

UG10259

MCUXpresso SDK Field-Oriented Control of 3-Phase PMSM and BLDC Motors (MIMXRT1180-EVK)

Rev. 1.0 — 3 July 2025

User guide

Document information

Information	Content
Keywords	RT1180-EVK , PMSM, FOC, MCAT, MID, Motor control, Sensorless control, Speed control, Servo control, Position control
Abstract	This user guide describes the implementation of the motor-control software for 3-phase Permanent Magnet Synchronous Motors.



1 Introduction

SDK motor control example user guide describes the implementation of the motor-control software for 3-phase Permanent Magnet Synchronous Motors (PMSM) using following NXP platforms:

- i.MX RT1180-EVK ([MIMXRT1180-EVK](#))
- Freedom Development Platform for Low-Voltage, 3-Phase PMSM Motor Control ([FRDM-MC-LVPMSM](#))

The document is divided into several parts. Hardware setup, processor features, and peripheral settings are described at the beginning of the document. The next part contains the PMSM project description and motor control peripheral initialization. The last part describes user interface and additional example features.

Available motor control examples types with supported motors, and possible control methods are listed in [Table 1](#).

Table 1. Available example type, supported motors and control methods

Example type	Supported motor	Possible control methods in SDK example				
		Scalar and Voltage	Current FOC (Torque)	Sensorless Speed FOC	Sensored Speed FOC	Sensored Position FOC
pmsm_enc	Linux 45ZWN24-40	✓	✓	✓	N/A	N/A
	Teknic M-2311P (with ENC)	✓	✓	✓	✓	✓

SDK motor control example description:

- **pmsm_enc** - pmsm example uses float arithmetic, the example contains sensed and also sensorless field oriented vector control (FOC). This example can be used for sensor and sensorless motor control application both. Default motor configuration is tuned for the Teknic M-2311P motor.

The SDK motor control example contains several additional features:

- **FreeMASTER** pmsm_float_enc.pmpx project provides a simple and user-friendly way for algorithm tuning, software control, debugging, and diagnostics.
- **MCAT** - Motor Control Application Tuning page based on the FreeMASTER runtime debugging tool.
- **MID** - Motor parameter identification.

The control software and the PMSM control theory, in general, are described in *Sensorless PMSM Field-Oriented Control (FOC)* (document [DRM148](#)).

2 Hardware setup

The following chapter describes the used hardware and the setup needed for proper example working

2.1 Linix motor

The Linix 45ZWN24-40 motor is a low-voltage 3-phase permanent-magnet motor with hall sensor used in PMSM applications. The motor parameters are listed below.

Table 2. Linix 45ZWN24-40 motor parameters

Characteristic	Symbol	Value	Units
Rated voltage	Vt	24	V
Rated speed	-	4000	RPM
Rated torque	T	0.0924	Nm
Rated power	P	40	W
Continuous current	Ics	2.34	A
Number of pole-pairs	pp	2	-

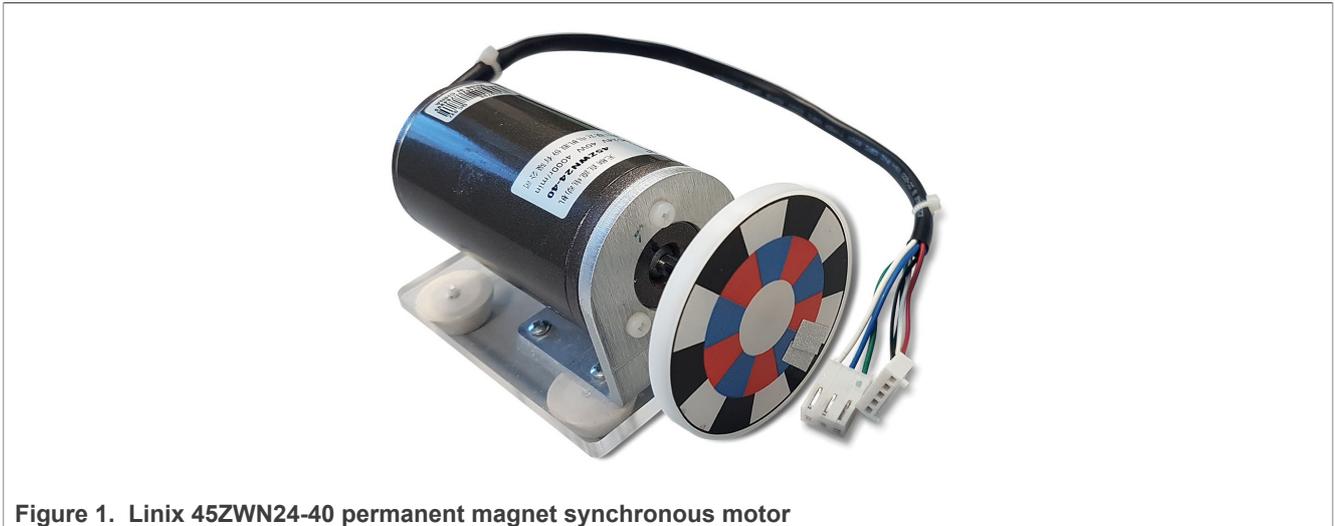


Figure 1. Linix 45ZWN24-40 permanent magnet synchronous motor

The motor has two types of connectors (cables). The first cable has three wires and is designated to power the motor. The second cable has five wires and is designated for the hall sensors' signal sensing. For the PMSM sensorless application, only the power input wires are needed.

2.2 Teknic motor

The Teknic M-2310P-LN-04K and M-2311P-LN-08D are a low-voltage 3-phase permanent-magnet motors used in PMSM applications. The motors have two feedback sensors (hall and encoder). For information on the wiring of feedback sensors, see the data sheet on the manufacturer webpage. The motor parameters are listed below.

Table 3. Teknic M-2310P-LN-04K motor parameters

Characteristic	Symbol	Value	Units
Rated speed	-	6000	RPM
Continuous (RMS) torque	T	0.247	Nm

Table 3. Teknic M-2310P-LN-04K motor parameters...continued

Characteristic	Symbol	Value	Units
Continuous (RMS) power	P	170	W
Continuous (RMS) current	Ics	7.1	A
Number of pole-pairs	pp	4	-
Encoder density	-	4000 (1000)	count/revolution (pulses)

Table 4. Teknic M-2311P-LN-08D motor parameters

Characteristic	Symbol	Value	Units
Rated speed	-	6000	RPM
Continuous (RMS) torque	T	0.4	Nm
Continuous (RMS) power	P	206	W
Continuous (RMS) current	Ics	7.7	A
Number of pole-pairs	pp	4	-
Encoder density	-	8000 (2000)	count/revolution (pulses)



Figure 2. Teknic permanent magnet synchronous motor

For the sensorless control mode, you only need the power input wires. If used with the hall or encoder sensors, connect the sensor wires to the NXP Freedom power stage.

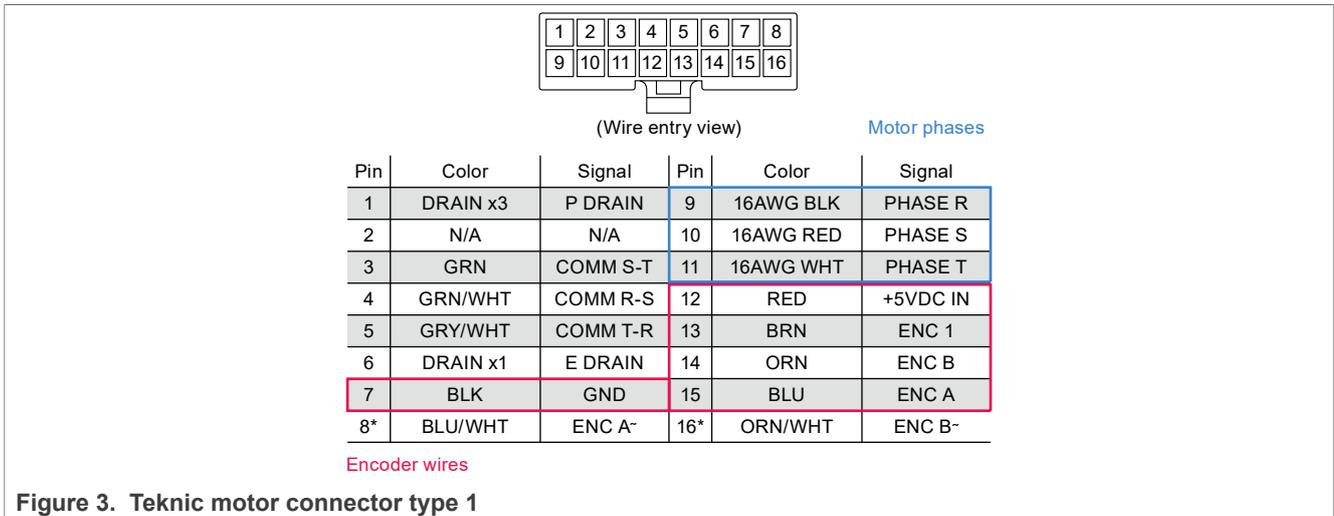


Figure 3. Teknic motor connector type 1

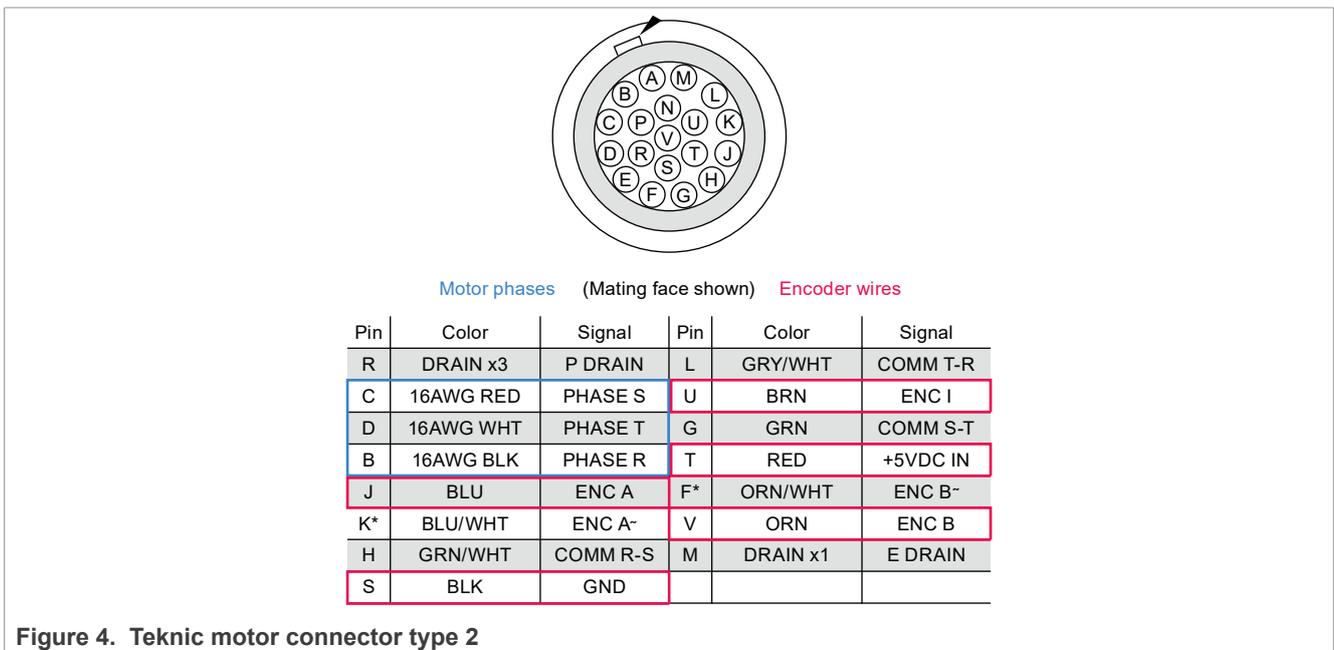


Figure 4. Teknic motor connector type 2

2.3 FRDM-MC-LVPMSM

In a shield form factor, this evaluation board effectively turns an NXP Freedom development board or an evaluation board into a complete motor-control reference design. It is compatible with existing NXP Freedom development boards and evaluation boards. The Freedom motor-control headers are compatible with the Arduino R3 pin layout.

