sensor control is performed.

When both definitions are not defined, sensorless control is performed.

When both definitions are defined, hall sensor and encoder controls.

Only hall sensor control is not supported.

12.2.1.2 VE Selection

__USE_VE	When using VE, please define.
-----------------	-------------------------------

12.2.1.3 COMP Selection

__USE_COMP	When using built-in comparator, please define.
-------------------	--

12.2.1.4 Shift PWM2 Selection

__SPWM2_CH0	
0:	When using Shift PWM2(U-phase Center), please define.
1:	When using Shift PWM2(V-phase Center), please define.
2:	When using Shift PWM2(W-phase Center), please define.

12.2.2 Parameter List per Motor Channel

Parameter Name	Description
cPOLH	Upper Phase Drive Logical Setup
	0: Low active/ 1: High active
	Change the values according to the board design. Set up the logic for the upper phase driver.
cPOLL	Logical Setup for Lower Phase Driver
	0: Low active/ 1: High active
	Change the values according to the board design. Setup the logic for the lower phase driver.
cV_MAX	Setup of Max Voltage
	Unit [V]
	Change the values according to the board design. Setup the value [V] x 2 ¹² (the value of power supply voltage variation with regard to the variation of 1LSB in the AD conversion).
cA_MAX	Setup of Max Current
	Unit [A]
	Change the values according to the board design. Setup the value [A] x 2 ¹¹ (the value of phase current variation with regard to the variation of 1 LSB in the AD conversion).
cSHUNT_TYPE	Setup of Current Acquisition Method (3-shunt or 1-shunt)
	1: 1-shunt/ 3: 3-shunt
	Change the values according to the board design. Set up the current acquisition method.
cBOOT_TYPE	Setup of Drive Type when Starting
	cBoot_i: Current Type Drive/ cBoot_v: Voltage Type Drive
	Set up the drive type for starting. Select Voltage Type Drive in such a case as when the current cannot be acquired at the startup of 1-shunt drive, and others.
cSHUNT_ZERO_OFFSET	Setup of Offset Voltage
	Unit [V]
	Set up the shunt voltage when no current flows. This value will be used as the initial value of average zero current.
cADCH_CURRENT_U	Setup of Phase-U Current Acquisition AD Channel (3-shunt)
	AINx
	Set up the AD channel for detecting the Phase-U current
cADCH_CURRENT_V	Setup of Phase-V Current Acquisition AD Channel (3-shunt)
	AINx
	Set up the AD channel for detecting the Phase-V current
cADCH_CURRENT_W	Setup of Phase-W Current Acquisition AD Channel (3-shunt)
	AINx
	Set up the AD channel for detecting the Phase-W current
cADCH_CURRENT_IDC	Setup of Current Acquisition AD Channel (1-shunt)
	AINx
	Set up the AD channel for detecting the current.
cADCH_VDC	Setup of Power Supply Voltage Acquisition AD Channel

	AINx
	Set up the AD channel for detecting the power supply voltage Vdc.
cOVC	Setup of Overcurrent Detecting Value
	Unit [A]
	Set up the overcurrent detecting value. When a coil current exceeding this setup value is detected, the output will be turned OFF by the software.
cVDC_MINLIM	Setup of Min Power Supply Voltage Vdc
	Unit [V]
	Set up the Min value of power supply voltage Vdc. When voltage lower than this value is detected, the motor will be stopped.
cVDC_MAXLIM	Setup of Max Power Supply Voltage Vdc
	Unit [V]
	Set up the Max value of power supply voltage Vdc. When voltage higher than this value is detected, the motor will be stopped.
cPWMPRD	Setup of PWM Cycle
	Unit [μs] Resolution 12.5ns@80MHz
	Set up the cycle for the PWM carrier.
cDEADTIME	Setup of Dead Time
	Unit [μs] Resolution 50.0ns@20MHz
	Set up the dead time.
cREPTIME	Setup of the number of skipped software control.
	Unit [times]:1 to 15
	The timing for executing the vector computation software processing may be skipped. Setting to "1" will execute the software processing of vector computation once every PWM cycle. Setup of "2" will execute the software processing of vector computation one time every two PWM cycles.
cSPEED_ACT	Setup of the command speed
	Unit: [Hz] or [RPS] or [RPM] The unit is as specified in __TGTSPD__UNIT.
	Set up the motor command speed. When SWx is turned ON, the motor drives based on this setup value.
cID_ST_USER_ACT	Setup of d-Axis Start Current
	Unit [A]
	Set up the d-axis start current. This current value will be used for positioning and forced commutation. Set up the value of approximately 10% of the rated commutation. When the motor does not operate, gradually increase the value until it operates.
cIQ_ST_USER_ACT	Setup of q-Axis Start Current
	Unit [A]

	Set up the q-axis start current. Set up a value of approximately 1/2 of d-axis start current. If the motor abruptly accelerates when transferring from the forced commutation (d-axis control) to the steady (q-axis control), set a smaller value and, if the motor stops, set a larger value.
cMOTOR_R	Motor Coil Resistance
	Unit [Ohm]
	Set up a resistance equivalent to that of the single phase of motor coil.
cMOTOR_LQ	q-Axis Inductance
	Unit [mH]
	Set up the inductance of q-axis of motor coil
cMOTOR_LD	d-Axis Inductance (not used)
	Unit [mH]
	Set up the inductance of d-axis of motor coil
cPOLE	Setup of the Number of Motor Poles
	Unit [poles]
	Set up the number of motor poles.
cID_KP	d-Axis Current Control Proportional Gain
	Unit [V/A]
	Set up the d-axis current control proportional gain.
cID_KI	d-Axis Current Control Integration Gain
	Unit [V/As]
	Set up the d-axis current control integration gain.
cIQ_KP	q-Axis Current Control Proportional Gain
	Unit [V/A]
	Set up the q-axis current control proportional gain.
cIQ_KI	q-Axis Current Control Integration Gain
	Unit [V/As]
	Set up the q-axis current control integration gain.
cPOSITION_KP	Position Estimation Proportional Gain
	Unit [Hz/V]
	Set up the position estimation proportional gain.
cPOSITION_KI	Position Estimation Integration Gain
	Unit [Hz/Vs]
	Set up the position estimation integration gain.
cSPEED_KP	Speed Control Proportional Gain
	Unit [A/Hz]
	Set up the speed control proportional gain.
cSPEED_KI	Speed Control Integration Gain
	Unit [A/Hzs]
	Set up the speed control integration gain.
cSPD_PI_PRD	Setup of Speed PI Control Cycle
	[Time]
	Set up the speed PI control cycle. Setting to "1" will execute the speed PI computation once every PWM cycle.

	Setting to "2" will execute the speed PI computation once every two PWM cycles.
cFCD_UD_LIM	Drive Speed Acceleration Rate (Forced Commutation)
	Unit [Hz/s]
	Setup the speed acceleration rate during the forced commutation. Decrease the value when the motor speed does not follow the output of forced commutation.
cSTD_UP_LIM	Drive Speed Acceleration Rate (Steady)
	Unit [Hz/s]
	Set up the speed acceleration rate during the steady state.
cSTD_DW_LIM	Drive Speed Deceleration Rate (Steady)
	Unit [Hz/s]
	Set up the deceleration rate during the steady state.
cBOOT_LEN	Bootstrap Waveform Output Duration
	Unit [s] Resolution: 1 ms
	Set up the output duration for the bootstrap waveform.
cINIT_LEN	Positioning Time
	Unit [s] Resolution: 1 ms
	Set up the positioning duration.
cINIT_WAIT_LEN	Standby Time after Positioning
	Unit [s] Resolution: 1 ms
	Set up the standby time after positioning.
cGOUP_DELAY_LEN	Wait Time after Change-up
	Unit [s] Resolution: 1 ms
	Set up the wait time after change-up
cHZ_MAX	Max Frequency
	Unit [Hz]
	Set up the max frequency to be detected by the microcontroller. Set up a value increased by 10% to 20% from the max frequency used for controlling. A smaller value will enhance the precision of computation, but if the detected value exceeds this figure, the control will collapse.
cHZ_MIN	Changeover speed from forced commutation to steady.
	Unit [Hz]
	Set up a speed for transferring from the forced commutation to steady. Set up a speed that permits the position estimation (the induced voltage will be detected).
cHZ_SPWM	Shift PWM switching Speed (For 1 - shunt 2 - phase modulation)
	Unit[Hz]
	Set switching Speed for Shift PWM⇔Normal PWM. Switching is performed based on the value of control command Speed.
cHZ_SPWM_HYS	Shift PWM switching speed Hysteresis (For 1-shunt 2-phase modulation)
	Unit[Hz]

