

# Contents

|                                                                          |             |
|--------------------------------------------------------------------------|-------------|
| <b>List of Figures</b>                                                   | <b>xvii</b> |
| <b>1 Introduction</b>                                                    | <b>1</b>    |
| 1.1 Outline . . . . .                                                    | 2           |
| 1.2 Main contributions of this thesis . . . . .                          | 3           |
| <b>2 System model</b>                                                    | <b>7</b>    |
| 2.1 Basic concepts and notation . . . . .                                | 7           |
| 2.1.1 Space vector representation and transformations . . . . .          | 9           |
| 2.2 Machine modeling . . . . .                                           | 11          |
| 2.2.1 Different rotor designs for synchronous machines . . . . .         | 13          |
| 2.3 Inverter modeling . . . . .                                          | 14          |
| 2.3.1 Inverter nonlinearities . . . . .                                  | 15          |
| 2.4 Experimental determination of the system's characteristics . . . . . | 18          |
| 2.4.1 Compensation of inverter nonlinearities . . . . .                  | 18          |
| 2.4.2 Machine flux linkage characterization . . . . .                    | 22          |
| <b>3 State of the art</b>                                                | <b>25</b>   |
| 3.1 Energy efficient control of PMSM . . . . .                           | 25          |
| 3.1.1 Look-up Table based approaches . . . . .                           | 25          |
| 3.1.2 Analytical approaches . . . . .                                    | 26          |
| 3.1.3 Numerical approaches . . . . .                                     | 27          |
| 3.1.4 Signal Injection based algorithms . . . . .                        | 28          |
| 3.2 Saliency-based sensorless control . . . . .                          | 29          |
| 3.2.1 Rotating injection . . . . .                                       | 29          |
| 3.2.2 Alternating injection . . . . .                                    | 30          |
| 3.2.3 Arbitrary injection . . . . .                                      | 32          |
| 3.3 Fundamental model based sensorless control . . . . .                 | 32          |
| 3.3.1 Machine models for observer design . . . . .                       | 32          |
| 3.3.1.1 Machine model in rotor coordinates . . . . .                     | 32          |
| 3.3.1.2 Machine model in stator coordinates . . . . .                    | 33          |
| 3.3.1.3 Extended EMF concept . . . . .                                   | 33          |

|          |                                                                                       |           |
|----------|---------------------------------------------------------------------------------------|-----------|
| 3.3.1.4  | Active Flux concept . . . . .                                                         | 33        |
| 3.3.2    | Observer structures for sensorless control . . . . .                                  | 34        |
| 3.4      | Parameter identification for PMSM . . . . .                                           | 36        |
| 3.4.1    | Observer-based online parameter identification . . . . .                              | 36        |
| 3.4.2    | Signal injection based parameter identification . . . . .                             | 37        |
| 3.4.3    | Parameter identification under sensorless operation . . . . .                         | 38        |
| <b>4</b> | <b>Optimal reference current generation for synchronous machines</b>                  | <b>39</b> |
| 4.1      | Mathematical formulation for energy optimization . . . . .                            | 39        |
| 4.2      | Optimal reference current generation at low speeds . . . . .                          | 40        |
| 4.2.1    | Solving the MTPC condition through binary search . . . . .                            | 42        |
| 4.2.1.1  | Convergence analysis . . . . .                                                        | 44        |
| 4.2.2    | Solving the MTPC condition through Newton Method . . . . .                            | 45        |
| 4.2.2.1  | Convergence analysis . . . . .                                                        | 45        |
| 4.2.3    | Experimental results . . . . .                                                        | 47        |
| 4.3      | Extension to deep field weakening operation . . . . .                                 | 47        |
| 4.3.1    | Solving the MTPF condition . . . . .                                                  | 50        |
| 4.4      | Consideration of flux limitation . . . . .                                            | 51        |
| 4.4.1    | Numerical approximation of the flux limit . . . . .                                   | 52        |
| 4.5      | Algorithm for Reference Current Generation . . . . .                                  | 53        |
| 4.6      | Influence of saturation and cross-coupling on the energy optimization . . . . .       | 57        |
| 4.6.1    | Low speed operation . . . . .                                                         | 58        |
| 4.6.1.1  | Convergence analysis . . . . .                                                        | 59        |
| 4.6.1.2  | Implicit equation for the MTPC considering saturation<br>and cross-coupling . . . . . | 60        |
| 4.6.1.3  | Simulation and experimental results . . . . .                                         | 60        |
| 4.6.2    | Deep-field weakening operation (MTPF) . . . . .                                       | 65        |
| 4.6.2.1  | Convergence analysis . . . . .                                                        | 66        |
| 4.6.2.2  | Implicit equation for MTPF considering saturation . . . . .                           | 67        |
| 4.6.2.3  | Simulation results . . . . .                                                          | 67        |
| 4.6.3    | Field weakening operation . . . . .                                                   | 69        |
| <b>5</b> | <b>Sensorless control for medium and high speeds</b>                                  | <b>73</b> |
| 5.1      | Introduction to the sensitivity calculation . . . . .                                 | 73        |
| 5.2      | Active Flux Observer with direct current model compensation . . . . .                 | 75        |
| 5.2.1    | Sensitivity regarding the stator resistance . . . . .                                 | 76        |
| 5.2.2    | Sensitivity regarding the the d-axis inductance . . . . .                             | 80        |
| 5.2.3    | Sensitivity regarding the q-axis inductance . . . . .                                 | 82        |
| 5.2.4    | Sensitivity regarding the PM-flux . . . . .                                           | 83        |
| 5.2.5    | Sensitivity regarding voltage errors . . . . .                                        | 86        |
| 5.2.5.1  | Voltage magnitude . . . . .                                                           | 86        |
| 5.2.5.2  | Voltage angle . . . . .                                                               | 87        |