The FRDM-MC-LVPMSM low-voltage, 3-phase Permanent Magnet Synchronous Motor (PMSM) Freedom development platform board has a power supply input voltage of 24 VDC to 48 VDC with reverse polarity protection circuitry. The auxiliary power supply of 5.5 VDC is created to supply the FRDM MCU boards. The output current is up to 5 A RMS. The inverter itself is realized by a 3-phase bridge inverter (six MOSFETs) and a 3-phase MOSFET gate driver. The analog quantities (such as the 3-phase motor currents, DC-bus voltage, and DC-bus current) are sensed on this board. There is also an interface for speed and position sensors (encoder, hall).

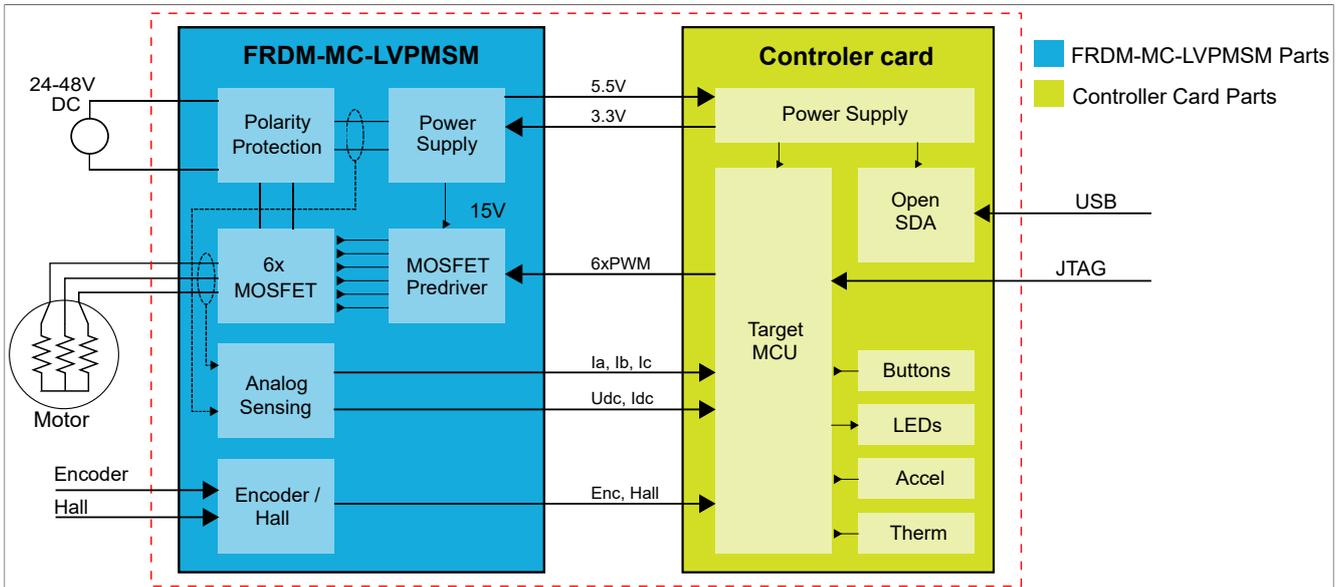


Figure 5. Motor-control development platform block diagram

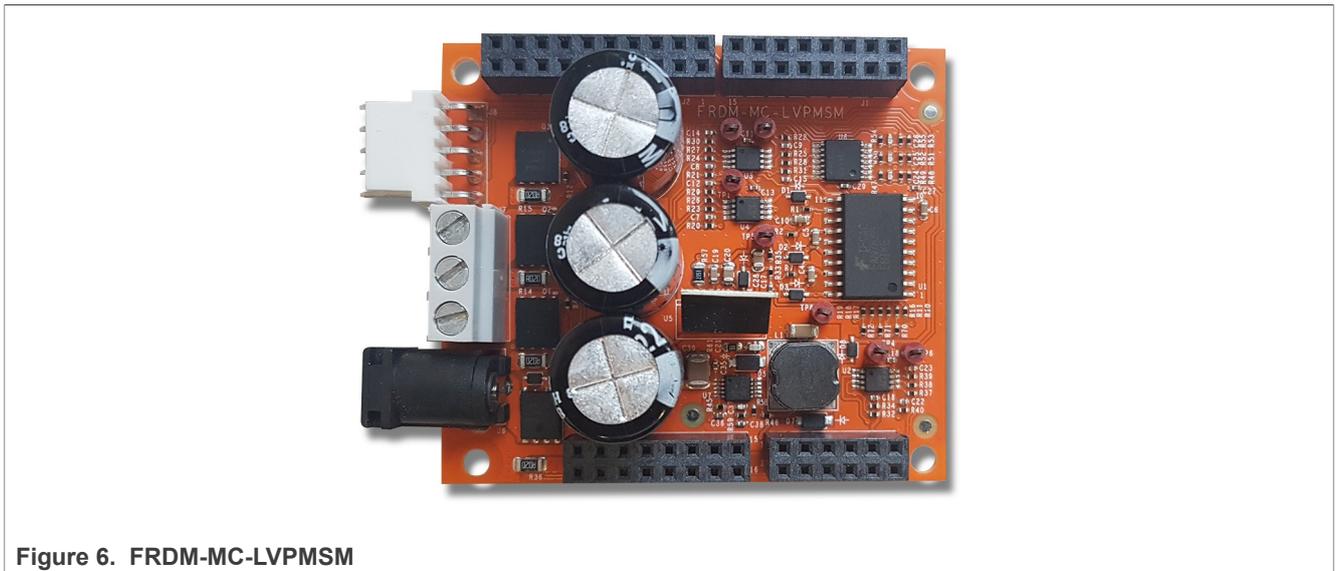


Figure 6. FRDM-MC-LVPMSM

The FRDM-MC-LVPMSM board does not require a complicated setup. For more information about the Freedom development platform, see www.nxp.com.

Note:

There might be a wrong FRDM-MC-LVPMSM series in the market (series VV19520XXX). This series is populated with 10 mOhm shunt resistors and noisy operational amplifiers which affect phase current measurement. The mc_pmsm example is tuned for original FRDM-MC-LVPMSM board with 20 mOhm shunt resistors.

2.4 i.MX RT1180 Evaluation Kit

The MIMXRT1180-EVK are two-layer low-cost through-hole USB-powered PCBs. At its heart lies the i.MX RT11xx crossover MCU. The dual core i.MX RT1180 runs on the Cortex-M7 core at 800 MHz and Arm Cortex-M33 at 240 MHz, while providing best-in-class security.

Table 5. MIMXRT1180-EVK jumper settings

Jumper	Setting	Jumper	Setting	Jumper	Setting
JP1	7-8	J57	2-3	J78	1-2
JP3	1-2	J58	2-3	J79	1-2
J4	1-2	J59	2-3	J90	1-2
J6	1-2	J63	1-2	J91	1-2
JP6	1-2	J65	1-2	J93	1-2
JP7	1-2	J72	1-2	J97	1-2
J9	1-2	J73	1-2	J98	1-2
J11	1-2	J75	2-3	J99	1-2
J12	1-2	J76	1-2	J100	1-2
J14	1-2	J77	1-2	J135	1-2

All others jumpers are open.

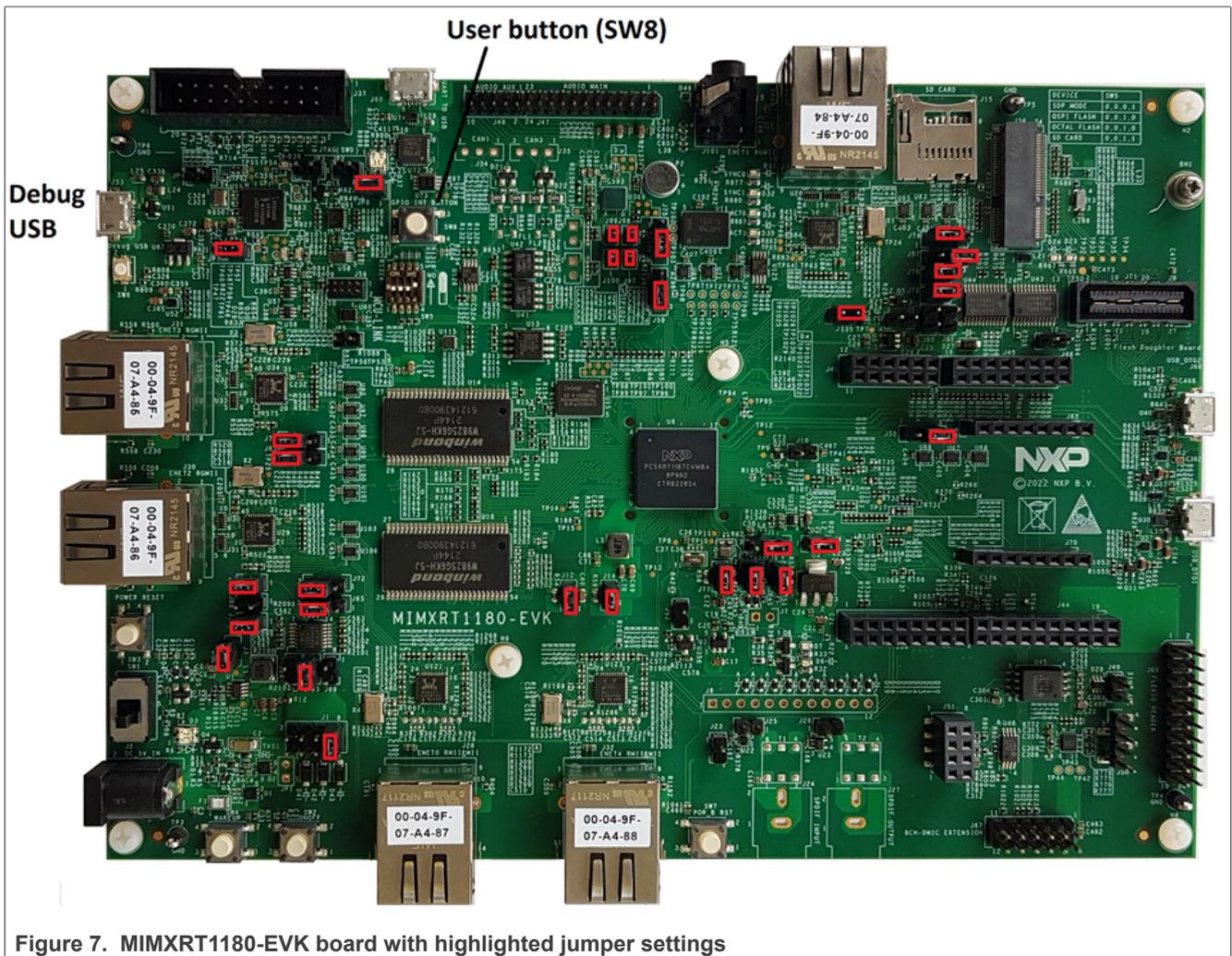


Figure 7. MIMXRT1180-EVK board with highlighted jumper settings

For a correct connection, the motor-control application requires remove and solder some zero resistors. Please, remove and solder zero resistors according table below.