	Set Hysteresis of switching Speed for Shift PWM⇔Normal PWM. Switching is performed using the value obtained after subtracting the control command Speed.
cMINPLS	Setup of minimum pulse (for 1-shunt)
	Unit [us]
	Set up the PWM pulse width time that makes it impossible to acquire a current for the 1-shunt drive. (Note1) When the PWM pulse width becomes less than this setup value, control is executed by using the previous value without using the detected current value.
cMAXPLS	Setup of maximum pulse (for three-shunt)
	Unit [us]
	Set up the PWM pulse width time in the median phase that makes it impossible to acquire a current for the 3-shunt drive. When the PWM pulse width becomes equal to or more than this setup value, control is executed by using the previous value without using the detected current value.
cID_LIM	d-Axis Current Limit
	Unit [A]
	Set up the d-axis current limit.
cIQ_LIM	q-Axis Current Limit
	Unit [A]
	Set up the q-axis current limit.
cINITIAL_POSITION	Initial Position
	Unit [deg]
	Set up the angle for positioning in the electrical angle.
cVD_POS	Positioning output voltage during the voltage drive
	Unit [V]
	Set up the voltage for positioning. Enabled only when the cBOOT_TYPE is "cBoot_v" For details, refer to 12.2.3.2.
cSPD_COEF	Forced Commutation Output Voltage Factor during Voltage Drive
	Set a value $x: 0 < x < 1$
	Determine the output voltage during the forced commutation. The multiplication of this setup and the reference speed is defined as the output voltage. $V_d = cSPD_COEF \times \Omega_{com}$ Enabled only when the cBOOT_TYPE is "cBoot_v" For details, refer to 12.2.3.2.
cHZ_V2I	Changeover Speed from Voltage Control to Current Control
	Unit [Hz]
	Set up a speed for changeover from the voltage control to the current control. When the motor estimated speed becomes faster than cHZ_MIN, the stage transitions from Forced Commutation to Steady, and voltage control is changed over to current control. Enabled only when the cBOOT_TYPE is "cBoot_v"
cENC_PULSE_NUM	Setup of the Number of Encoder Pulses
	Unit [ppr]

	Set up the number of pulses for the encoder. Small value for the number of encoder pulses will degrade the speed detection accuracy. If the detected speed is not stable, increase the filtering factor cOMEGAENC_AVE.
cENC_DEG_ADJUST	Encoder Position Adjustment
	Unit [deg]
	Set up the shifted positional angle of phase-Z with regard to the electrical angle 0°
cENC_NOISE_TIME	Setup of Encoder Input Signal Noise Cancellation Time (Only A-ENC is enabled)
	Unit [μs] Resolution fc (12.5ns@80MHz)
	Set up the noise cancellation time of the encoder input signal. The signals shorter than this setup time will be canceled. This setup will be enabled only for the microcontroller equipped with A-ENC.
__FIXED_VDC	Setup of Power Supply Voltage Fixing
	0: Detected Value, 1: Fixed Value
	When setting the power supply voltage to a fixed value, set up to "1"
cVDC	Fixed Power Supply Voltage
	Unit [V]
	Set up the power supply voltage. Enabled only when the __FIXED_VDC is "1"
cTRGCMP0_SHIFT2	Shift PWM2 Trigger 0 Compensation Time Setting(VE)
	Unit[ns]
	Range:0 to (cPWMPRD/2)
cTRGCMP1_SHIFT2	Shift PWM2 Trigger 1 Compensation Time Setting(VE)
	Unit[ns]
	Range:0 to (cPWMPRD/2)
cLS_CONT_MD	Shift PWM2 Mode Setting
	0: Normal PWM/ 5: Shift PWM2
	Set 1-shunt1 PWM
cAD_TRG0_MODURATION_SHIFT2	Shift PWM2 Trigger 0 Time Setting(Software)
	Unit[%]
	Range:0 to 100%
cAD_TRG1_MODURATION_SHIFT2	Shift PWM2 Trigger 1 Time Setting(Software)
	Unit[%]
	Range:0 to 100%
cHZ_SPWM2	Normal /Shift PWM2 Mode switching Speed
	Unit[Hz]
	Set the speed at which switching occurs between Shift PWM2 ⇔ Normal PWM during speed-detection

	configuration. Switching is performed based on the control command Speed value.
cHZ_SPWM2_HYS	Normal /Shift PWM2 Mode switching speed Hysteresis
	Unit[Hz]
	Set the hysteresis for the speed used when switching between Shift PWM2 ⇔ Normal PWM during speed-detection configuration. Switching is performed using the value after subtracting the control command Speed.
cIA_OFFSET_SHIFT2_U_CENTER	U-phase current offset(U-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for three-phase current affected by current ripple. (Note2)
cIB_OFFSET_SHIFT2_U_CENTER	V-phase current offset(U-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIC_OFFSET_SHIFT2_U_CENTER	W-phase current offset(U-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIA_OFFSET_SHIFT2_V_CENTER	U-phase current offset(V-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIB_OFFSET_SHIFT2_V_CENTER	V-phase current offset(V-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for 3phase current affected by current ripple. (Note3)
cIC_OFFSET_SHIFT2_V_CENTER	W-phase current offset(V-phase Center) for Shift PWM2
	Unit[A/AMAX]
	This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIA_OFFSET_SHIFT2_W_CENTER	U-phase current offset(W-phase Center) for Shift PWM2
	Unit[A/AMAX]

	This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIB_OFFSET_SHIFT2_W_CENTER	V-phase current offset(W-phase Center) for Shift PWM2 Unit[A/AMAX] This is the correction value for 3phase current affected by current ripple. Adjust based on the current waveform obtained from DAC output.
cIC_OFFSET_SHIFT2_W_CENTER	W-phase current offset(W-phase Center) for Shift PWM2 Unit[A/AMAX] This is the correction value for 3phase current affected by current ripple. (Note2)
cVD_LIMIT_SHIFT2	d-axis voltage Limit for Shift PWM2 Unit[V] Set the d-axis current limit used when Shift PWM2 is active. If the calculated d-axis voltage exceeds this value, it will be clamped to the limit.
cvQ_LIMIT_SHIFT2	q-axis voltage Limit for Shift PWM2 Unit[V] Set the q-axis current limit used when Shift PWM2 is active. If the calculated q-axis voltage exceeds this value, it will be clamped to the limit.
cCOMP_OVC	Internal Comparator Over-Current Detection Value (Positive / Negative Current) Unit[A] Set the over-current detection thresholds for the internal comparator. If coil current exceeds this value, the output will be turned OFF by software.
__Flux_CONTROL_MOTOR	Flux Observer Control Setting 0: Disable/ 1: Enable Enable or disable Flux Observer control.
cDETECT_TYPE	Position Detection Method Setting 0: Induced Voltage Method / 1:Flux Observer Method Select the position-detection method.
cPHI_MAX	Maximum Flux Value Setting Unit[Wb] Modify the value according to the PCB design.

cFORCE2_ONOFF	Forced Commutation 2 Setting
	cForce2_on: Enabled / cForce2_off: Disabled
	Enable or disable Forced Commutation 2.

Note1: Operation during Shift PWM has not been evaluated.

Apply a method such as starting in voltage mode to use the Shift PWM function.

Note2: U-phase current is calculated by software; therefore, this setting is fixed to 0.

Note3: V-phase current is calculated by software; therefore, this setting is fixed to 0.