|          |                                                                         |            |
|----------|-------------------------------------------------------------------------|------------|
| 5.2.6    | Sensitivity regarding current measurement errors . . . . .              | 91         |
| 5.2.6.1  | Current magnitude . . . . .                                             | 91         |
| 5.2.6.2  | Current angle . . . . .                                                 | 91         |
| 5.3      | Comparison among different machine types . . . . .                      | 92         |
| <b>6</b> | <b>Sensorless control for low-speed operation</b>                       | <b>101</b> |
| 6.1      | Principle of the alternating signal injection . . . . .                 | 101        |
| 6.2      | Why high-low frequency signal injection? . . . . .                      | 103        |
| 6.2.1    | Challenges on reducing the injection frequency . . . . .                | 104        |
| 6.3      | An observer-based subtractive filtering strategy . . . . .              | 104        |
| 6.3.1    | Kalman-filter for current reconstruction . . . . .                      | 105        |
| 6.3.2    | Demodulation of the HF current signal . . . . .                         | 109        |
| 6.4      | Integration of the position estimate into the voltage model . . . . .   | 111        |
| 6.4.1    | The influence of inverter nonlinearities and their compensation . . .   | 113        |
| 6.5      | Hybrid sensorless control implementation . . . . .                      | 116        |
| <b>7</b> | <b>Online parameter identification</b>                                  | <b>121</b> |
| 7.1      | Rank-deficiency problem of the IPMSM . . . . .                          | 121        |
| 7.2      | Full-parameter estimation using HF-voltage injection . . . . .          | 122        |
| 7.2.1    | Observability conditions . . . . .                                      | 125        |
| 7.2.2    | Experimental Results . . . . .                                          | 127        |
| 7.3      | The influence of inverter nonlinearities and its compensation . . . . . | 129        |
| 7.4      | Analysis of the numerical conditioning . . . . .                        | 130        |
| 7.5      | Full-parameter identification under sensorless operation . . . . .      | 137        |
| <b>8</b> | <b>Conclusions</b>                                                      | <b>141</b> |
| 8.1      | Outlook . . . . .                                                       | 143        |
|          | <b>Bibliography</b>                                                     | <b>145</b> |
| <b>A</b> | <b>List of publications</b>                                             | <b>159</b> |
| <b>B</b> | <b>Test-bench data</b>                                                  | <b>161</b> |
| B.1      | Electrical machines . . . . .                                           | 161        |
| B.2      | Test-benches . . . . .                                                  | 161        |
| <b>C</b> | <b>Abbreviations</b>                                                    | <b>165</b> |