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Design of Pmsm Based On Dtc Method with Mras

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ABSTRACT :

Permanent magnet synchronous motors (PMSM) are appropriate for applications with load-independent speeds or synchronous operation with high accuracy under defined speed. In this paper analysis the structure and equations of the PMSM, direct torque control (DTC) and voltage space vector process then study model reference adaptive system (MRAS) estimators. The PI controller uses from estimate speed feedback and do the speed sensor less control of PMSM based on DTC method with MRAS. The simulation results show that the speed of rotor estimates with high precision and torque response is considerably fast.

Keywords - permanent magnet synchronous motor; speed control; direct torque control; model reference adaptive system**.**

I. INTRODUCTION

In the last years permanent magnet synchronous motor, because of properties such as high efficiency, high torque, high power, small volume and accurate speed control have become more attention and uses in chemical industry, texturing plants, glass industry, transport systems, electrical household appliances, ship engines, robotic automation, and escalators. The control methods used for the permanent magnet synchronous motors are: V/f control, field oriented control and direct torque control [1].

The basic principle of DTC is to directly select stator voltage vectors according to the differences between the reference and actual torque and stator flux linkage. The DTC possesses advantages such as lesser parameter dependence and fast torque response when compared with the torque control via PWM current control [2].

Position sensor with higher quality is a necessary component part of the drive system employed in So that it is highly desired to develop the position sensor less technology of PMSM. For the mechanical position sensor could be bulky and easy to failure in harsh environments, sensor less technology can increase the reliability of the drive system. Research on sensor less technology has increased in academic and industrial communities over.

During recent years, sensor less drives of PMSM has attracted much attention. Many techniques have been proposed in order to estimate the rotor speed and position, such as open-loop estimators using stator voltages and currents, back EMF-based position estimators, MRAS estimators, observe-based position speed and position estimators, high-frequency signal injection and artificial intelligence.

This paper adopts the MRAS scheme which uses the PMSM itself as the reference model to estimate the speed of the motor [3].

II. PERMANENT MAGNET SYNCHRONOUS MOTOR TECHNOLOGY

Permanent magnet synchronous motors can be designed in different structures according to their application. In this motor permanent magnet can replacing the DC induction coils of the rotor, that is supplied the magnetic flux on the rotor. Stator coils placed on the stator are three phase and the amount of current drawn from the supply is minimal that leads to low losses of the rotor and excitation, increase of efficiency comparable with other motors and savings on energy costs. The magnets on the rotor have two following structure:

A. *Placing the magnets on the rotor surface*

Magnets are installed on the rotor in forms of strips or arcs. These motors have large air gap and faint armature reaction and are utilized in low-speed applications because the low endurance of the magnets to the centrifugal forces. These motors are usually known as surface permanent magnet motors (SPMSM). This motor is shown in Fig. 1.

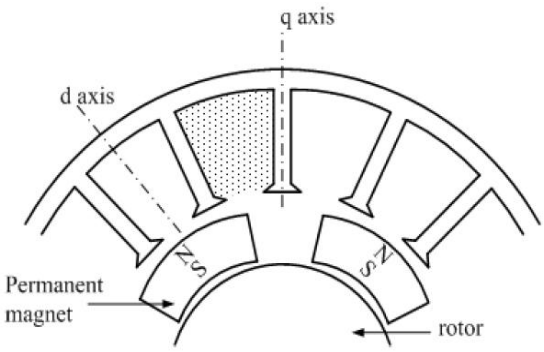


Figure1. Magnets on the rotor surface

The differences between Radially and Circular structure are shown in table 1 [4].

TABLE I. DIFFERENCES RADIALLY AND CIRCULARSTRUCTURE

	Radially structure	Circular structure
Place of magnets	around the rotor axis	pointing the main axis
Air gap	low	high
Resistance to the centrifugal forces	high	high

II. DIRECT TORQUE CONTROL

DTC is a sensor less technique which operates the motor without requiring a shaft mounted mechanical sensor. It is suitable for control of the torque and flux without changing the motor parameters and load. In this method torque and stator flux are directly controlled by two hysteresis controllers [5-7]. The block diagram of direct torque control for permanent magnet synchronous motor is shown in Fig.