12.2.3 Relationship of Constant Setups and Waveform

12.2.3.1 Constants for Current Type Starting

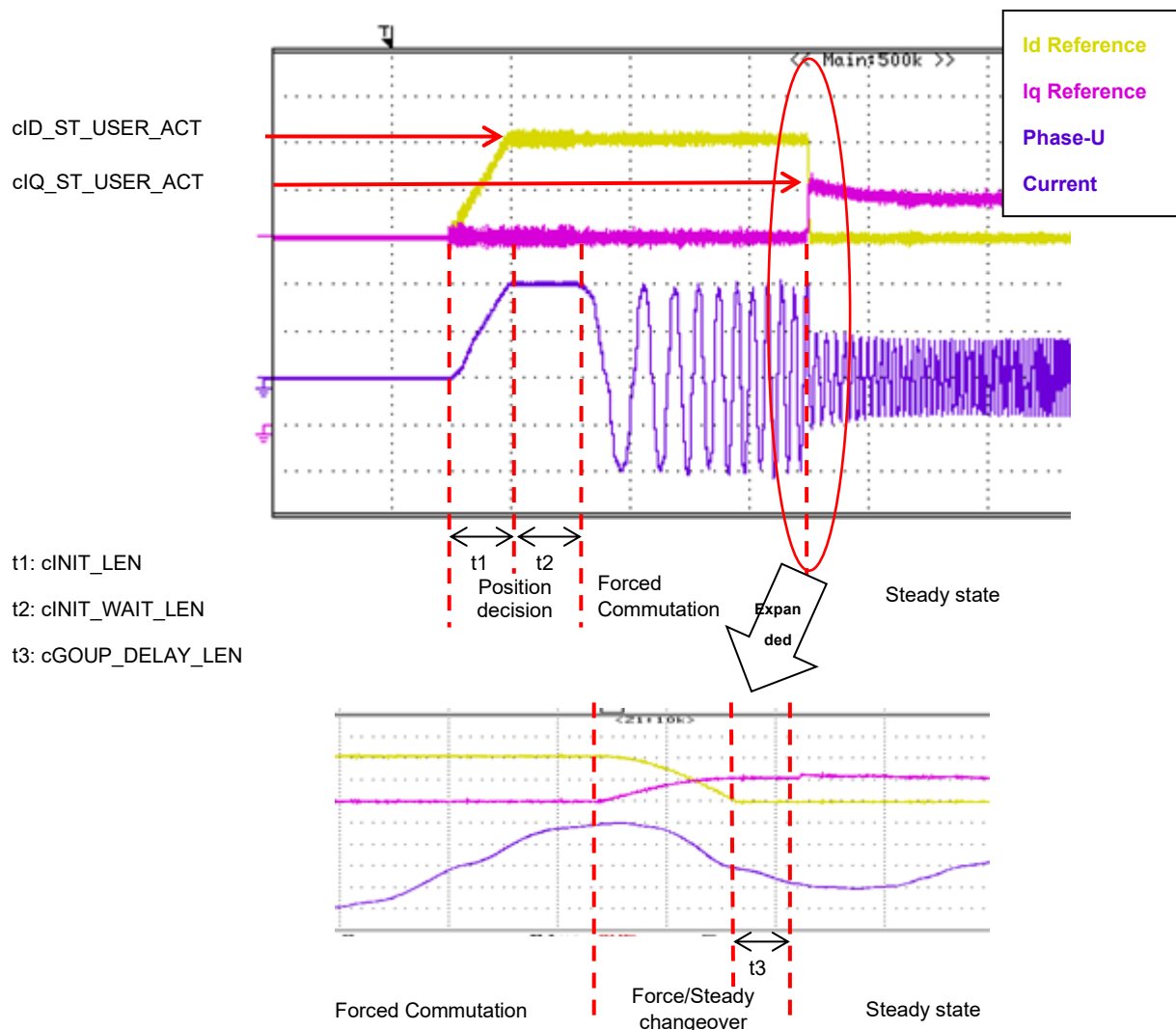


Figure 12.1 Starting Current Waveform (Positioned to electrical angle 0°)

In the Change-up Stage, the values of `cID_ST_USER_ACT` and `cIQ_ST_USER_ACT` will be updated. After upgrading, the control will be conducted with a constant reference value of `Iq` only for the time of `cGOUP_DELAY_LEN`.

After transferring to the steady state, the `Iq` reference value will be computed by the PI control.

12.2.3.2 Constants for Voltage Type Starting

Determine the constants while checking the current waveform on an oscilloscope.

Observing the current waveform, the cVD_POS value should be adjusted to be the target current value.

The voltage Vd during the forced commutation is calculated by the following formula.

$$\text{Speed} \times \text{Constant value cSPD_COEF}$$

The cSPD_COEF value should be adjusted for the current in the forced

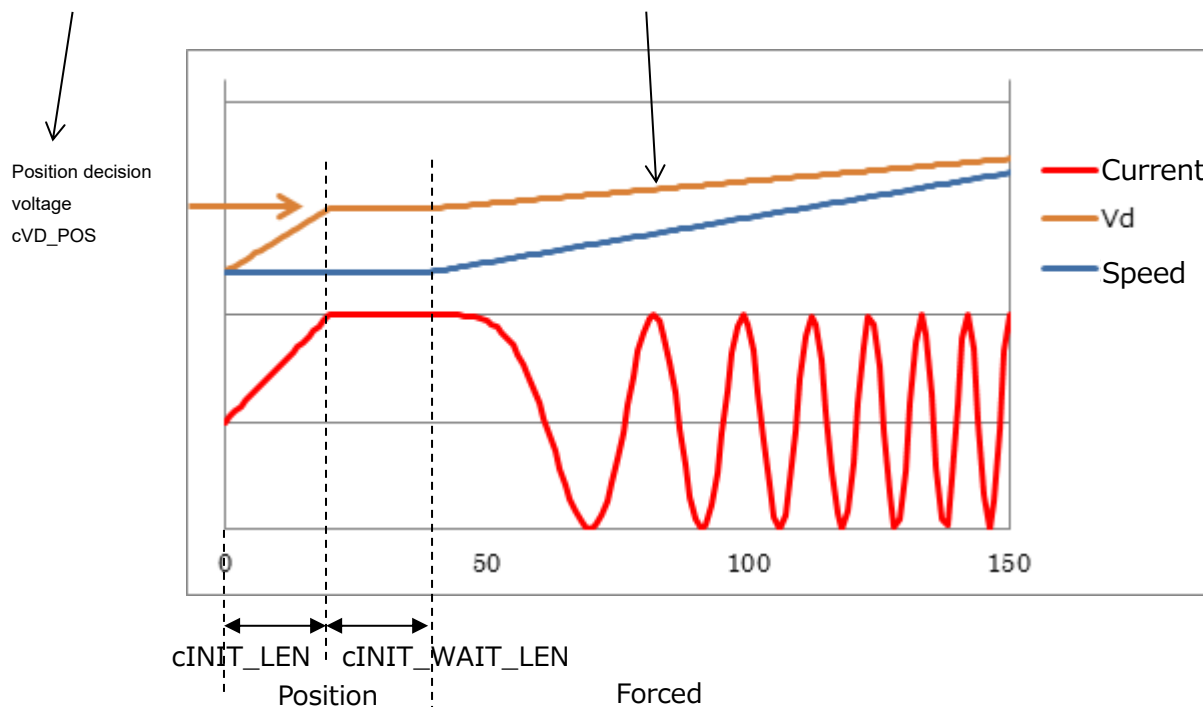


Figure 12.2 Parameter adjustment at Voltage drive

12.3 Constants for User Control

/*Initial value*/

```
#define cINIT_VALUE      (0)
```

```
#define cINIT_FF         (0xff)
```

/* Key setting */

```
#define cS_SW1            (*((__IO uint32_t *)BITBAND_PERI(&TSB_PH->DATA, 1)))    /* SW1 */
#define cS_SW2            (*((__IO uint32_t *)BITBAND_PERI(&TSB_PA->DATA, 7)))    /* SW2 */
#define cS_SW3            (*((__IO uint32_t *)BITBAND_PERI(&TSB_PE->DATA, 1)))    /* SW3 */
#define cS_SW4            (*((__IO uint32_t *)BITBAND_PERI(&TSB_PE->DATA, 2)))    /* SW4 */
#define cUSW1             (*((__IO uint32_t *)BITBAND_PERI(&TSB_PJ->DATA, 0)))    /* USW1 */
#define cUSW2             (*((__IO uint32_t *)BITBAND_PERI(&TSB_PJ->DATA, 1)))    /* USW2 */
#define cUSW3             (*((__IO uint32_t *)BITBAND_PERI(&TSB_PE->DATA, 3)))    /* USW3 */
#define cKEY_CHATA_CNT    (20)           /* [cnt] chattering counter for KEY SW */
#define cKEY_NO_INPUT    (0x00)         /* USW1 to 3 no input */
#define cKEY_MASK_USW    (0x07)         /* USW1 to 3 mask */
```

```

#define cKEY_INPUT_USW1      (0x01)      /* USW1 input */
#define cKEY_INPUT_USW2      (0x02)      /* USW2 input */
#define cKEY_INPUT_USW3      (0x04)      /* USW3 input */

/* Soft ADC Setting */
#define cADUNIT_VR            TSB_ADA      /* VR ad data ADCUnit */
#define cADUNIT_TEMPO         TSB_ADA      /* TEMPO ad data ADCUnit */

#define cADTRG_USR            ADC_TRG_SINGLE /* AD Trigger Type */

#define cADCH_VR              ADC_AIN4      /* ADC Channel for VR */
#define cADREG_VR             ADC_REG8      /* Result register Number for VR */
#define cADCH_TEMPO           ADC_AIN13     /* ADC Channel for TEMPO */
#define cADREG_TEMPO          ADC_REG9      /* Result register Number for TEMPO */

#define cADAVECNT             (10)          /* ADC average count */
#define cONE_ABOVE            (1)

/* Speed Control Setting */
#define cSPEED_USER_STOP      (0)
#define cSPEED_USER_MIN_CH0   cHZ_MIN_CH0 /* [Hz] Min Target speed of motor ch0 */
#define cSPEED_USER_MAX       (200)        /* [Hz] Max Target speed of motor ch0*/
#define cAD_MIN               (0x10)        /* Voltage value 0.3V */
#define cAD_MAX               (0xF0)        /* Voltage value 4.7V */

/* DACMODE setting */
#define cDACMODE_MIN          (0)           /* DACMODE count0 */
#define cDACMODE_MAX          (3)           /* DACMODE count3 */

/* LED setting */
#define cLED_EMG_CH0 (*( (__IO uint32_t *)BITBAND_PERI(&TSB_PD->DATA, 4))) /* LED4 */
#define cLED_ON               (1)           /* LED ON level */
#define cLED_OFF              (0)           /* LED OFF level */

/* State control Setting */
#define cMOTOR_CH0            (0x00)        /* Control channel : CH0 */

/* UART Setting */
#define cUART_BRD_INIT        ((uint32_t)0x00A6002B)
#define cUART_CLK_INIT        ((uint32_t)0x00000000)