Table 6. Add and remove resistors

Add resistors		Remove resistors	
R747	R764	R104	R146
R749	R767	R105	R148
R760	R1049	R107	R1052
R763	R1051	R126	R1089
		R135	R1090

For locate resistors on the board see layout on [board web page](#). For more information about the MIMXRT1180-EVK hardware (processor, peripherals, etc.), see the [nxp.com](#)

2.4.1 Hardware assembling

1. Connect the FRDM-MC-LVPMSM shield on top of the MIMXRT1180-EVK board (there is only one possible option).
Note: Watch out for unwanted connections between bottom of FRDM-MC-PMSM and jumpers on top of MIMXRT11xx-EVK.
2. Connect the 3-phase motor wires to the screw terminals (J7) on the Freedom PMSM power stage.
3. Plug the USB cable from the USB host to the Debug USB connector J53 on the EVK board.
4. Plug the 24-V DC power supply to the DC power connector on the Freedom PMSM power stage.

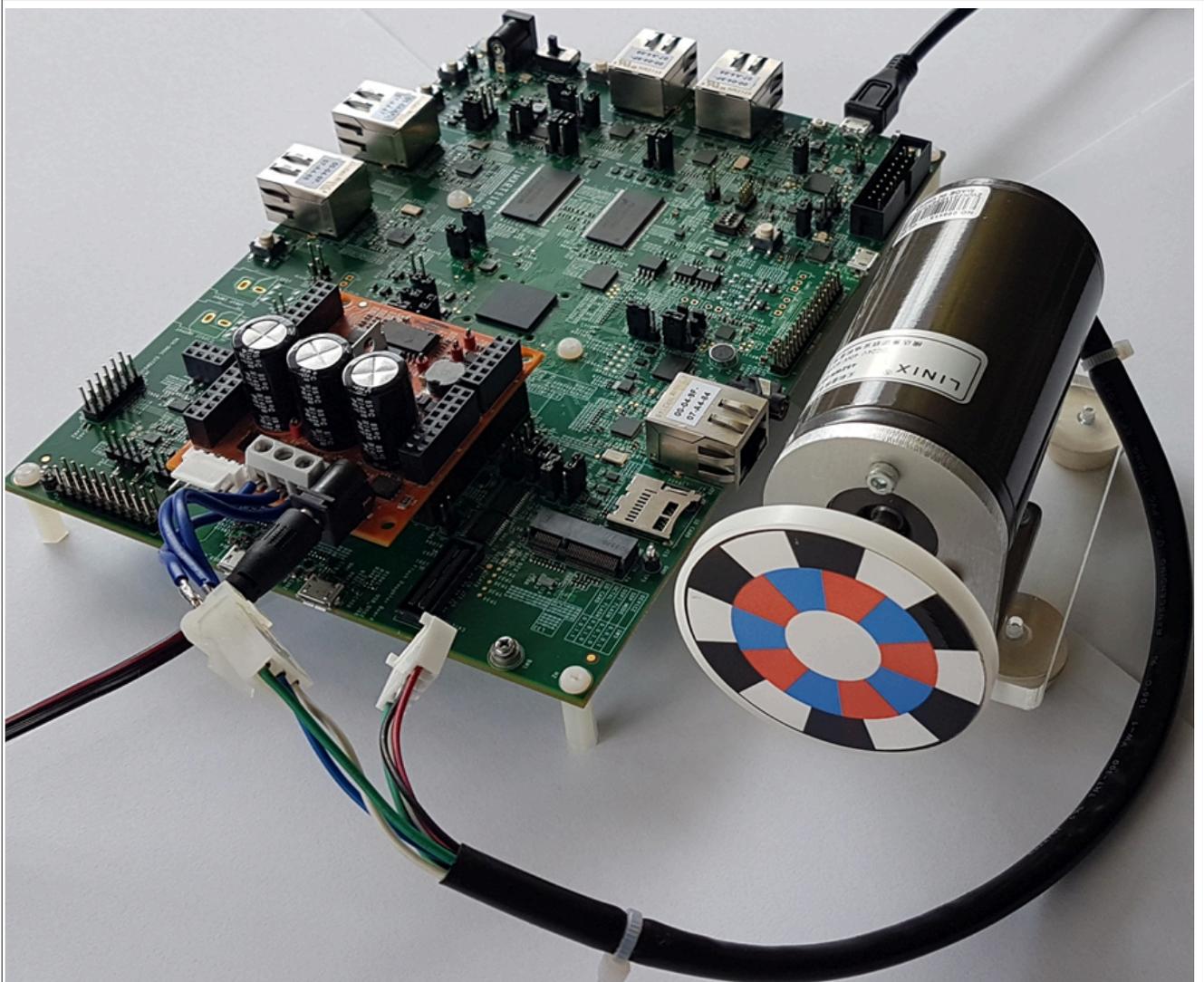


Figure 8. Assembled Freedom system

Note: The example has been tested on the board with schematic number: SCH-50577 REV C2.

3 Processors features and peripheral settings

This chapter describes the peripheral settings and application timing.

3.1 i.MX RT1180

The i.MX RT series of crossover MCUs are part of the EdgeVerse™ [edge computing](#) platform and feature Arm® Cortex®-M cores, high performance real-time functionality and MCU usability at a cost-effective price. The i.MX RT1180 crossover MCU family includes a Gb time sensitive networking (TSN) switch to enable real-time rich networking integration that handles both time-sensitive and industrial real-time communication. The i.MX RT1180 supports multiple protocols, bridging communications between real-time Ethernet and industry 4.0 systems. This family includes a state-of-the-art EdgeLock secure enclave, a dual core architecture with both an 800 MHz Cortex-M7 and a 240 MHz Cortex-M33 for ultimate design flexibility. The i.MX RT1180 is supported by an extensive developer ecosystem, featuring [MCUXpresso software and tools](#), for an optimal microcontroller design experience.

For more information, see [i.MX RT1180 Crossover MCU Family](#) web pages.

3.1.1 RT1180 - Hardware timing and synchronization

Correct and precise timing is crucial for motor-control applications. Therefore, the motor-control-dedicated peripherals take care of the timing and synchronization on the hardware layer. In addition, you can set the PWM frequencies as a multiple of the ADC interrupt (ADC ISR) frequency where the FOC algorithm is calculated. In this case, the PWM frequency is equal to the FOC frequency.

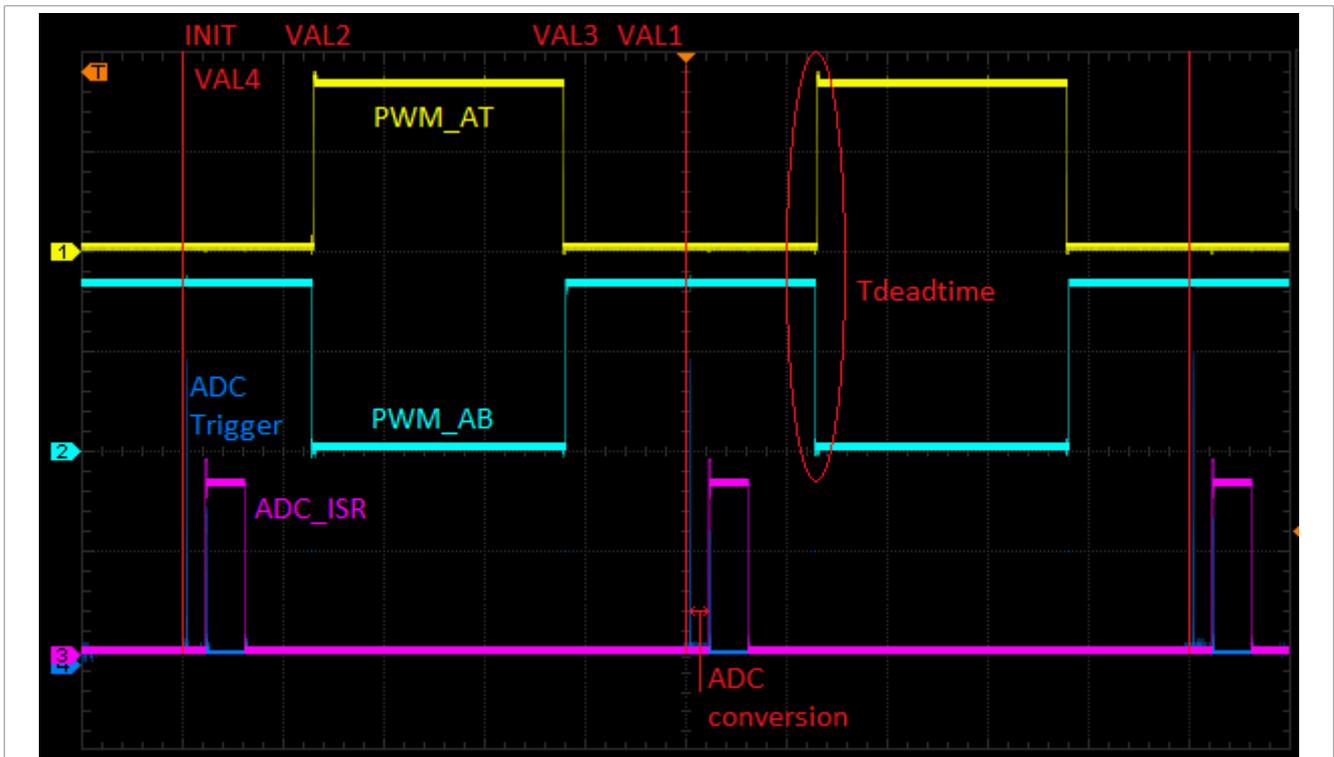


Figure 9. Hardware timing and synchronization on i.MX RT1180

- The top signal shows the PWM_AT (PWM phase A - top) and PWM_AB (PWM phase A - bottom). The dead time is emphasized at the PWM top and PWM bottom signals.

- The eFlexPWM submodule SM0 generates trigger 0 (ADC Trigger) when the counter counts to a value equal to the VAL4 value. ADC Trigger is delayed of approximately $T_{deatime}/2$. This delay ensures correct current sampling at the duty cycles close to 100 %.
- When the ADC conversion is completed, the ADC_ISR (ADC interrupt) is entered. The FOC calculation is done in this interrupt.

3.1.2 RT1180 - Peripheral settings

This section describes the peripherals used for the motor control. On i.MX RT1180, three submodules from the enhanced FlexPWM (eFlexPWM) are used for 6-channel PWM generation and two 12-bit ADCs for the phase currents and DC-bus voltage measurement. The eFlexPWM and ADC are synchronized via submodule 0 from the eFlexPWM. The following settings are located in the `mc_periph_init.c` and `peripherals.c` files and their header files.