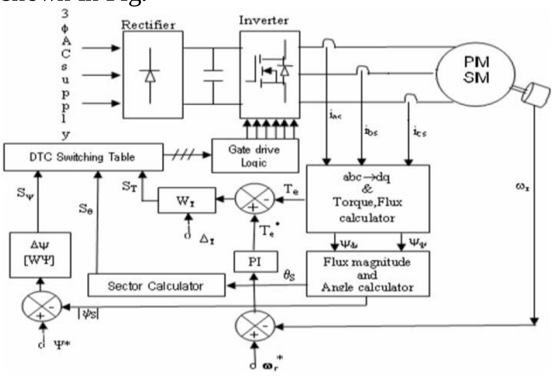


Figure4. Block diagram of DTC for PMSM

A. Permanent magnet synchronous motor Equations

Stator current vector on rotor flux (dq) reference system as id,iq and the electromagnetic torque is related with these vectors. Equations (1-3) and equation (4) are electrical and mechanical model equations respectively[8].

$$\dot{i}_d = \frac{1}{L_d}u_d - \frac{R_s}{L_d}i_d + \frac{L_q}{L_d}\omega_r i_q \quad (1)$$

$$\dot{i}_q = \frac{1}{L_q}u_q - \frac{R_s}{L_q}i_q + \frac{L_d}{L_q}\omega_r i_d - \frac{\psi_f\omega_r}{L_q} \quad (2)$$

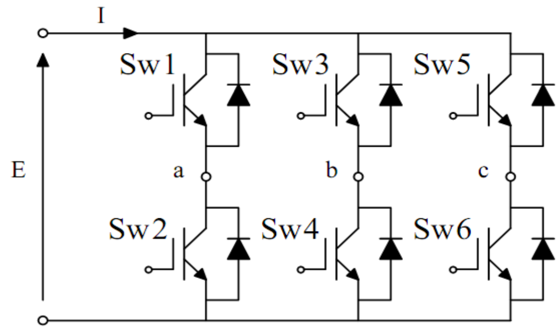
$$T_e = 1.5P[\psi_f i_q - (L_q - L_d)i_d i_q] \quad (3)$$

$$\dot{\omega}_m = \frac{1}{J}(T_e - B\omega_m - T_L) \quad (4)$$

$$\omega_r = p\omega \quad (5)$$

Where
Ψ_f = rotor magnetic flux,
Ld = d - axis ststor inductance,
Lq = q - axis ststor inductance,
Rs = stator resistance,
Te = electromagnetic torque,
T_L = load torque,
ω_m = mechanical speed,
ω_r = angular speed,
J = moment of inertia,
β = friction coefficient,
P = nuber of pole couples.

Structure of voltage source inverter(VSI) is shown in fig. 5 at the same time only one switch on the each column can can be on [5].



By the different selects of the six switches, there are eight vectors that are six non-zero voltage vectors (V_1, V_2, V_3, V_4, V_5, V6) and two zero voltage vectors (V_7, V_8) [2]. Lines to line voltages are:

$$v_{ab} = E.(S_a - S_b) \quad (6)$$

$$v_{bc} = E.(S_b - S_c) \quad (7)$$

$$v_{ca} = E.(S_c - S_a) \quad (8)$$

Line-to-neutral voltages are:

$$v_a = \frac{2v_{ab} + v_{bc}}{3} \quad (9)$$

$$v_b = \frac{v_{bc} - v_{ab}}{3} \quad (10)$$

$$v_c = \frac{-v_{ab} - 2v_{bc}}{3} \quad (11)$$

The ststor voltages-vectors(V1-V8) can be expressed in terms of the dc-link voltages (E) which obtained from transformation motor terminal voltage to stator D and Q axes. These voltages are show in table 2 [5].

TABLE II. VOLTAGES V_D , V_Q

	v_d	v_q
V_1	E	0
V_2	0.5E	0.866E
V_3	-0.5E	0.866E
V_4	-E	0
V_5	-0.5E	-0.866E
V_6	0.5E	-0.866E
V_7	0	0
V_0	0	0

Stator magnetic flux can be calculated with following equation:

$$\Psi_s = \int (u_s - R_s i_s)dt \qquad (12)$$

Value of R is low, equation (12) implies that the flux vector equal voltages integrate and the stator flux vector will move in the same direction voltage vector as shown in Fig. 6.