```

```
#define cUART_CRO_INIT          ((uint32_t)0x00000001)
#define cUART_CR1_INIT          ((uint32_t)0x00000040)
#define cUART_SEND_WAIT        (1000)
#define cUART_COUNT             (0)
#define c1MHz                   (1000000)
#define cLOW_ACTIVE             (0)
#define cSWRST10                (0x2U)
#define cSWRST01                (0x1U)
#define cSWRSTF                 (0x80)
#define cSendBufSIZE            (80+1)

#define cDISP_INI_STATUS        (0x00) /* Initial status display */
#define cDISP_CONTROL_CH        (0x01) /* Control channel display */
#define cDISP_CARRIER_FREQUENCY (0x02) /* Carrier frequency display */
#define cDISP_DEAD_TIME         (0x03) /* Dead time display */
#define cDISP_GATE_ACTIVE       (0x04) /* Gate active display */
#define cDISP_POSITION_DETECT   (0x05) /* position detect display */
#define cDISP_VDC_VOLTAGE       (0x06) /* VDC voltage display */
#define cDISP_INVERTER_TEMP     (0x07) /* Inverter Temp */
#define cDISP_UVW_VOLTAGE       (0x08) /* U-phase/V-phase/W-phase voltage display */
#define cDISP_DAC_DATA          (0x09) /* Dac data display */
#define cDISP_INTERNAL_AMP       (0x0A) /* Internal amp display */
#define cDISP_DIRECTION         (0x0B) /* Direction display */
#define cDISP_MODULATION        (0x0C) /* Modulation display */
#define cDISP_ROTATE_INSTRUCTION (0x0D) /* Rotate instruction display */
#define cPOSITION_DETECT_3SHUNT  (3) /* Position Ditect : 3shunt */
#define cPOSITION_DETECT_1SHUNT  (1) /* Position Ditect : 1shunt */

/* User_interface Setting */
#define cFLG_ON                  (1)
#define cFLG_OFF                 (0)
#define cSW_Hi                   (1)
#define cSW_Low                  (0)
#define cROTATION_CW              (1)
#define cROTATION_CCW             (0)
#define cSPDTEMP_CHG_SPD         (1)
#define cSPDTEMP_CHG_TEMP        (0)
#define cINV_MIN_TEMP            (-200)
#define cINV_MAX_TEMP            (1000)
```

13. Timings for Control and Data Update

13.1 Vector Control Using Software

13.1.1 3-shunt Control

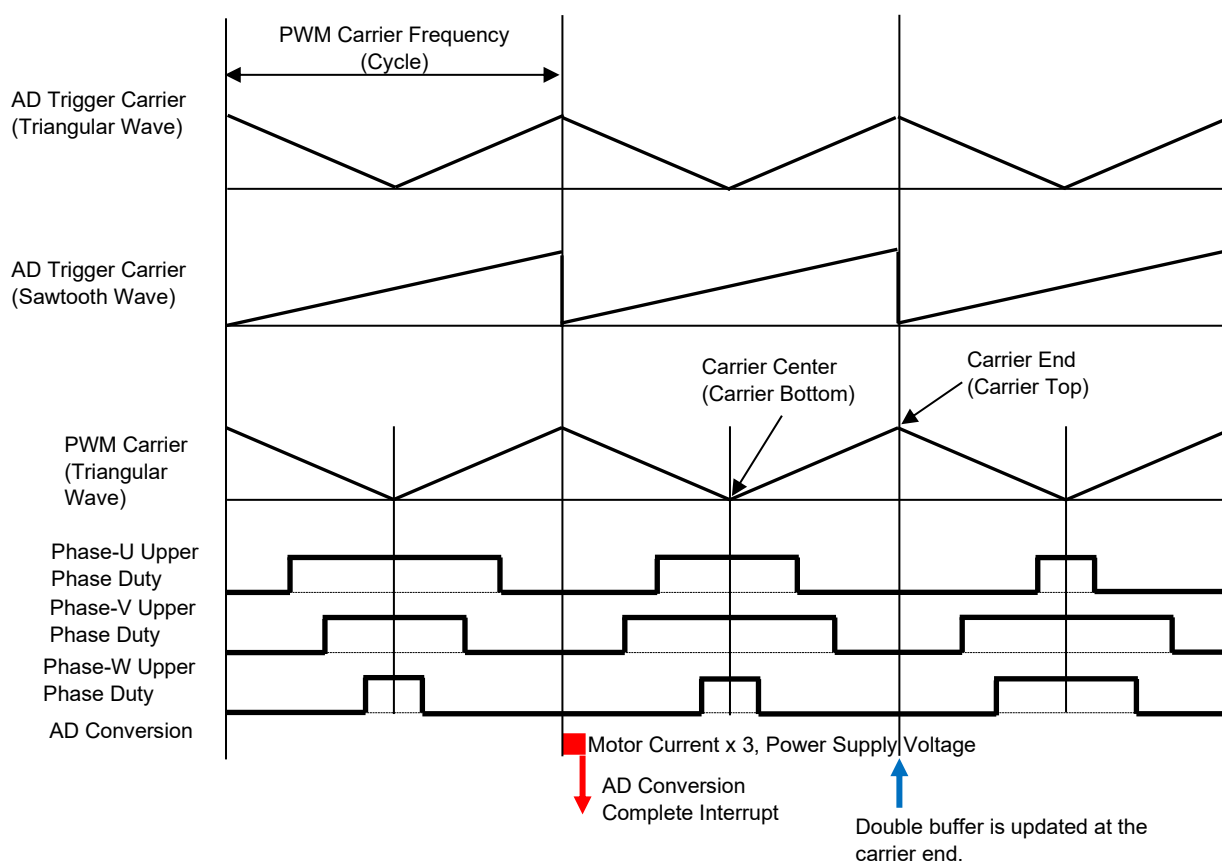


Figure 13.1 3-shunt Control

13.1.1.1 Carrier Waveform

Type	Waveform
PWM	Triangular Wave (for all three phases)
AD Trigger	Sawtooth Wave

13.1.1.2 Double Buffer Update Timing

Data	Update Timing
PWM Cycle (RATE)	Carrier End
Duty Value (CMPU, CMPV, CMPW)	Carrier End
Trigger Position (TRGCMPx)	Carrier End
Output Setup (MDOUT)	Carrier End

13.1.1.3 Interruption

Interruption Request	Interruption	Timing
PWM(PMD)	Prohibited	Once every one time, twice and four times.
AD Conversion Complete	Permitted	After completing the AD conversion for all of motor current x 3 and power supply voltage.
AD Trigger	—	Same frequency as PWM