3.1.2.1 PWM generation - PWM1

- Six channels from three submodules are used for the 3-phase PWM generation. Submodule 0 generates the master reload at event every n^{th} opportunity, depending on the user-defined macro `M1_FOC_FREQ_VS_PWM_FREQ`.
- Submodules 1 and 2 get their clocks from submodule 0.
- The counters at submodules 1 and 2 are synchronized with the master reload signal from submodule 0.
- Submodule 0 is used for synchronization with ADC. The submodule generates the output trigger after the PWM reload, when the counter counts to VAL4.
- Fault mode is enabled for channels A and B at submodules 0, 1, and 2 with automatic fault clearing.
Note: *The PWM outputs are re-enabled at the first PWM reload after the fault input returns to zero.*
- The PWM period (frequency) is determined by how long the counter takes to count from INIT to VAL1. By default, `INIT = -MODULO/2` and `VAL1 = MODULO/2 - 1` where `MODULO = FastPeripheralClock / M1_PWM_FREQ`.
- Dead time insertion is enabled. Define the dead time length in the `M1_PWM_DEADTIME` macro.

3.1.2.2 Analog sensing - ADC1 and ADC2

ADC1 and ADC2 are used for the MC analog sensing of currents and DC-bus voltage.

- The ADCs operate as 12-bit with the single-ended conversion and hardware trigger selected.
- ADC1 and ADC2 are controlled by the same trigger source. The trigger source is the PWM submodule 0.

3.1.2.3 Quadrature Decoder (eQDC) module

The QD module is used to sense the position and speed from the encoder sensor.

- The direction of counting is set in the `M1_POSPE_ENC_DIRECTION` macro.
- The modulo counting and the modulus counting roll-over/under to increment/decrement revolution counter are enabled.

3.1.2.4 Peripheral interconnection for - XBAR

The crossbar is used to interconnect the trigger from the PWM to the ADC and to connect the encoder (connected to GPIO) to the QD.

- The PWM output trigger (generated by submodule 0) is configured in `pinmux.c`.
- The encoder signal Phase A and Phase B are configured in `pinmux.c`.

3.1.2.5 Slow-loop interrupt generation - TMR1

The QuadTimer module TMR1 is used to generate the slow-loop interrupt.

- The slow loop is usually ten times slower than the fast loop. Therefore, the interrupt is generated after the counter counts from CNTR0 = 0 to COMP1 = FastPeripheralClock / (16U * Speed Loop Freq). The speed loop frequency is set in the M1_SPEED_LOOP_FREQ macro and equals 1000 Hz.
- An interrupt (which serves the slow-loop period) is enabled and generated at the reload event.

3.2 CPU load and memory usage

The following information applies to the application built using one of the following IDE: MCUXpresso IDE, IAR, Keil MDK or CodeWarrior. The memory usage is calculated from the *.map linker file, including FreeMASTER recorder buffer allocated in RAM. In the MCUXpresso IDE, the memory usage can be also seen after project build in the Console window. The table below shows the maximum CPU load of the supported examples. The CPU load is measured using the SYSTICK timer. The CPU load is dependent on the fast-loop (FOC calculation) and slow-loop (speed loop) frequencies. The total CPU load is calculated using the following equations:

$$CPU_{fast} = cycles_{fast} \frac{f_{fast}}{f_{CPU}} 100 \left[\% \right] \tag{1}$$

$$CPU_{slow} = cycles_{slow} \frac{f_{slow}}{f_{CPU}} 100 \left[\% \right] \tag{2}$$

$$CPU_{total} = CPU_{fast} + CPU_{slow} \left[\% \right] \tag{3}$$

Where:

- CPU_{fast} = the CPU load taken by the fast loop
- cycles_{fast} = the number of cycles consumed by the fast loop
- f_{fast} = the frequency of the fast-loop calculation
- f_{CPU} = CPU frequency
- CPU_{slow} = the CPU load taken by the slow loop
- cycles_{slow} = the number of cycles consumed by the slow loop
- f_{slow} = the frequency of the slow-loop calculation
- CPU_{total} = the total CPU load consumed by the motor control

Table 7. Maximum CPU load (fast loop)

Device	Example	Debug configuration	
		Speed Control	Position Control
i.MX RT1180-EVK	pmsm_enc	8.6 %	9.2 %

Table 8. Memory usage

	Debug configuration	Release configuration
Readonly code memory	57 228 B	40 368 B
Readwrite code memory	642 B	642 B
Readonly data memory	18 874 B	14 741 B
Readwrite data memory	9 753 B	9 728 B

CPU load measured without defined `RAM_RELOCATION` macro. Measured CPU load and memory usage applies to the application built using IAR IDE.

Note: *The maximum CPU load is depending on executing functions from RAM or flash memory. Executing functions can be speeding up in `RTCESL_cfg.h` header file by using macro `RAM_RELOCATION`.*

Note: *Memory usage and maximum CPU load can differ depending on the used IDEs and settings.*

4 SDK package project file and IDE workspace structure

All the necessary files are included in one package, which simplifies the distribution and decreases the size of the final package. The directory structure of this package is simple, easy to use, and organized logically. The folder structure used in the IDE differs from the structure of the PMSM package installation, but it uses the same files. The different organization is chosen due to better manipulation of folders and files in workplaces and the possibility of adding or removing files and directories. The `pack_motor_<board_name>` project includes all the available functions and routines. This project serves for development and testing purposes.

4.1 PMSM project structure

The directory tree of the PMSM project is shown in below.



Figure 10. Directory tree

The main project folder `pack_motor_<board_name>\boards\<board_name>\demo_apps\mc_pmsm\pmsm_enc\` contains the following folders and files:

- `iar`: for the IAR Embedded Workbench IDE.
- `armgcc`: for the GNU Arm IDE.
- `mdk`: for the uVision Keil IDE.
- `m1_pmsm_appconfig.h`: contains the definitions of constants for the application control processes, parameters of the motor and regulators, and the constants for other vector-control-related algorithms. When

you tailor the application for a different motor using the Motor Control Application Tuning (MCAT) tool, the tool generates this file at the end of the tuning process.

- `main.c`: contains the basic application initialization (enabling interrupts), subroutines for accessing the MCU peripherals, and interrupt service routines. The FreeMASTER communication is performed in the background infinite loop.
- `board.c`: contains the functions for the UART, GPIO, and SysTick initialization.
- `board.h`: contains the definitions of the board LEDs, buttons, UART instance used for FreeMASTER, and so on.
- `clock_config.c` and `.h`: contains the CPU clock setup functions. These files are going to be generated by the clock tool in the future.
- `mc_periph_init.c`: contains the motor-control driver peripherals initialization functions that are specific for the board and MCU used.
- `mc_periph_init.h`: header file for `mc_periph_init.c`. This file contains the macros for changing the PWM period and the ADC channels assigned to the phase currents and board voltage.
- `freemaster_cfg.h`: the FreeMASTER configuration file containing the FreeMASTER communication and features setup.
- `pin_mux.c` and `.h`: port configuration files. Generate these files in the pin tool.
- `peripherals.c` and `.h`: MCUXpresso Config Tool configuration files.

The main motor-control folder `pack_motor_<board_name>\middleware\motor_control\` contains these subfolders:

- `pmsm`: contains main PMSM motor-control functions.
- `freemaster`: contains the FreeMASTER project file `pmsm_float_enc.pmpx`. Open this file in the FreeMASTER tool and use it to control the application. The folder also contains the auxiliary files for the MCAT tool.

The `pack_motor_<board_name>\middleware\motor_control\pmsm\pmsm_float\` folder contains these subfolders common to the other motor-control projects:

- `mc_algorithms`: contains the main control algorithms used to control the FOC and speed control loop.
- `mc_cfg_template`: contains templates for MCUXpresso Config Tool components.
- `mc_drivers`: contains the source and header files used to initialize and run motor-control applications.
- `mc_identification`: contains the source code for the automated parameter-identification routines of the motor.
- `mc_state_machine`: contains the software routines that are executed when the application is in a particular state or state transition.
- `state_machine`: contains the state machine functions for the FAULT, INITIALIZATION, STOP, and RUN states.

5 Github project structure

More informations for examples released through [NXP MCUXpresso Github](#) are available on link [MCUXpresso SKD Documentation](#).

6 Motor-control peripheral initialization

The motor-control peripherals are initialized by calling the `MCDRV_Init_M1()` function during MCU startup and before the peripherals are used. All initialization functions are in the `mc_periph_init.c` source file and the `mc_periph_init.h` header file. The definitions specified by the user are also in these files. The features provided by the functions are the 3-phase PWM generation and 3-phase current measurement, as well as the DC-bus voltage and auxiliary quantity measurement. The principles of both the 3-phase current measurement and the PWM generation using the Space Vector Modulation (SVM) technique are described in *Sensorless PMSM Field-Oriented Control* (document [DRM148](#)).

The `mc_periph_init.h` header file provides the following macros defined by the user:

- `M1_MCDRV_ADC_PERIPH_INIT`: this macro calls ADC peripheral initialization.
- `M1_MCDRV_PWM_PERIPH_INIT`: this macro calls PWM peripheral initialization.
- `M1_MCDRV_QD_ENC`: this macro calls QD peripheral initialization.
- `M1_PWM_FREQ`: the value of this definition sets the PWM frequency.
- `M1_FOC_FREQ_VS_PWM_FREQ`: enables you to call the fast-loop interrupt at every first, second, third, or n^{th} PWM reload. This is convenient when the PWM frequency must be higher than the maximal fast-loop interrupt.
- `M1_SPEED_LOOP_FREQ`: the value of this definition sets the speed loop frequency (TMR1 interrupt).
- `M1_PWM_DEADTIME`: the value of the PWM dead time in nanoseconds.
- `M1_PWM_PAIR_PH[A..C]`: these macros enable a simple assignment of the physical motor phases to the PWM periphery channels (or submodules). You can change the order of the motor phases this way.
- `M1_ADC[1,2]_PH[A..C]`: these macros assign the ADC channels for the phase current measurement. The general rule is that at least one-phase current must be measurable on both ADC converters, and the two remaining phase currents must be measurable on different ADC converters. The reason for this is that the selection of the phase current pair to measure depends on the current SVM sector. If this rule is broken, a preprocessor error is issued. For more information about the 3-phase current measurement, see *Sensorless PMSM Field-Oriented Control* (document [DRM148](#)).
- `M1_ADC[1,2]_UDCB`: this define is used to select the ADC channel for the measurement of the DC-bus voltage.

In the motor-control software, the following API-serving ADC and PWM peripherals are available:

- The available APIs for the ADC are:
 - `mcdrv_adc_t`: MCDRV ADC structure data type.
 - `void M1_MCDRV_ADC_PERIPH_INIT()`: this function is by default called during the ADC peripheral initialization procedure invoked by the `MCDRV_Init_M1()` function and should not be called again after the peripheral initialization is done.
 - `void M1_MCDRV_CURR_3PH_CHAN_ASSIGN(mcdrv_adc_t*)`: calling this function assigns proper ADC channels for the next 3-phase current measurement based on the SVM sector.
 - `void M1_MCDRV_CURR_3PH_CALIB_INIT(mcdrv_adc_t*)`: this function initializes the phase-current channel-offset measurement.
 - `void M1_MCDRV_CURR_3PH_CALIB(mcdrv_adc_t*)`: this function reads the current information from the unpowered phases of a stand-still motor and filters them using moving average filters. The goal is to obtain the value of the measurement offset. The length of the window for moving the average filters is set to eight samples by default.
 - `void M1_MCDRV_CURR_3PH_CALIB_SET(mcdrv_adc_t*)`: this function asserts the phase-current measurement offset values to the internal registers. Call this function after a sufficient number of `M1_MCDRV_CURR_3PH_CALIB()` calls.