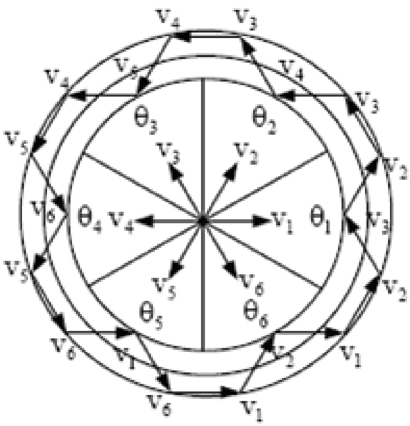


Figure 6. voltage space vectors

Voltage vectors controlling the amplitude of the stator flux, so the voltage vector plane is divided into six regions as shown in Fig. 6. In each region, there are two adjacent voltage vectors that increase or decrease the amplitude of Ψ_s . For example, when Ψ_s in region 1, vectors of V_1, V_2, V_6 and V_3, V_4, V_5 are increase and increse and decrease the amplitude of Ψ_s respectively. In this way Ψ_s can be controlled at the required value by selecting the proper voltage vectors [9-12].

Switching table, for controlling both the flux and torque are indicated in table 3. If Ψ= 1, Ψ=0 then the actual flux is smaller and bigger than the refernce value, respectively. The same is true for the torque.

TABLE III. SWITCHINHG TABLE OF PMSM

		θ					
ψ	T	θ_1	θ_2	θ_3	θ_4	θ_5	θ_6
ψ = 1	T=1	V_2	V_3	V_4	V_5	V_6	V_1
	T=0	V_6	V_1	V_2	V_3	V_4	V_5
ψ = 0	T=1	V_3	V_4	V_5	V_6	V_1	V_2
	T=0	V_5	V_6	V_1	V_2	V_3	V_4

III. MODEL REFERENCE ADAPTIVE SYSTEM

When the motor is running, its parameter will change and its performance will become bad. Adaptive control can remove this problem. The model reference adaptive system (MRAS) is an important adaptive controller [13]. The rotor speed is included in the (1) and (2) equations that present current model are relevant to rotor speed. So the stator current model is chosen as the state variable:

$$\frac{d}{dt}\begin{bmatrix} i_d \\ i_q \end{bmatrix} = \begin{bmatrix} -\frac{R_s}{L_d} & \omega_e \frac{L_q}{L_d} \\ -\omega_e \frac{L_d}{L_q} & -\frac{R_s}{L_q} \end{bmatrix} \begin{bmatrix} i_d \\ i_q \end{bmatrix} + \begin{bmatrix} \frac{u_d}{L_d} \\ \frac{u_q}{L_q} - \omega_e \frac{\psi_f}{L_q} \end{bmatrix} \qquad (13)$$

Define $i_d^*, i_q^*, u_d^*, u_q^*$ as follow:

$$i_d^* = i_d + \frac{\psi_f}{L_d}, \; i_q^* = i_q \qquad (14)$$

$$u_d^* = u_d + \frac{R_s}{L_d}\psi_f, \; u_q^* = u_q \qquad (15)$$

So equation (14) can be converted to the equation State of the adjustable model of PMSM with speed angle as the adjustable parameter as follow:

$$\frac{d}{dt}\begin{bmatrix} \hat{i}_d^* \\ \hat{i}_q^* \end{bmatrix} = \begin{bmatrix} -\frac{R_s}{L_d} & \hat{\omega} \frac{L_q}{L_d} \\ -\hat{\omega} \frac{L_d}{L_q} & -\frac{R_s}{L_q} \end{bmatrix} \begin{bmatrix} \hat{i}_d^* \\ \hat{i}_q^* \end{bmatrix} + \begin{bmatrix} \frac{1}{L_d} u_d^* \\ \frac{1}{L_q} u_q^* \end{bmatrix} \qquad (16)$$

where:

$$\hat{i}_d^* = \hat{i}_d + \frac{\psi_f}{L_q}, \; \hat{i}_q^* = \hat{i}_q \qquad (17)$$

Presume the adaptive mechanism as follow:

$$\hat{\omega} = \int_0^t F_1(v, t, \tau)\,d\tau + F_2(v, t) + \hat{\omega}(0) \qquad (18)$$

F_1 and F_2 are show as follow:

$$\begin{cases} F_1(v,t) = k_1 e^T J \hat{i}^* \\ F_2(v,t) = k_2 e^T J \hat{i}^* \end{cases} \quad (19)$$

where:

$$J = \begin{bmatrix} 0 & \frac{L_q}{L_d} \\ -\frac{L_d}{L_q} & 0 \end{bmatrix} \quad (20)$$

$$e = \begin{bmatrix} i_d^* - \hat{i}_d^* \\ i_q^* - \hat{i}_q^* \end{bmatrix} \quad (21)$$

$$\hat{i}^* = \begin{bmatrix} \hat{i}_d^* \\ \hat{i}_q^* \end{bmatrix} \quad (22)$$