13.1.2 1-shunt Control

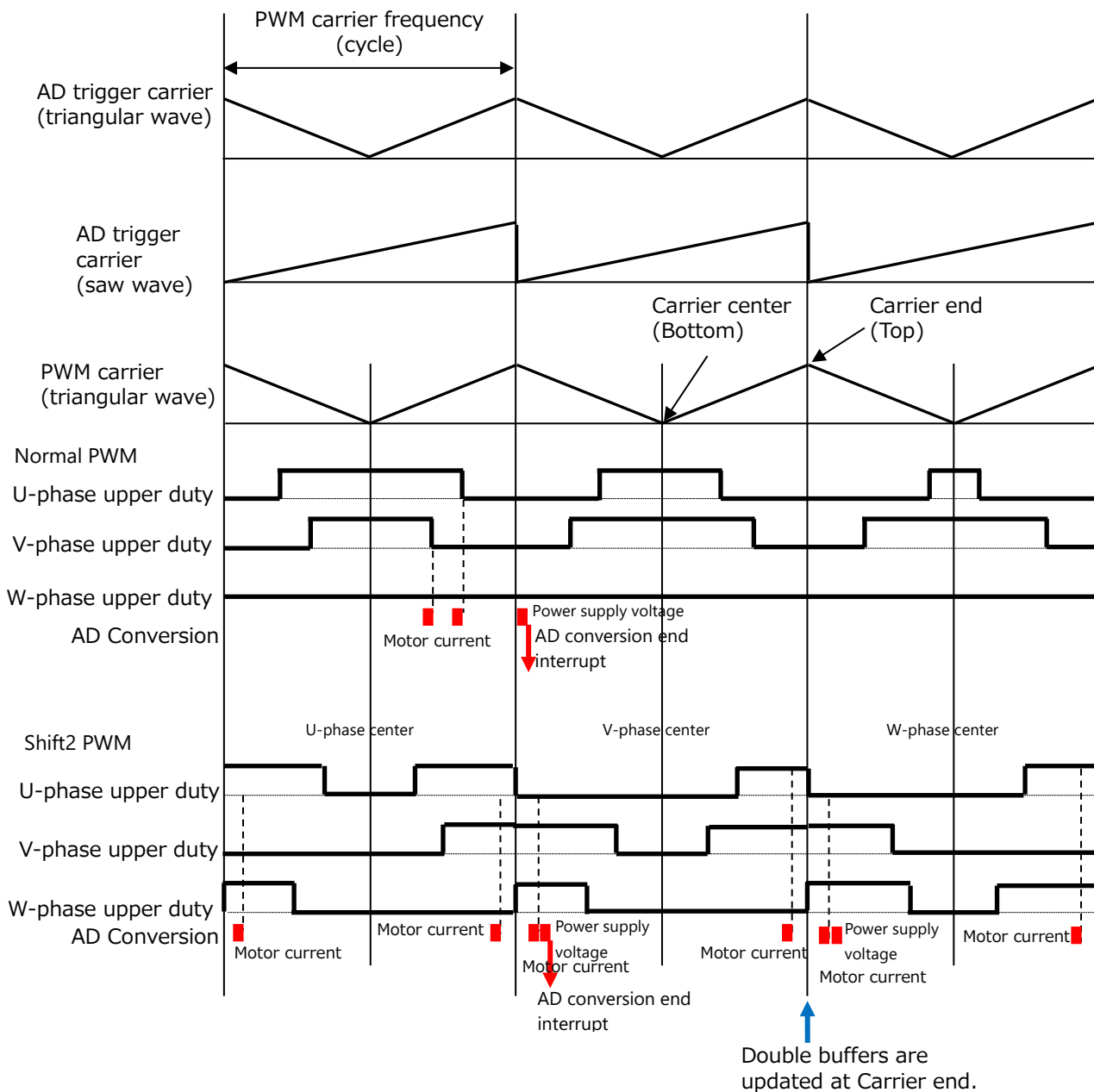


Figure 13.2 1-shunt Control

13.1.2.1 Carrier Waveform

Type	Waveform	
	Normal PWM	Shift2 PWM
PWM	Triangular Wave (for all three phases)	Center (Triangular Wave), Non-center (Sawtooth Wave and Reverse Sawtooth Wave)
AD Trigger	Sawtooth Wave	Sawtooth Wave

13.1.2.2 Double Buffer Update Timing

Data	Update Timing
PWN Cycle (RATE)	Carrier End
Duty Value (CMPU, CMPV, CMPW)	Carrier End
Trigger Position (TRGCMPx)	Carrier End
Output Setup (MDOUT)	Carrier End

13.1.2.3 Interruption

Interruption Request	Interruption	Timing
PWM(PMD)	Prohibited	Once every one time, twice and four times.
AD Conversion Complete	Permitted	After completion of AD conversion of power supply voltage
AD Trigger	—	Same frequency as PWM

13.2 Vector Control by VE

13.2.1 3-shunt Control

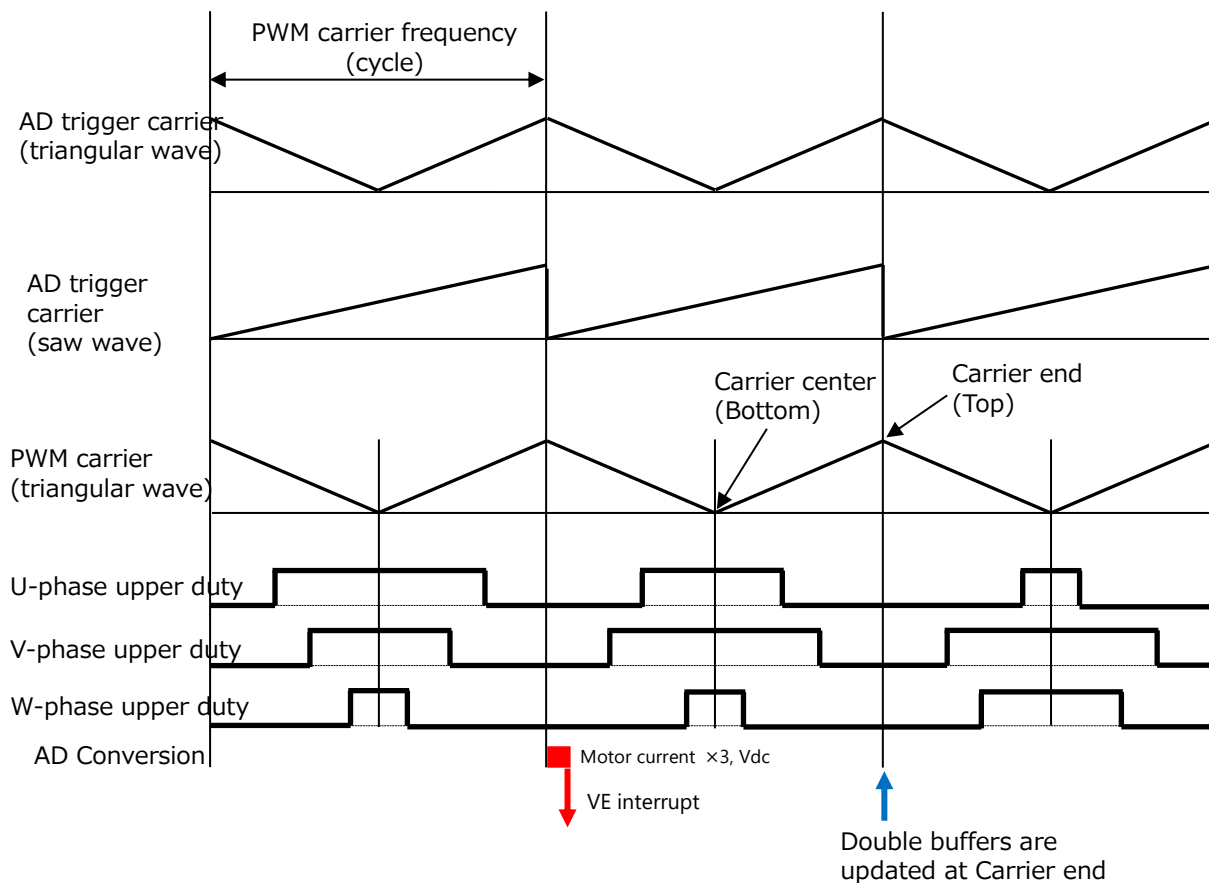


Figure 13.3 3-shunt Control

13.2.1.1 Carrier wave

Type	Waveform
PWM	Triangular waves for all three phases
AD trigger	Saw wave

13.2.1.2 Update Timing for Double Buffers

Data	Update timing
PWM cycle (RATE)	Carrier end
Duty value (CMPU, CMPV, and CMPW)	Carrier end
Trigger position (TRGCMPlx)	Carrier end
Output setting (MDOUT)	Carrier end

13.2.1.3 Interrupt

Interrupt request	Interrupt	Timing
VE	Enable	After the VE input schedule ends
PWM (PMD)	Disable	Every time, Every two times, and Every four times
AD conversion end	Disable	After completion of all AD conversions of Motor current $\times 3$ and Power supply voltage
AD trigger	—	The same frequency as PWM