- void M1_MCDRV_CURR_3PH_VOLT_DCB_GET(mcdrv_adc_t*): this function reads and calculates the actual values of the 3-phase currents, DC-bus voltage, and auxiliary quantity.
- The available APIs for the PWM are:
 - mcdrv_pwm3ph_t: MCDRV PWM structure data type.
 - void M1_MCDRV_PWM_PERIPH_INIT: this function is by default called during the PWM peripheral initialization procedure invoked by the MCDRV_Init_M1() function.
 - void M1_MCDRV_PWM3PH_SET(mcdrv_pwm3ph_t*): this function updates the PWM phase duty cycles.
 - void M1_MCDRV_PWM3PH_EN(mcdrv_pwm3ph_t*): this function enables all PWM channels.
 - void M1_MCDRV_PWM3PH_DIS(mcdrv_pwm3ph_t*): this function disables all PWM channels.
 - bool_t M1_MCDRV_PWM3PH_FLT_GET(mcdrv_pwm3ph_t*): this function returns the state of the overcurrent fault flags and automatically clears the flags (if set). This function returns true when an overcurrent event occurs. Otherwise, it returns false.
- The available APIs for the quadrature encoder are:
 - mcdrv_qd_enc_t: MCDRV QD structure data type.
 - void M1_MCDRV_ENC_PERIPH_INIT(): this function is by default called during the QD peripheral initialization procedure invoked by the MCDRV_Init_M1() function.
 - void M1_MCDRV_ENC_GET(mcdrv_qd_enc_t*): this function returns the actual position and speed.
 - void M1_MCDRV_ENC_SET_DIRECTION(mcdrv_qd_enc_t*): this function sets the direction of the quadrature encoder.
 - void M1_MCDRV_ENC_SET_PULSES(mcdrv_qd_enc_t*): this function sets the number of pulses of the quadrature encoder.
 - void M1_MCDRV_ENC_CLEAR(mcdrv_qd_enc_t*): this function clears the internal variables and decoder counter.

Note: Not all macros are available for every motor control example type. The structure data types may vary across the platforms.

7 User interface

The application contains the demo mode to demonstrate motor rotation. You can operate it either using the user button, or using FreeMASTER. The NXP development boards include a user button associated with a port interrupt (generated whenever one of the buttons is pressed). At the beginning of the ISR, a simple logic executes and the interrupt flag clears. When you press the button, the demo mode starts. When you press the same button again, the application stops and transitions back to the STOP state.

The other way to interact with the demo mode is to use the FreeMASTER tool. The FreeMASTER application consists of two parts: the PC application used for variable visualization and the set of software drivers running in the embedded application. The serial interface transfers data between the PC and the embedded application. This interface is provided by the debugger included in the boards.

The application can be controlled using the following two interfaces:

- The user button on the development board (controlling the demo mode):
 - MIMXRT1180-EVK - SW8
- Remote control using FreeMASTER (Following chapter):
 - Setting a variable in the FreeMASTER Variable Watch. See chapter [Section 8.4](#)

Identify all motor parameters if you are using your own motor (different from the default motors). The automated parameter identification is described in the following sections.

8 Remote control using FreeMASTER

This section provides information about the tools and recommended procedures to control the sensor/sensorless PMSM Field-Oriented Control (FOC) application using FreeMASTER. The application contains the embedded-side driver of the FreeMASTER real-time debug monitor and data visualization tool for communication with the PC. It supports non-intrusive monitoring, as well as the modification of target variables in real time, which is very useful for the algorithm tuning. Besides the target-side driver, the FreeMASTER tool requires the installation of the PC application as well. You can download the latest version of FreeMASTER at www.nxp.com/freemaster. To run the FreeMASTER application including the MCAT tool, double-click the `pmsm_float_enc.pmpx` file located in the `middleware\motor_control\freemaster` folder. The FreeMASTER application starts and the environment is created automatically, as defined in the `*.pmpx` file.

Note: In MCUXpresso, the FreeMASTER application can run directly from IDE in `motor_control/freemaster` folder.

8.1 Establishing FreeMASTER communication

The remote operation is provided by FreeMASTER via the USB interface. To control a PMSM motor using FreeMASTER, perform the steps below:

1. Download the project from your chosen IDE to the MCU and run it.
2. Open the FreeMASTER project `pmsm_float_enc.pmpx`. The PMSM project uses the TSA by default, so it is not necessary to select a symbol file for FreeMASTER.
3. To establish the communication, click the communication button (the green "GO" button in the top left-hand corner).

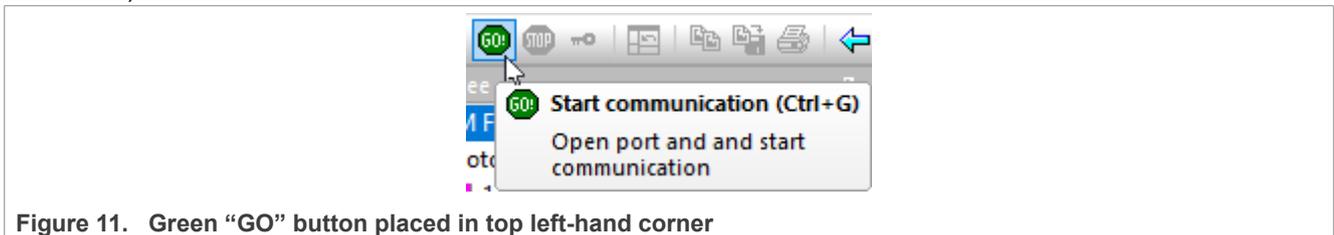


Figure 11. Green "GO" button placed in top left-hand corner

4. If the communication is established successfully, the FreeMASTER communication status in the bottom right-hand corner changes from "Not connected" to "RS-232 UART Communication; COMxx; speed=115200". Otherwise, the FreeMASTER warning pop-up window appears.



Figure 12. FreeMASTER—communication is established successfully

5. To reload the MCAT HTML page and check the App ID, press F5.
6. Control the PMSM motor by writing to a control variable in a variable watch.
7. If you rebuild and download the new code to the target, turn the FreeMASTER application off and on.

If the communication is not established successfully, perform the following steps:

1. Go to the **Project > Options > Comm** tab and make sure that the correct COM port is selected and the communication speed is set to 115200 bps.

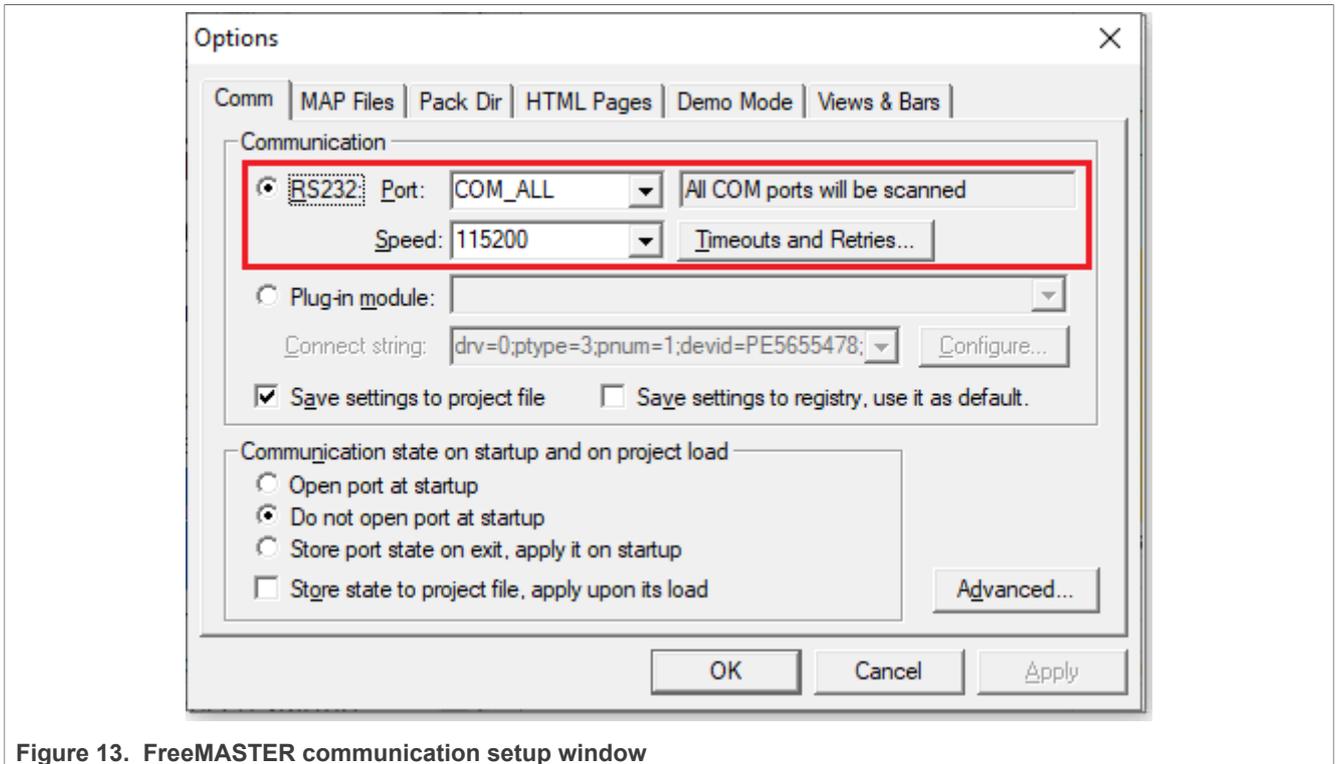


Figure 13. FreeMASTER communication setup window

2. Ensure, that your computer is communicating with the plugged board. Unplug and then plug in the USB cable and reopen the FreeMASTER project.

8.2 TSA replacement with ELF file

The FreeMASTER project for motor control example uses Target-Side Addressing (TSA) information about variable objects and types to be retrieved from the target application by default. With the TSA feature, you can describe the data types and variables directly in the application source code and make this information available to the FreeMASTER tool. The tool can then use this information instead of reading symbol data from the application's ELF/Dwarf executable file.

FreeMASTER reads the TSA tables and uses the information automatically when an MCU board is connected. A great benefit of using the TSA is no issues with the correct path to ELF/Dwarf file. The variables described by TSA tables may be read-only, so even if FreeMASTER attempts to write the variable, the target MCU side denies the value. The variables not described by any TSA tables may also become invisible and protected even for read-only access.

The use of TSA means more memory requirements for the target. If you do not want to use the TSA feature, you must modify the example code and FreeMASTER project.

To modify the example code, follow the steps below:

1. Open motor control project and rewrite macro `FMSTR_USE_TSA` from 1 to 0 in `freemaster_cfg.h` file.
2. Build, download, and run motor control project.
3. Open FreeMASTER project and click to **Project > Options** (or use shortcut `Ctrl+T`).
4. Click to **MAP Files** tab and find Default symbol file (ELF/Dwarf executable file) located in IDE output folder.