So with replace equation (17) into equation (16), the speed adaptive mechanism finally appears [14]:

$$\hat{\omega} = (K_p + \frac{K_i}{p})\left[\frac{L_q}{L_d} i_d \hat{i}_q - \frac{L_d}{L_q} i_q \hat{i}_d - \frac{\psi_f}{L_q}(i_q - \hat{i}_q) + \hat{i}_d \hat{i}_q (\frac{L_d}{L_q} - \frac{L_q}{L_d}) \right] + \hat{\omega}(0) \quad (23)$$

But the above equation for SPMSM can be simplified as follow (because Ld = Lq = Ls):

$$\hat{\omega} = (K_p + \frac{K_i}{p})\left[i_d \hat{i}_q - i_q \hat{i}_d - \frac{\psi_f}{L_s}(i_q - \hat{i}_q) \right] + \hat{\omega}(0) \quad (24)$$

By these equations, block diagram control of the PMSM based on MRAS can be gotten, and it is shown as Fig. 7.

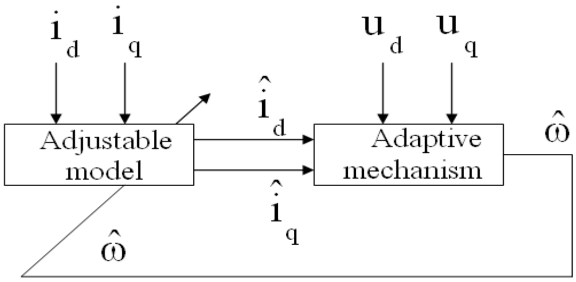


Figure7. The block diagram control of based on MRAS

IV. SIMULATION PMSM BASED ON DTC METHOD WITH MRAS ADAPTIVE SYSTEM

With combine Fig. 4 and Fig. 7, can be estimated the rotor speed and simulate with MATLAB software Fig. 8 shows the block diagram of speed sensor less control of PMSM based on DTC method with MRAS. In Fig. 8, the estimate output speed of MRAS compare with the reference speed of input and uses from this speed as real speed of machine.

Reference speed is 25 rad/s at 0s and then leaps to 10 rad/s at 1s. in the Fig. 9 speed of the motor is 25 rad/s at 0.8s and 10 rad/s at 1.6s Fig. 10 sows the torque of the motor. Load torqueis 10N.m as shown in fig. 10, torque response is fast. Fig. 11 and fig. 12 sow flux of alfa axis and beta axis.

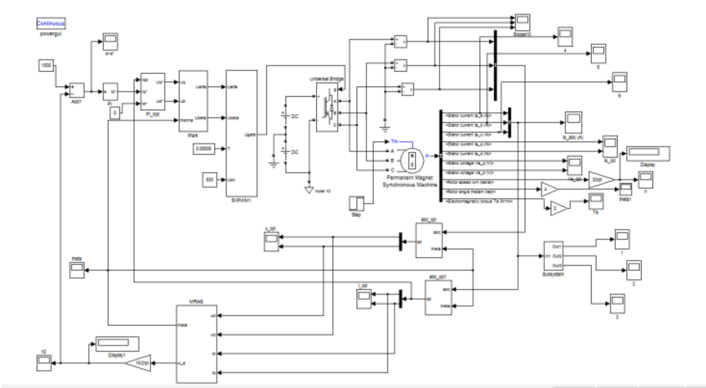


Figure8. Simulation model of DTC method with MRAS

OBSERVED WAVEFORMS:

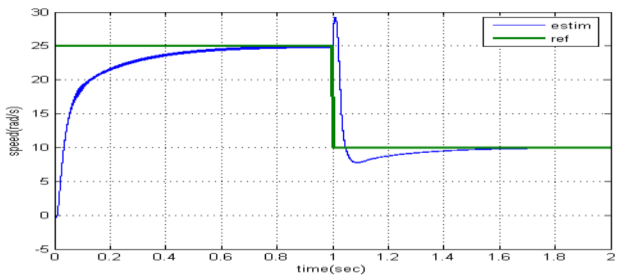


Figure9. Real speed and Estimated speed of PMSM

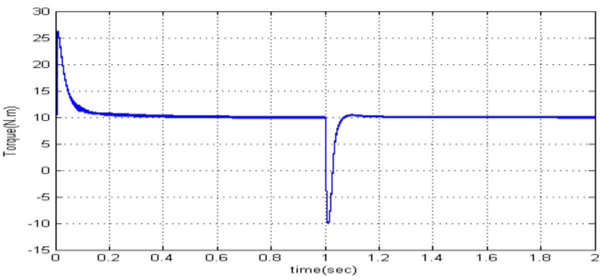


Figure10. Torque of PMSM

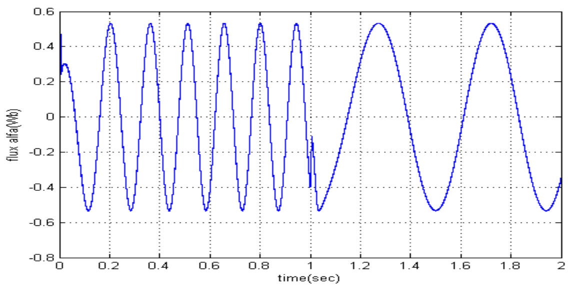


Figure11. Flux of alfa axis

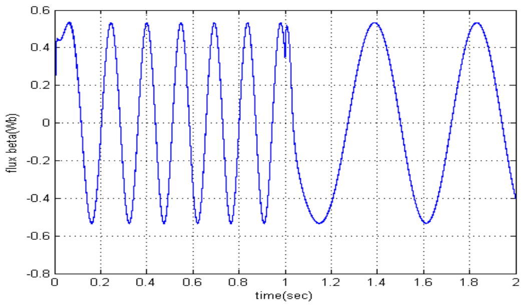


Figure12. Flux of beta axis

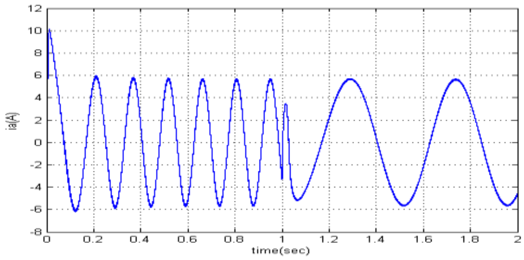


Figure13. The current of phase a (ia)

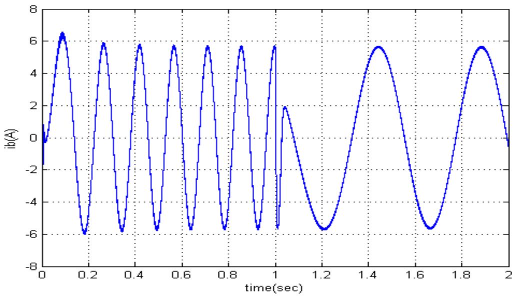


Figure14. The current of phase b (ib)

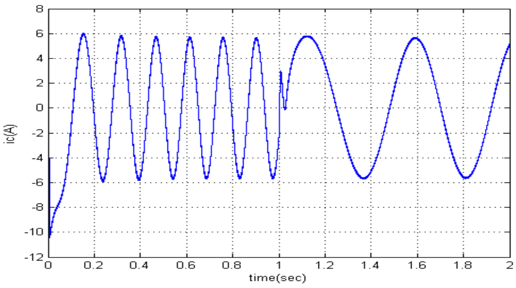


Figure15. The current of phase c (ic)

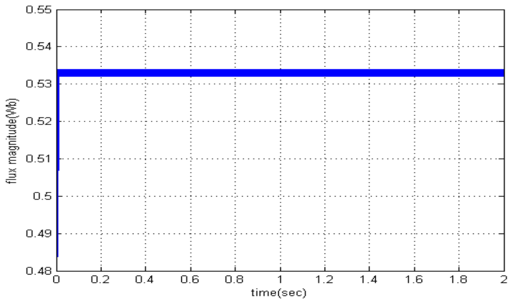


Figure16. Magnitude of stator flux

In Fig. 16 flux is constant and about 0.532 wb. Table 4 shows the parameters of the PMSM used to simulate.

TABLE IV. PARAMETERS OF PMSM

Parameter	Value
Ψ_M	0.533 wb
R_s	5.8 Ω
L_d	44.8 mH
L_q	102.7 mH
J	0.0329 kgm^2
V_d	165 V
B_m	0.0003882
P	2

V. CONCLUSION

In this paper analysis DTC method and a control system of MRAS is introduced. DTC method is designed for an efficient control of torque and flux without changing the motor parameters and load, which in this method the flux and torque can be directly controlled with the inverter voltage vectors. The DTC is use in a wide range.

MRAS method using adjustable model and the reference model so that estimates the position and speed of the rotor, which in this method use the motor itself as the reference model. The simulation results with MATLAB software indicate that speed sensor less control of PMSM based on DTC method with MRAS has preferable good dynamic performance, speed estimation precise and fast torque response.

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