13.2.2 1-shunt Control

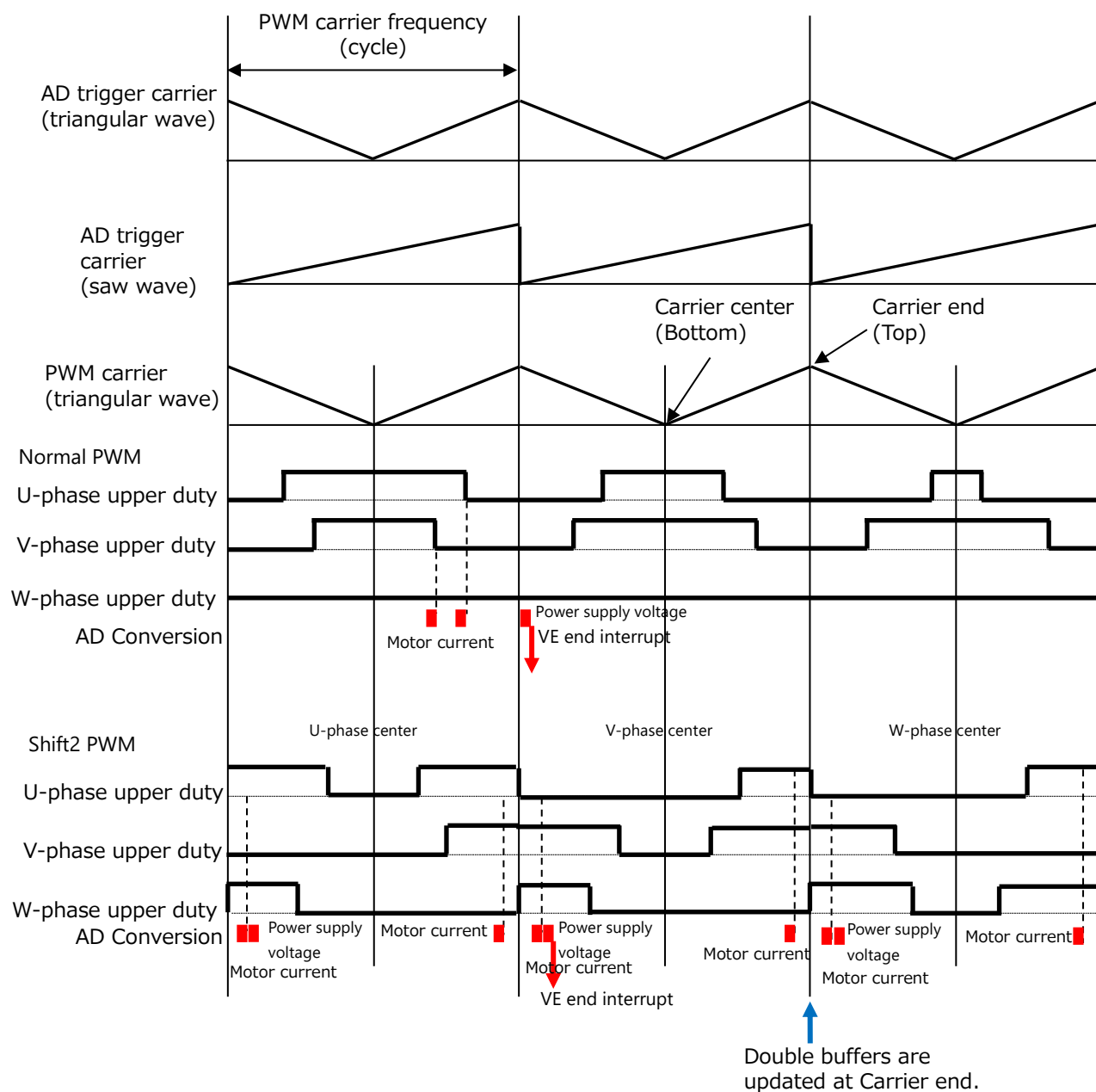


Figure 13.4 1-shunt Control

13.2.2.1 Carrier wave

Type	Waveform	
	Normal PWM	Shift2 PWM
PWM	Triangular waves for all three phases	Center (Triangular Wave), Non-center (Sawtooth Wave and Reverse Sawtooth Wave)
AD trigger	Sawtooth wave	Sawtooth wave

13.2.2.2 Update Timing for Double Buffers

Normal PWM

Data	Update timing
PWM period (RATE)	Carrier end
Duty value (CMPU, CMPV, and CMPW)	Carrier end
Trigger position (TRGCMPx)	Carrier end
Output setting (MDOUT)	Carrier end

Shift2 PWM

Data	Update timing
PWM period (RATE)	Carrier end
Duty value (CMPU, CMPV, and CMPW)	Carrier end
Trigger position (TRGCMPx)	Carrier end
Output setting (MDOUT)	Carrier end

13.2.2.3 Interrupt

Interrupt request	Interrupt	Timing
VE	Enable	After the VE input schedule ends
PWM (PMD)	Disable	Every time, Every two times, and every four times
AD conversion end	Disable	After completion of AD conversion of Power supply voltage.
AD trigger	—	The same frequency as PWM

14. Peripheral Driver

14.1 Microcontroller Peripheral Circuit Addresses

Define the base addresses of microcontroller peripheral circuit registers to be passed to the peripheral driver API.

14.1.1 Data Structure

14.1.1.1 ipdrv_t

Data Fields:

TSB_VE_TypeDef* const	VE_x : Select an VE Address.
TSB_PMD_TypeDef* const	PMD_x : Select an PMD Address.
TSB_AD_TypeDef* const	AD_x : Select an ADC Address.

14.2 Vector Engine (VE)

14.2.1 Function Specification

14.2.1.1 IP_VE_init

VE initial setting

API:

```
void IP_VE_init(TSB_VE_TypeDef* const VEx, VE_InitTypeDef* const _initdata)
```

Argument:

VE_x: Select VE address

_initdata: VE initial setting data structure

For details, see 14.2.2.1 VE_InitTypeDef.

Function:

Perform initial setting of VE.

Comment:

This function should be called when the VE stops, and the interrupt is disabled.

Return value:

None

14.2.1.2 VE_Start

Start of VE

API:

```
void VE_Start(Const ipdrv_t* const _ipdrv);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Start VE.

Comment:

None

Return value:

None

14.2.1.3 VE_GetPhaseCurrent

Acquisition of phase currents

API:

```
void VE_GetPhaseCurrent(const ipdrv_t* const _ipdrv,  
                        q15_t* _ia, q15_t* _ib, q15_t* _ic);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined.

For details, see Section **エラー! 参照元が見つかりません。**

_ia: Set the variable address that stores the a-phase current.

_ib: Set the variable address that stores the b-phase current.

_ic: Set the variable address that stores the c-phase current.

Function:

Acquire the current value of each phase.

U-phase, V-phase, and W-phase current values are assigned to the a-phase, b-phase, and c-phase current values, respectively.

Comment:

None

Return value:

None

14.2.1.4 VE_GetCurrentAdcData

Acquisition of AD conversion value of current

API:

```
void VE_GetCurrentAdcData(const ipdrv_t* const _ipdrv,  
                          uint32_t* _adc_ia, uint32_t* _adc_ib, uint32_t* _adc_ic);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_adc_ia: Set the variable address that stores the a-phase current AD value.

_adc_ib: Set the variable address that stores the b-phase current AD value.

_adc_ic: Set the variable address that stores the c-phase current AD value.

Function:

Obtain the values of IAADCx, IBADCx, and ICADCx registers as the current AD values of the corresponding phases.

Comment:

None

Return value:

None

14.2.1.5 VE_GetdataFromVEreg

Acquisition of VE register data

API:

```
void VE_GetdataFromVEreg(const ipdrv_t* const _ipdrv, vector_t* const  
_motor)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Store the values of Power supply voltage of the motor Vdc, d-axis voltage Vd, q-axis voltage Vq, d-axis current Id, and q-axis current Iq from the VE registers to the corresponding vector control variables.

When no currents can be detected due to improper duty widths, write the previous detection values of the d-axis current Id and the q-axis current Iq to the VE registers.

Comment:

None

Return value:

None

14.2.1.6 VE_GetPWM_DutyU

Acquisition of U-phase duty value

API:

uint32_t VE_GetPWM_DutyU(const ipdrv_t* const _ipdrv)

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the value of the U-phase duty register.

Comment:

None

Return value:

U-phase duty

14.2.1.7 VE_GetPWM_DutyV

Acquisition of V-phase duty value

API:

uint32_t VE_GetPWM_DutyV(const ipdrv_t* const _ipdrv)

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the value of the V-phase duty register.

Comment:

None

Return value:

V-phase duty

14.2.1.8 VE_GetPWM_DutyW

Acquisition of W-phase duty value

API:

uint32_t VE_GetPWM_DutyW(const ipdrv_t* const _ipdrv)

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the value of the W-phase duty register.

Comment:

None

Return value:

W phase Duty

14.2.1.9 VE_GetPWM_DutyMed

Acquisition of middle duty values

API:

uint32_t VE_GetPWM_DutyMed(const ipdrv_t* const _ipdrv)

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the middle value of the U, V, and W-phase duties.

Comment:

None

Return value:

Middle value of Duty

14.2.1.10 VE_GetPWM_Modulation

Acquisition of a modulation mode

API:

```
int VE_GetPWM_Modulation(const ipdrv_t* const _ipdrv)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the modulation mode.

Comment:

None

Return value:

Modulation mode 0: 3-phase modulation, 1: 2-phase modulation

14.2.1.11 VE_GetSector

Acquisition of a current sector number

API:

```
uint32_t VE_GetSector(const ipdrv_t* const _ipdrv)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire the current sector number.

Comment:

None

Return value:

Current sector number [0-11]

14.2.1.12 VE_GetShiftPWMState

Acquisition of Shift PWM state

API:

```
int VE_GetShiftPWMState(const ipdrv_t* const _ipdrv)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire Shift PWM state.

Comment:

None

Return value:

Shift PWM state 0: Normal PWM, 1: Shift PWM

14.2.1.13 VE_GetOutputMode

Acquisition of PWM output state

API:

```
int VE_GetOutputMode(const ipdrv_t* const _ipdrv)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

Function:

Acquire PWM output state.