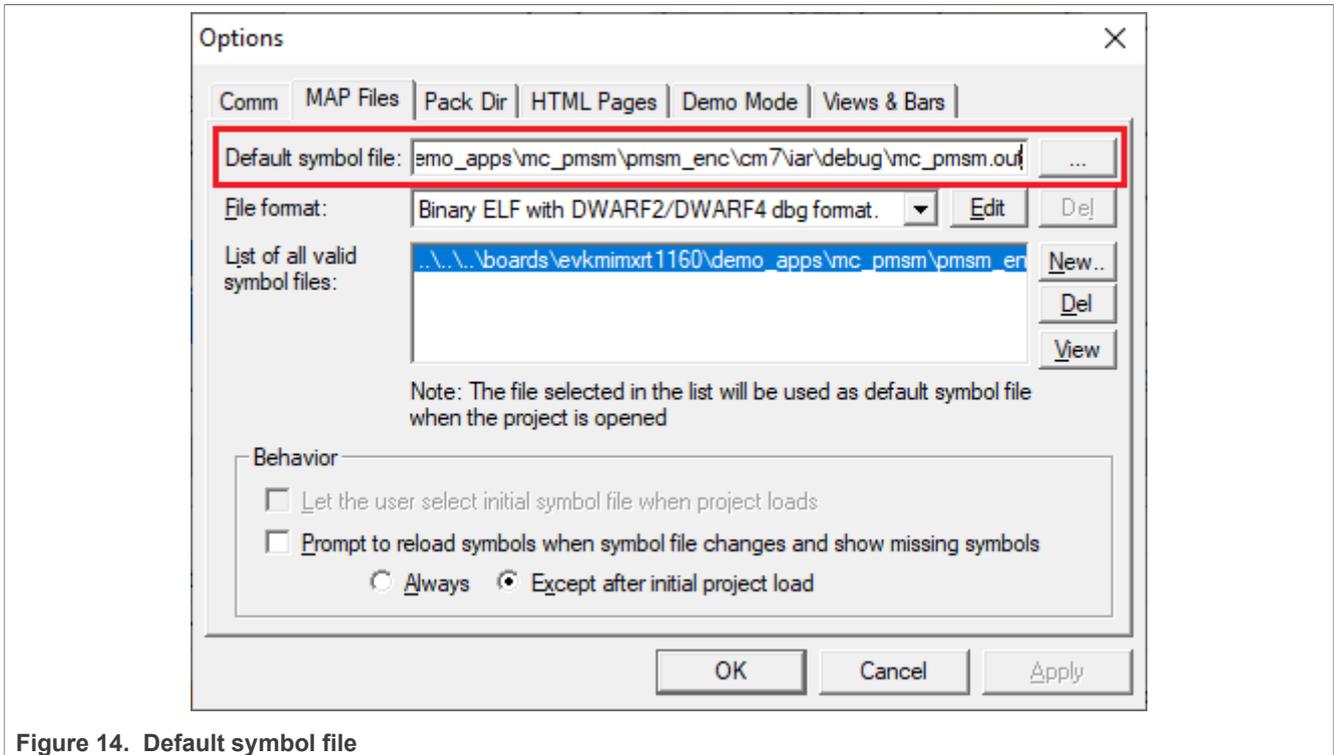


Figure 14. Default symbol file

5. Click **OK** and restart the FreeMASTER communication.

For more information, check [FreeMASTER User Guide](#).

8.3 Motor Control Application Tuning interface (MCAT)

The PMSM sensor/sensorless FOC application can be easily controlled and tuned using the [Motor Control Application Tuning \(MCAT\) plug-in for PMSM](#). The MCAT for PMSM is a user-friendly page, which runs within the FreeMASTER. The tool consists of the tab menu and workspace as shown in [Figure 15](#). Each tab from the tab menu (4) represents one submodule which enables tuning or controlling different application aspects. Besides the MCAT page for PMSM, several scopes, recorders, and variables in the project tree (5) are predefined in the FreeMASTER project file to further the motor parameter tuning and debugging simplify.

When the FreeMASTER is not connected to the target, the "Board found" line (2) shows "Board ID not found". When the communication with the target MCU is established, the "Board found" line is read from Board ID variable watch and displayed. If the connection is established and the board ID is not shown, press F5 to reload the MCAT HTML page.

There are three action buttons in MCAT (3):

- **Load data** - MCAT input fields (for example, motor parameters) are loaded from `mX_pmsm_appconfig.h` file (JSON formatted comments). Only existing `mX_pmsm_appconfig.h` files can be selected for loading. Loaded `mX_pmsm_appconfig.h` file is displayed in grey field (7).
- **Save data** - MCAT input fields (JSON formatted comments) and output macros are saved to `mX_pmsm_appconfig.h` file. Up to 9 files (`m1-9_pmsm_appconfig.h`) can be selected. A pop-up window with the user motor ID and description appears when a different `mX_pmsm_appconfig.h` file is selected. The motor ID and description are also saved in `mX_pmsm_appconfig.h` as a JSON comment. The embedded code includes `m1_pmsm_appconfig.h` only at single motor control application. Therefore, saving to higher indexed `mX_pmsm_appconfig.h` files has no effect at the compilation stage.
- **Update target** - writes the MCAT calculated tuning parameters to FreeMASTER Variables, which effectively updates the values on target MCU. These tuning parameters are updated in MCU's RAM. To write these

tuning parameters to MCU's flash memory, `m1_pmsm_appconfig.h` must be saved, code recompiled, and downloaded to MCU.

Every time the communication with the board is established or MCAT is refreshed by pressing F5, MCAT looks for the `m1_pmsm_appconfig.h` file. A path to `m1_pmsm_appconfig` is relative to `*.pmpx` file. The path is composed from the fixed defined folders name and from the following FreeMASTER variables: *User Path 1*, *User Path 2*, *Board ID*, *Example ID*. Variables *User Path 1* and *User Path 2* are intended for user's custom path to the `m1_pmsm_appconfig.h`. These variables are defined in example's `main.c` file where user can modify them. There are several possible paths with different priority (higher to lower) and typical use case:

1. *User Path 1*/
2. *User Path 2*/
3. `../boards/Board ID/mc_pmsm/Example ID/`
 - typical use case during SDK example development
4. `../../../../boards/Board ID/demo_apps/mc_pmsm/Example ID/`
 - typical use case in the SDK package
5. `../../../../boards/Board ID/demo_apps/mc_pmsm/Example ID/cm7/`
 - typical use case in the SDK package
6. `../../../../boards/Board ID/demo_apps/mc_pmsm/Example ID/cm33_core0/`
 - typical use case in the SDK package
7. `../../../../source/`
 - typical use case in the workspace

When the `m1_pmsm_appconfig.h` is found in one of the above defined path, it is loaded into the MCAT. Then, MCAT uses this directory for further operations (Load data, Save data). When `m1_pmsm_appconfig.h` is not found even in one of the path above, the default `m1_pmsm_appconfig.h` is loaded. The default `m1_pmsm_appconfig.h` is located in the `mcats` folder. In case of default file is loaded to the MCAT, newly saved `mX_pmsm_appconfig.h` files will be placed next to the `*.pmpx` file.

Note: Since the path to `mX_pmsm_appconfig.h` is composed from *User Path 1*, *User Path 2*, *Board ID* and *Example ID*, FreeMASTER must be connected to the target, and FreeMASTER variables value read prior using Save/Load buttons.

Note: Only **Update target** button updates values on the target in real time. Load/Save buttons operate with `mX_pmsm_appconfig.h` file only.

Note: MCAT may require Internet connection. If no Internet connection is available, CSS and icons may not be loaded properly.

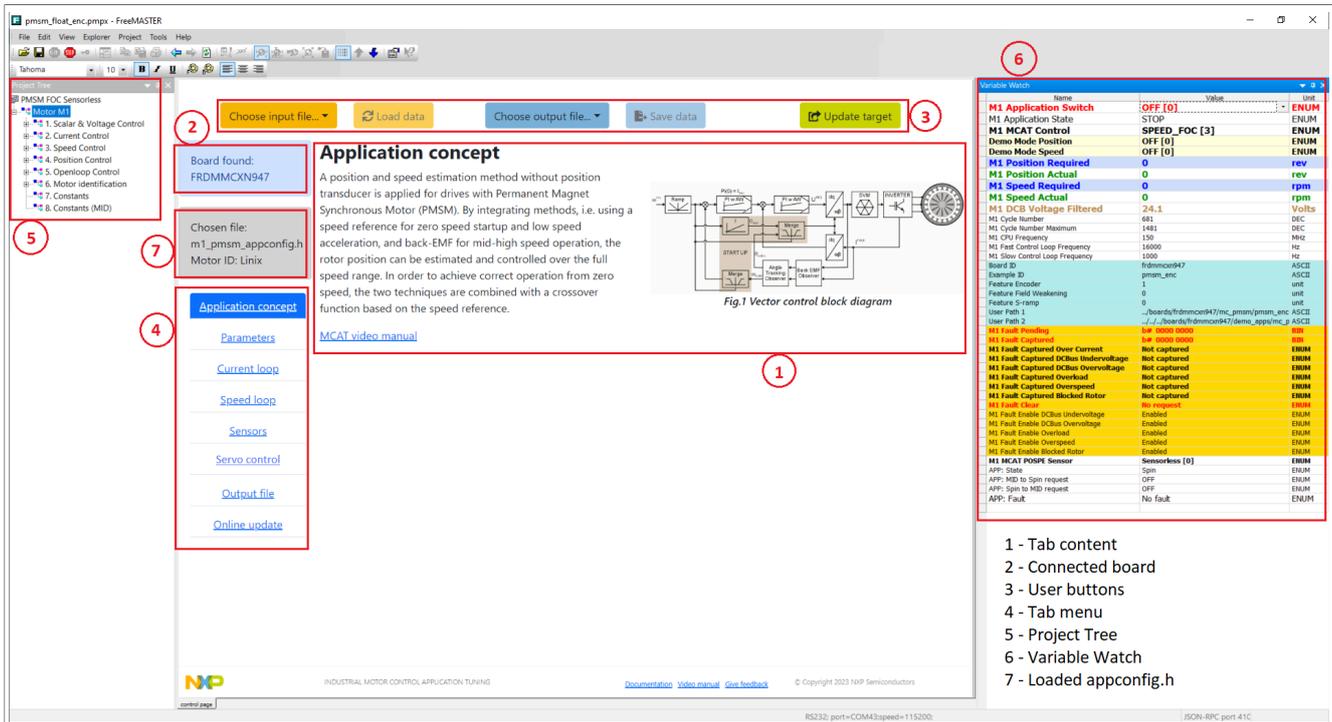


Figure 15. FreeMASTER + MCAT layout

In the default configuration, the following tabs (4) are available:

- Application concept: welcome page with the PMSM sensor/sensorless FOC diagram and a short application description.
- Parameters: this page enables you to modify the motor parameters, hardware and application scales specification, alignment, and fault limits.
- Current loop: current loop PI controller gains and output limits.
- Speed loop: this tab contains fields for the specification of the speed controller proportional and integral gains, as well as the output limits and parameters of the speed ramp. .
- Servo control: this tab contains fields for the specification of the position controller proportional gain, as well as the output limits.
- Sensorless: this page enables you to tune the parameters of the BEMF observer, tracking observer, and open-loop startup.
- Output file: this tab shows all the calculated constants that are required by the PMSM sensor/sensorless FOC application. It is also possible to generate the `mX_pmsm_appconfig.h` file, which is then used to preset all application parameters permanently at the project rebuild.
- Online update : this tab shows actual values of variables on target and new calculated values, which can be used to update the target variables.

Every sublock in FreeMASTER project tree (5) has defined several variables in variable watch (6).

The following sections provide simple instructions on how to identify the parameters of a connected PMSM motor and how to tune the application appropriately.

8.3.1 MCAT tabs description

This chapter describes MCAT input parameters and equations used to calculate MCAT output (generated) parameters. In the default configuration, the below described tabs are available. Some tabs may be missing

if not supported in the embedded code. There are general constants used at MCAT calculations listed in the following table:

Table 9. Constants used in equations

Constant	Value	Unit
UmaxCoeff	1.73205	-
DiscMethodFactor	2	-
k_factor	100	-
pi	3.1416	-

8.3.1.1 Application concept

This tab is a welcome page with the PMSM sensor/sensorless FOC diagram and a short description of the application.

8.3.1.2 Parameters

This tab enables modification of motor parameters, specification of hardware and application scales, alignment, and fault limits. All inputs are described in the following table. MCAT group and MCAT name help to locate the parameter in MCAT layout. Equation name represents the input parameter in equations below.

Table 10. Parameters tab inputs

MCAT group	MCAT name	Equation name	Description	Unit
Motor parameters	PP	parametersPp	Motor number of pole-pairs. Obtain from motor manufacturer or use the pole-pair assistant to determine and then fill manually.	-
	Rs	parametersRs	Stator phase resistance. Obtain from motor manufacturer or use the electrical parameters identification and then fill manually.	[Ω]
	Ld	parametersLd	Stator direct inductance. Obtain from motor manufacturer or use the electrical parameters identification and then fill manually.	[H]
	Lq	parametersLq	Stator quadrature inductance. Obtain from motor manufacturer or use the electrical parameters identification and then fill manually.	[H]
	Kt	parametersKt	Motor torque constant. Obtain from motor manufacturer or use the Kt identification and then fill manually.	[Nm/A]
	J	parametersJ	Drive inertia (motor + plant). Use the mechanical identification and then fill manually.	[kg.m2]
	Iph nom	parametersIphNom	Nominal motor current. Obtain from motor manufacturer.	[A]

MCUXpresso SDK Field-Oriented Control of 3-Phase PMSM and BLDC Motors (MIMXRT1180-EVK)

Table 10. Parameters tab inputs...continued

MCAT group	MCAT name	Equation name	Description	Unit
	Uph nom	parametersUphNom	Nominal motor voltage. Obtain from motor manufacturer.	[V]
	N nom	parametersNnom	Nominal motor speed. Obtain from motor manufacturer.	[rpm]
Hardware scales	I max	parametersImax	Current sensing HW scale. Keep as-is in case of standard NXP HW or recalculate according to own schematic.	[A]
	U DCB max	parametersUdcbMax	DCBus voltage sensing HW scale. Keep as-is in case of standard NXP HW or recalculate according to own schematic.	[V]
Fault limits	U DCB trip	parametersUdcbTrip	DCBus braking resistor threshold. Braking resistor's transistor is turned on when DCbus voltage exceeds this threshold.	[V]
	U DCB under	parametersUdcbUnder	DCBus under voltage fault threshold	[V]
	U DCB over	parametersUdcbOver	DCBus over voltage fault threshold	[V]
	N over	parametersNover	Over speed fault threshold	[rpm]
	N min	parametersNmin	Minimal closed loop speed. When the required speed ramps down under this threshold, the motor control state machine goes to freewheel state where top and bottom transistors are turned off and motor speeds down freely. Applies only for sensorless operation.	[rpm]
	E block	parametersEblock	Blocked rotor detection. When BEMF voltage drops under <i>E block</i> threshold for more than <i>E block per</i> (fast loop ticks), the blocked rotor fault is detected.	[V]
	E block per	parametersEblockPer		-
Application scales	N max	parametersNmax	Application speed scale. Keep about 10 % margin above <i>N over</i> .	[rpm]
	U DCB IIR F0	parametersUdcbIIRf0	Cut-off frequency of DCBus IIR filter	[Hz]
	Calibration duration	parametersCalibDuration	ADC (phase current offset) calibration duration. Done every time transitioning from STOP to RUN.	[sec]
	Fault duration	parametersFaultDuration	After fault condition disappears, wait defined time to clear pending faults bitfield and transition to STOP state.	[sec]

Table 10. Parameters tab inputs...continued

MCAT group	MCAT name	Equation name	Description	Unit
	Freewheel duration	parametersFreewheelDuration	Free-wheel state duration. Freewheel state is entered when ramped speed drops under <i>N min</i> .	[sec]
	Scalar Uq min	parametersScalarUqMin	Scalar control voltage minimal value.	[V]
	Scalar V/Hz factor ratio	parametersScalarVHzRatio	Scalar V/Hz ratio gain.	[%]
Alignment	Align voltage	parametersAlignVoltage	Motor alignment voltage.	[V]
	Align duration	parametersAlignDuration	Motor alignment duration.	[sec]

Output equations (applies for saving to `mX_pmsm_appconfig.h` and also for updating a corresponding FreeMASTER variable):

- $M1_U_MAX = parametersUdcbMax / UmaxCoeff$
- $M1_MOTOR_PP = parametersPp$
- $M1_I_PH_NOM = parametersIphNom$
- $M1_I_MAX = parametersImax$
- $M1_U_DCB_MAX = parametersUdcbMax$
- $M1_U_DCB_TRIP = parametersUdcbTrip$
- $M1_U_DCB_UNDERVOLTAGE = parametersUdcbUnder$
- $M1_U_DCB_OVERVOLTAGE = parametersUdcbOver$
- $M1_FREQ_MAX = parametersNmax / 60 * parametersPp$
- $M1_ALIGN_DURATION = parametersAlignDuration / speedLoopSampleTime$
- $M1_CALIB_DURATION = parametersCalibDuration / speedLoopSampleTime$
- $M1_FAULT_DURATION = parametersFaultDuration / speedLoopSampleTime$
- $M1_FREEWHEEL_DURATION = parametersFreewheelDuration / speedLoopSampleTime$
- $M1_E_BLOCK_TRH = parametersEblock$
- $M1_E_BLOCK_PER = parametersEblockPer$
- $M1_N_MIN = parametersNmin / 60 * (parametersPp * 2 * pi)$
- $M1_N_MAX = parametersNmax / 60 * (parametersPp * 2 * pi)$
- $M1_N_ANGULAR_MAX = (60 / (parametersPp * 2 * pi))$
- $M1_N_NOM = parametersNnom / 60 * (parametersPp * 2 * pi)$
- $M1_N_OVERSPEED = parametersNover / 60 * (parametersPp * 2 * pi)$
- $M1_UDCB_IIR_B0 = (2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime) / (2 + (2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime))$
- $M1_UDCB_IIR_B1 = (2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime) / (2 + (2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime))$
- $M1_UDCB_IIR_A1 = -(2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime - 2) / (2 + (2 * pi * parametersUdcbIIRf0 * currentLoopSampleTime))$
- $M1_SCALAR_UQ_MIN = parametersScalarUqMin$
- $M1_ALIGN_VOLTAGE = parametersAlignVoltage$
- $M1_SCALAR_VHZ_FACTOR_GAIN = parametersUphNom * parametersScalarVHzRatio / 100 / (parametersNnom * parametersPp / 60)$
- $M1_SCALAR_INTEG_GAIN = 2 * pi * parametersPp * parametersNmax / 60 * currentLoopSampleTime / pi$
- $M1_SCALAR_RAMP_UP = speedLoopIncUp * currentLoopSampleTime / 60 * parametersPp$
- $M1_SCALAR_RAMP_DOWN = speedLoopIncDown * currentLoopSampleTime / 60 * parametersPp$

8.3.1.3 Current loop

This tab enables current loop PI controller gains and output limits tuning. All inputs are described in the following table. MCAT group and MCAT name help to locate the parameter in MCAT layout. Equation name represents the input parameter in equations bellow.

Table 11. Current loop tab input

MCAT group	MCAT name	Equation name	Description	Unit
Loop parameters	Sample time	currentLoopSampleTime	Fast control loop period. This disabled value is read from target via FreeMASTER because application timing is set in embedded code by peripherals setting. This value is accessible only if target is not connected and value cannot be obtained from target.	[sec]
	F0	currentLoopF0	Current controller's bandwidth	[Hz]
	ξ	currentLoopKsi	Current controller's attenuation	-
Current PI controller limits	Output limit	currentLoopOutputLimit	Current controllers' output voltage limit = Duty cycle limit. Be careful setting this limit above 95 % because it affects current sensing (Some minimal bottom transistors on time is required).	[%]

Output equations (applies for saving to `mX_pmsm_appconfig.h` and also for updating a corresponding FreeMASTER variable):

- $M1_CLOOP_LIMIT = currentLoopOutputLimit / UmaxCoeff / 100$
- $M1_D_KP_GAIN = (2 * currentLoopKsi * 2 * pi * currentLoopF0 * parametersLd) - parametersRs$
- $M1_D_KI_GAIN = (2 * pi * currentLoopF0)^2 * parametersLd * currentLoopSampleTime / DiscMethodFactor$
- $M1_Q_KP_GAIN = (2 * currentLoopKsi * 2 * pi * currentLoopF0 * parametersLq) - parametersRs$
- $M1_Q_KI_GAIN = (2 * pi * currentLoopF0)^2 * parametersLq * currentLoopSampleTime / DiscMethodFactor$
- $kp_q = (4 * currentLoopKsi * pi * currentLoopF0 * parametersLq - parametersRs)$
- $ki_q = (parametersLq * (2 * pi * currentLoopF0)^2)$
- $Ti = kp_q / ki_q$
- $M1_Q_IIR_ZC_B0 = currentLoopSampleTime / (currentLoopSampleTime + 2 * Ti)$
- $M1_Q_IIR_ZC_B1 = currentLoopSampleTime / (currentLoopSampleTime + 2 * Ti)$
- $M1_Q_IIR_ZC_A1 = -(currentLoopSampleTime - 2 * Ti) / (currentLoopSampleTime + 2 * Ti)$

8.3.1.4 Speed loop

This tab enables speed loop PI controller gains and output limits tuning, required speed ramp parameters and feedback speed filter tuning. MCAT group and MCAT name help to locate the parameter in MCAT layout. Equation name represents the input parameter in equations bellow.