Comment:

None

Return value:

PWM state: OCRMD_OUT_OFF: Output OFF
 OCRMD_OUT_ON: Output ON
 OCRMD_OUT_ON_LOWPH: Only Lower phases are ON.

14.2.1.14 VE_SetdataToVEreg_Stop

Data set to VE register (Stop)

API:

```
void VE_SetdataToVEreg_Stop(const ipdrv_t* const _ipdrv,  
                             const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register in the Stop stage.

Initialize the Current control integral gain value register and others.

Set the Program Task Pointer Start Register to 0.

Comment:

None

Return value:

None

14.2.1.15 VE_SetdataToVEreg_Bootstrap

Data set to VE register (Bootstrap)

API:

```
void          VE_SetdataToVEreg_Bootstrap(const ipdrv_t* const _ipdrv,  
                                           const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register in the Bootstrap stage.

Using the VE short circuit braking function, a waveform is output in which only the L side turns ON.

Set the Program Task Pointer Start Register to 3.

Comment:

None

Return value:

None

14.2.1.16 VE_SetdataToVEreg_Initposition_i

Data set to VE register (Initposition of Current control type)

API:

```
void          VE_SetdataToVEreg_Initposition_i (const ipdrv_t* const _ipdrv,  
                                                const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the current control type Positioning stage.

In the program task pointer start register,
Set "20" when in Shift PWM2 mode, and "11" for all other modes.

Comment:

None

Return value:

None

14.2.1.17 VE_SetdataToVEreg_Initposition_v

Data set to VE register (Initposition of Voltage control type)

API:

```
void VE_SetdataToVEreg_Initposition_v (const ipdrv_t* const _ipdrv  
                                         const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the voltage control type Positioning stage.

Set the Program Task Pointer Start Register to 3.

Comment:

None

Return value:

None

14.2.1.18 VE_SetdataToVEreg_Force_i

Data set to VE register (Forced commutation of Current control type)

API:

```
void VE_SetdataToVEreg_Force_i (const ipdrv_t* const _ipdrv,  
                                const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the current control type Forced commutation stage.

In the program task pointer start register,

Set "20" when in Shift PWM2 mode, and "11" for all other modes.

Comment:

None

Return value:

None

14.2.1.19 VE_SetdataToVEreg_Force_v

Data set to VE register (Forced commutation of Voltage control type)

API:

```
void VE_SetdataToVEreg_Force_v(const ipdrv_t* const _ipdrv,  
                                const vector_t* const _motor)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the voltage control type Forced commutation stage.

Set the Program Task Pointer Start Register to 3.

Comment:

None

Return value:

None

14.2.1.20 VE_SetdataToVEreg_Change_up

Data set to VE register (Force-to-Steady Switching)

API:

```
void          VE_SetdataToVEreg_Change_up (const ipdrv_t* const _ipdrv,  
                                             const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the Force-to-Steady switching (Change-up) stage.

In the program task pointer start register,
Set "20" when in Shift PWM2 mode, and "11" for all other modes.

Comment:

None

Return value:

None

14.2.1.21 VE_SetdataToVEreg_Steady_A

Data set to VE register (Steady)

API:

```
void VE_SetdataToVEreg_Steady_A (const ipdrv_t* const _ipdrv,  
                                const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set structure address of vector control variable

Function:

Perform the setting processing to the VE register of the Steady stage.

In the program task pointer start register,

Set "20" when in Shift PWM2 mode, and "11" for all other modes.

Comment:

None

Return value:

None

14.2.1.22 VE_SetdataToVEreg_Change_down

Data set to VE register (Change_down)

API:

```
void          VE_SetdataToVEreg_Change_down (const ipdrv_t* const _ipdrv,  
                                              const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set structure address of vector control variable

Function:

Perform the setting processing to the VE register of the Steady-to-Force switching (Change-down) stage.

In the program task pointer start register,

Set "20" when in Shift PWM2 mode, and "11" for all other modes.

Comment:

None

14.2.1.23 VE_SetdataToVEreg_Emergency

Data set to VE register (EMG)

API:

```
void          VE_SetdataToVEreg_Emergency (const ipdrv_t* const _ipdrv,  
                                             const vector_t* const _motor);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined.

For details, see Section **エラー! 参照元が見つかりません。**

_motor: Set the structure address of the vector control variable.

Function:

Perform the setting processing to the VE register of the Emergency stage.

Set the Program Task Pointer Start Register to 0.

Comment:

None

Return value:

None

14.2.1.24 VE_SetZeroCurrentData

Zero current setting

API:

```
void VE_SetZeroCurrentData(const ipdrv_t* const _ipdrv,  
                           uint32_t _z_ia, uint32_t _z_ib, uint32_t _z_ic)
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined.

For details, see Section エラー! 参照元が見つかりません。。

_z_ia: Set a-phase zero current AD value.

_z_ib: Set b-phase zero current AD value.

_z_ic: Set c-phase zero current AD value.

Function:

Set the AD value at zero current to the VE register.

Comment:

None

Return value:

None

14.2.1.25 VE_SetVDCreg

Setting of Power supply voltage of the motor Vdc.

API:

```
void VE_SetVDCreg(const ipdrv_t* const _ipdrv, q15_t _dat);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined.

For details, see Section **エラー! 参照元が見つかりません。**

_dat: Set the power supply voltage of the motor

Function:

Set the power supply voltage of the motor to the VE register.

Comment:

None

Return value:

None

14.2.1.26 VE_SetSpwmMode

Setting of Shift PWM mode

API:

```
void VE_SetSpwmMode(const ipdrv_t* const _ipdrv, uint8_t _dat);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_dat: Select Shift PWM mode.

Function:

Set the status of the shift PWM mode to the VE register.

Comment:

None

Return value:

None

14.2.1.27 VE_SetModulType

Modulation mode setting

API:

```
void VE_SetModulType (const ipdrv_t* const _ipdrv, uint8_t _dat);
```

Argument:

_ipdrv: Specify the structure where the MCU peripheral addresses are defined. For details, see Section **エラー! 参照元が見つかりません。**

_dat: Select the modulation mode.

Function:

Set the modulation mode to the VE register.

Comment:

None

Return value:

None

14.2.2 Data Structure

14.2.2.1 VE_InitTypeDef

Data Fields:

uint8_t	shunt: Shunt type 1: 1-shunt 3: 3-shunt
uint16_t	reptime: Repeat times (1 to 15)
uint16_t	trgmode: Startup trigger TRGMODE_UNITA: Activated by ADCA PMD0 trigger synchronous conversion end interrupt
uint16_t	tpwm: PWM cycle time (For phase interpolation) Value to be set in the VETPWM register
uint16_t	idkp: d-axis current control proportional gain
uint16_t	idki: d-axis current control integral gain
uint16_t	iqkp: q-axis current control proportional gain
uint16_t	iqki: q-axis current control integral gain
uint16_t	zerooffset: Zero current offset value
uint16_t	trgcomp0: Trigger timing 0 setting Value to be set in the VExTRGCOMP0 register
uint16_t	trgcomp1: Trigger timing 1 setting Value to be set in the VExTRGCOMP1 register
uint32_t	fmode: Flow control setting Value to be set in the VExFMODE register
uint16_t	fpwmchg: PWM switch speedsetting Value to be set in the VExFPWMCHG register
uint16_t	piolim: PI control output limitation setting Value to be set in the VExPIOLIM register

14.3 Motor Control Circuit (PMD)

14.3.1 Specifications of Functions

14.3.1.1 IP_PMD_init

PMD Initial Setup

API:

void IP_PMD_init(TSB_PMD_TypeDef* const PMDx, PMD_InitTypeDef* const _initdata)

Parameter:

PMDx: Select a PMD address

_initdata: PMD Initial Setup Data Structure

For details, refer to 14.3.2.1 PMD_InitTypeDef.

Function:

Initial setup of PMD

Supplement:

Call up during PMD suspension with prohibited interruption.

Returned Value:

No

14.3.1.2 PMD_GetEMG_Status

Acquisition of EMG Protection Status

API:

emg_status_e PMD_GetEMG_Status(const ipdrv_t* const _ipdrv)

Parameter:

_ipdrv: Specify the structure where the microcontroller peripheral circuit addresses are defined.

For details, refer to 14.1.1.1.

Function:

Acquires the EMG protection status.

Supplement:

None

Returned Value:

emg_status_e: EMG Protection Status

cNormal: Normal

cEMGProtected: Protected

14.3.1.3 PMD_ReleaseEMG_Protection

EMG Protection Status Released

API:

Void PMD_ReleaseEMG_Protection(const ipdrv_t* const _ipdrv)

Parameter:

_ipdrv: Specify the structure where the microcontroller peripheral circuit addresses are defined.

For details, refer to 14.1.1.1.

Function:

Releases the EMG protection status.

Supplement:

Even if this function is called up, the protection status will not be released unless the MDOUT is 0 and the EMG port is H.

Returned Value:

No

14.3.2 Data Structure

14.3.2.1 PMD_InitTypeDef

Data Fields:

uint8_t shunt: Shunt Type

1: 1-shunt

3: 3-shunt

uint8_t poll: L-Side Polarity

0: L active

1: H active

uint8_t polh: H-Side Polarity

0: L active

1: H active

uint16_t pwmrate: PWM Frequency

A value to be set up to PMDxRATE

uint16_t pwmfreq: PWM Frequency

A value to be set up to PMDxMDPRD

uint16_t deadtime: Dead Time

A value to be set up to PMDxDTR

uint8_t busmode: Mode Selection

A value to be set up to PMDxMODESEL

14.4 Analogue Digital Converter (ADC)

14.4.1 Specifications of Functions

14.4.1.1 IP_ADC_init

ADC Initial Setup

API:

```
void IP_ADC_init(TSB_AD_TypeDef* const ADx, AD_InitTypeDef* const _initdata)
```

Parameter:

ADx: Select an ADC Address

_initdata: ADC Initial Setup Data Structure

For details, refer to 14.4.2.1 AD_InitTypeDef.

Function:

Initial setup of ADC

Supplement:

Call up during ADC suspension with prohibited interruption.

Returned Value:

No

14.4.2 Data Structure

14.4.2.1 AD_InitTypeDef

Data Fields:

uint8_t shunt: Shunt Type

1: 1-shunt

3: 3-shunt

uint8_t iuch: Phase-U Current Input AD Channel No.(3-shunt)

uint8_t ivch: Phase-V Current Input AD Channel No.(3-shunt)

uint8_t iwch: Phase-W Current Input AD Channel No.(3-shunt)

uint8_t idcch: DC Current Input AD Channel No.(1-shunt)

uint8_t vdcch: Motor Power Supply Voltage Vdc Input AD Channel No.

uint8_t pmd_ch: Select a PMD Channel

cPMD0: PMD Channel 0

uint8_t pints: Select Interruption for PM Trigger

cPINTS_A: INTADxPDA

cPINTS_B: INTADxPDB

uint32_t** p_adreg0: AD Conversion Result Storage Register Address 0

uint32_t** p_adreg1: AD Conversion Result Storage Register Address 1

uint32_t** p_adreg2: AD Conversion Result Storage Register Address 2

uint32_t** p_adreg3: AD Conversion Result Storage Register Address 3

15. Appendix

15.1 Fixed Decimal Point Processing

The decimal arithmetic is executed with the fixed decimal point in this software. A general explanation is given on the fixed decimal point computation.

15.2 Normalization

The normalization is to deform the data in accordance with the certain rules for ease of utilization.

In this application note, the most significant bit is used as the sign bit (0: positive, 1: negative) and a decimal point is placed between the next bit, and normalized in such a way that the maximum possible value (0x7fff) for the data will be "1" and the minimum value (0x8000) will be "-1."

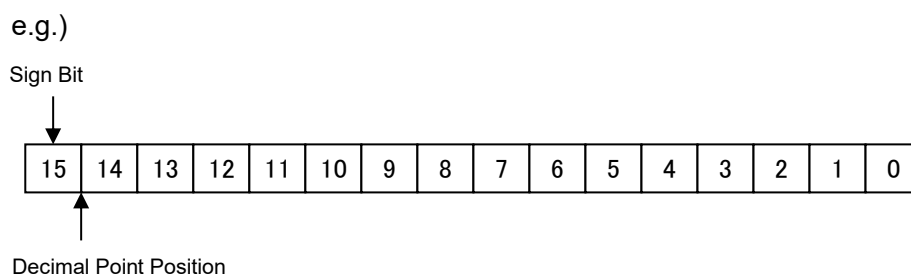


Figure 15.1 Example of 16-Bit Data

In this application note, the maximum value of current data is defined as cA_Max : For example, $A_Max(A)$ when a 16-bit current data is 0x7fff and $-A_Max(A)$ for the case of 0x8000.

15.3 Data Format

The fixed decimal point computation is used in the motor controller of this application. The number of bits in the decimal fraction is expressed in Q format in the fixed decimal point computation. Basically for 16-bit data, computation is performed using Q15 format (15 bits for decimal fraction) and Q31 format for 32-bit data (31 bits for decimal fraction). The value that can be displayed in the decimal format depends on the format.

Table 15.1 Single Precision (16-bit) Decimal Fraction Format

Q Format	Number of Bits for Decimal Fraction	Positive Maximum Value (0x7FFF)	Negative Maximum Value (0x8000)
Q15	15	0.999969482421875	-1
Q14	14	1.999938964843750	-2
Q13	13	3.999877929687500	-4
Q12	12	7.999755859375000	-8
Q11	11	15.999511718750000	-16
Q10	10	31.999023437500000	-32
Q9	9	63.998046875000000	-64
Q8	8	127.996093750000000	-128
Q7	7	255.992187500000000	-256
Q6	6	511.984375000000000	-512
Q5	5	1023.968750000000000	-1024
Q4	4	2047.937500000000000	-2048
Q3	3	4095.875000000000000	-4096
Q2	2	8191.750000000000000	-8192
Q1	1	16383.500000000000000	-16384
Q0	0	32767.000000000000000	-32768

Table 15.2 Double Precision (32-bit) Decimal Fraction Format

Q Format	Number of Bits for Decimal Fraction	Positive Maximum Value (0x7FFFFFFF)	Negative Maximum Value (0x80000000)
Q31	31	0.999999999534338	-1
Q30	30	1.999999999068670	-2
Q29	29	3.999999998137350	-4
Q28	28	7.999999996274700	-8
Q27	27	15.999999992549400	-16
Q26	26	31.999999985098800	-32
Q25	25	63.999999970197600	-64
Q24	24	127.999999940395000	-128
Q23	23	255.999999880790000	-256
Q22	22	511.999999761581000	-512
Q21	21	1023.999999523160000	-1024
Q20	20	2047.999999046320000	-2048
Q19	19	4095.999998092650000	-4096
Q18	18	8191.999996185300000	-8192
Q17	17	16383.999992370600000	-16384
Q16	16	32767.999984741200000	-32768
Q15	15	65535.999969482400000	-65536
Q14	14	131071.999938965000000	-131072
Q13	13	262143.999877930000000	-262144
Q12	12	524287.999755859000000	-524288
Q11	11	1048575.999511720000000	-1048576
Q10	10	2097151.999023440000000	-2097152
Q9	9	4194303.998046870000000	-4194304
Q8	8	8388607.996093750000000	-8388608
Q7	7	16777215.992187500000000	-16777216
Q6	6	33554431.984375000000000	-33554432
Q5	5	67108863.968750000000000	-67108864
Q4	4	134217727.937500000000000	-134217728
Q3	3	268435455.875000000000000	-268435456
Q2	2	536870911.750000000000000	-536870912
Q1	1	1073741823.500000000000000	-1073741824
Q0	0	2147483647.000000000000000	-2147483648

15.4 Computation with Fixed Decimal Point

In the four arithmetic operations of fixed decimal point computation, addition and subtraction are performed as if they were integers, but in multiplication and division, the decimal point position of the result of computation will be shifted; accordingly, it is necessary to set the correct decimal point position.

(1) Multiplication

In the case of multiplication between decimal fraction formats, for example, when multiplying Q15 format data, the result will be in the double precision Q30 format. When the Q31 format data is required, a double precision Q31 format is acquired by the left shifting of computation result by 1 bit.

$$Q15 * Q15 = 2^{-15} * 2^{-15} = 2^{(-15 + -15)} = 2^{-30} = Q30$$

(2) Division

In the case of division between decimal fraction formats, for example, when the Q31 format is divided by the Q15 format, the result will be in the Q16 format. When the Q15 format data is required, the Q15 format data is acquired by right shifting of divisor by 1 bit before computing.

$$Q31 / Q15 = 2^{-31} / 2^{-15} = 2^{(-31 - (-15))} = 2^{-16} = Q16$$

15.5 Assert Function

To report the name of the source file and source line number where the `assert_param` error has occurred, "DEBUG" must be defined.

And detailed definition of `assert_failed()` is needed to be implemented, which can be done, for example, in the `main.c` file.

(example)

```
#ifdef DEBUG
/*
 * @brief Deal with the error parameter
 * @param file: Pointer to the file where the error parameter locates
 * @param line: Number of the line in which the error parameter locates
 * @retval None
 */
void assert_failed(char *file, int32_t line)
{

}

#endif
```

16. Revision History

Date	Rev.	Description
2025-05-29	1.0	First release

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