Table 12. Speed loop tab input

MCAT group	MCAT name	Equation name	Description	Unit
Loop parameters	Sample time Ts	speedLoopSampleTime	Slow control loop period. This disabled value is read from target via FreeMASTER because	[sec]

Table 12. Speed loop tab input...continued

MCAT group	MCAT name	Equation name	Description	Unit
			application timing is set in embedded code by peripherals setting. This value is accessible only if target is not connected and value cannot be obtained from target.	
	Bandwidth F0	speedLoopF0	Speed controller's bandwidth	[Hz]
	Attenuation ξ	speedLoopKsi	Speed controller's attenuation	-
Speed ramp	Inc up	speedLoopIncUp	Required speed maximal acceleration	[rpm/sec]
	Inc down	speedLoopIncDown	Required speed maximal acceleration	[rpm/sec]
Actual speed filter	Cut-off freq	speedLoopCutOffFreq	Speed feedback (before entering PI subtraction) filter bandwidth.	[Hz]
Speed PI controller limits	Upper limit	speedLoopUpperLimit	Maximal required Q-axis current (Speed controller's output). Q-axis current limitation equals to motor torque limitation.	[A]
	Lower limit	speedLoopLowerLimit	Minimal required Q-axis current (Speed controller's output). Q-axis current limitation equals to motor torque limitation.	[A]

Output equations (applies for saving to `mX_pmsm_appconfig.h` and also for updating a corresponding FreeMASTER variable):

- $M1_SPEED_PI_PROP_GAIN = (4 * speedLoopKsi * pi * speedLoopF0 * parametersJ) / (parametersKt * parametersPp)$
- $M1_SPEED_PI_INTEG_GAIN = ((2 * pi * speedLoopF0) * (2 * pi * speedLoopF0) * parametersJ) / (parametersKt * parametersPp) * (speedLoopSampleTime / DiscMethodFactor)$
- $M1_SPEED_RAMP_UP = (speedLoopIncUp * speedLoopSampleTime / (60 / (parametersPp * 2 * pi)))$
- $M1_SPEED_RAMP_DOWN = (speedLoopIncDown * speedLoopSampleTime / (60 / (parametersPp * 2 * pi)))$
- $M1_SPEED_IIR_B0 = (2 * pi * speedLoopCutOffFreq * speedLoopSampleTime) / (2 + (2 * pi * speedLoopCutOffFreq * speedLoopSampleTime))$
- $M1_SPEED_IIR_B1 = (2 * pi * speedLoopCutOffFreq * speedLoopSampleTime) / (2 + (2 * pi * speedLoopCutOffFreq * speedLoopSampleTime))$
- $M1_SPEED_IIR_A1 = -(2 * pi * speedLoopCutOffFreq * speedLoopSampleTime - 2) / (2 + (2 * pi * speedLoopCutOffFreq * speedLoopSampleTime))$
- $M1_SPEED_LOOP_HIGH_LIMIT = speedLoopUpperLimit$
- $M1_SPEED_LOOP_LOW_LIMIT = speedLoopLowerLimit$
- $Tfilt = M1_SPEED_PI_PROP_GAIN / (M1_SPEED_PI_INTEG_GAIN * (2 / speedLoopSampleTime))$
- $M1_SPEED_IIR_ZC_B0 = (speedLoopSampleTime / (speedLoopSampleTime + 2 * Tfilt))$
- $M1_SPEED_IIR_ZC_B1 = (speedLoopSampleTime / (speedLoopSampleTime + 2 * Tfilt))$
- $M1_SPEED_IIR_ZC_A1 = (-1) * (speedLoopSampleTime - 2 * Tfilt) / (speedLoopSampleTime + 2 * Tfilt)$

8.3.1.5 Servo control

This tab enables position loop P/PI controller gains and output limits tuning. MCAT group and MCAT name help to locate the parameter in MCAT layout. Equation name represents the input parameter in equations bellow.

Table 13. Servo control tab input

MCAT group	MCAT name	Equation name	Description	Unit
Servo control parameters	Sample time Ts	positionLoopSampleTime	Slow control loop period. This disabled value is read from target via FreeMASTER because application timing is set in embedded code by peripherals setting. This value is accessible only if target is not connected and value cannot be obtained from target.	[sec]
	Bandwidth F0	positionLoopF0	Servo controller's bandwidth	[Hz]
	Attenuation ξ	positionLoopKsi	Servo controller's attenuation	-
Position loop - P controller limits	Upper limit	positionPControllerHighLimit	Maximal required speed (Position controller's output)	[rpm/sec]
	Lower limit	positionPControllerLowLimit	Minimal required speed (Position controller's output)	[rpm/sec]
Speed loop - PI controller limits	Upper limit	servo_speedLoopUpperLimit	Maximal required Q-axis current (Speed controller's output). Q-axis current limitation equals to motor torque limitation.	[A]
	Lower limit	servo_speedLoopLowerLimit	Minimal required Q-axis current (Speed controller's output). Q-axis current limitation equals to motor torque limitation.	[A]

Output equations (applies for saving to `mX_pmsm_appconfig.h` and also for updating a corresponding FreeMASTER variable):

- $k10 = 1/(2 * pi * parametersPp)$
- $M1_SERVO_POSITION_P_PROP_GAIN = (2 * pi * positionLoopF0)/(2 * positionLoopKsi + 1) * k10$
- $M1_SERVO_POSITION_P_HIGH_LIMIT = (2 * pi * positionPControllerHighLimit * parametersPp / 60.0)$
- $M1_SERVO_POSITION_P_LOW_LIMIT = (2 * pi * positionPControllerLowLimit * parametersPp / 60.0)$
- $M1_SERVO_FEED_FRWD_K1 = (2 * positionLoopKsi * M1_SERVO_POSITION_P_PROP_GAIN / (2 * pi * positionLoopF0))$
- $M1_SERVO_FEED_FRWD_K2 = (M1_SERVO_POSITION_P_PROP_GAIN / ((2 * pi * positionLoopF0) * (2 * pi * positionLoopF0)))$
- $Tfilt = (2 * positionLoopKsi + 1) / ((2 * positionLoopKsi + 1) * 2 * pi * positionLoopF0)$
- $M1_SERVO_IIR_ZC_B0 = (positionLoopSampleTime / (positionLoopSampleTime + 2 * Tfilt))$
- $M1_SERVO_IIR_ZC_B1 = (positionLoopSampleTime / (positionLoopSampleTime + 2 * Tfilt))$
- $M1_SERVO_IIR_ZC_A1 = (-1) * (positionLoopSampleTime - 2 * Tfilt) / (positionLoopSampleTime + 2 * Tfilt)$
- $M1_SERVO_SPEED_PI_PROP_GAIN = ((2 * positionLoopKsi + 1) * (2 * pi * positionLoopF0) * parametersJ) / (parametersKt * parametersPp)$
- $M1_SERVO_SPEED_PI_INTEG_GAIN = ((parametersJ * (2 * positionLoopKsi + 1) * (2 * pi * positionLoopF0) * (2 * pi * positionLoopF0)) / (parametersKt * parametersPp)) * (positionLoopSampleTime / DiscMethodFactor)$

- M1_SERVO_SPEED_PI_HIGH_LIMIT = servo_speedLoopUpperLimit
- M1_SERVO_SPEED_PI_LOW_LIMIT = servo_speedLoopLowerLimit

8.3.1.6 Sensorless

This tab enables BEMF observer and Tracking observer parameters tuning and open-loop startup tuning. MCAT group and MCAT name help to locate the parameter in MCAT layout. Equation name represents the input parameter in equations bellow.

Table 14. Sensorless tab input

MCAT group	MCAT name	Equation name	Description	Unit
BEMF observer parameters	F0	sensorlessBemfObsrvF0	BEMF observer bandwidth	[Hz]
	ξ	sensorlessBemfObsrvKsi	BEMF observer attenuation	-
Tracking observer parameters	F0	sensorlessTrackObsrvF0	Tracking observer bandwidth	[Hz]
	ξ	sensorlessTrackObsrvKsi	Tracking observer attenuation	-
Open loop startup parameters	Startup ramp	sensorlessStartupRamp	Open loop startup ramp	[rpm/sec]
	Startup current	sensorlessStartupCurrent	Open loop startup current	[A]
	Merging Speed	sensorlessMergingSpeed	Merging speed	[rpm]
	Merging Coefficient	sensorlessMergingCoeff	Merging coefficient (100 % = merging is done within one electrical revolution)	[%]

Output equations (applies for saving to mX_pmsm_appconfig.h and also for updating a corresponding FreeMASTER variable):

- $M1_I_SCALE = (parametersLd / (parametersLd + currentLoopSampleTime * parametersRs))$
- $M1_U_SCALE = (currentLoopSampleTime / (parametersLd + currentLoopSampleTime * parametersRs))$
- $M1_E_SCALE = (currentLoopSampleTime / (parametersLd + currentLoopSampleTime * parametersRs))$
- $M1_WI_SCALE = (parametersLq * currentLoopSampleTime / (parametersLd + currentLoopSampleTime * parametersRs))$
- $M1_BEMF_DQ_KP_GAIN = ((2 * sensorlessBemfObsrvKsi * 2 * pi * sensorlessBemfObsrvF0 * parametersLd - parametersRs))$
- $M1_BEMF_DQ_KI_GAIN = (parametersLd * (2 * pi * sensorlessBemfObsrvF0)^2 * currentLoopSampleTime)$
- $M1_TO_KP_GAIN = 2 * sensorlessTrackObsrvKsi * 2 * pi * sensorlessTrackObsrvF0$
- $M1_TO_KI_GAIN = ((2 * pi * sensorlessTrackObsrvF0)^2 * currentLoopSampleTime)$
- $M1_TO_THETA_GAIN = (currentLoopSampleTime / pi)$
- $M1_OL_START_RAMP_INC = (sensorlessStartupRamp * currentLoopSampleTime / (60 / (parametersPp * 2 * pi)))$
- $M1_OL_START_I = sensorlessStartupCurrent$
- $M1_MERG_SPEED_TRH = (sensorlessMergingSpeed / (60 / (parametersPp * 2 * pi)))$
- $M1_MERG_COEFF = ((sensorlessMergingCoeff / 100) * sensorlessMergingSpeed * parametersPp * currentLoopSampleTime) / 60$
- $TO_IIR_cutoff_freq = 1 / (2 * speedLoopSampleTime) * 0.8$
- $M1_TO_SPEED_IIR_B0 = (2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime) / (2 + (2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime))$
- $M1_TO_SPEED_IIR_B1 = (2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime) / (2 + (2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime))$

- $M1_TO_SPEED_IIR_A1 = -(2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime - 2) / (2 + (2 * pi * TO_IIR_cutoff_freq * currentLoopSampleTime))$

8.4 Motor Control Modes - How to run motor

In the "Project Tree", you can choose between the scalar and FOC control using the appropriate FreeMASTER tabs. The FreeMASTER variables can control the application, corresponding to the control structure selected in the FreeMASTER project tree. This is useful for application tuning and debugging. The required control structure must be selected in the "M1 MCAT Control" variable. To turn on or off the application, use "M1 Application Switch" variable. Set/clear "M1 Application Switch" variable also enables/disables all PWM channels.

Before motor starts, several conditios have to be completed:

1. Connected power supply to the inverter with the correct voltage value.
2. If you want to use sensed control (encoder feedback), connect the encoder to the inverter.
3. No pending fault. Check variable "M1 Fault Pending" in "Motor M1" project tree subblock. If there is some value, first remove the cause of the fault, or disable fault checking. (for example in variable "M1 Fault Enable Blocked Rotor")

8.4.1 Scalar control

The scalar control diagram is shown in figure below. It is the simplest type of motor-control techniques. The ratio between the magnitude of the stator voltage and the frequency must be kept at the nominal value. Therefore, the control method is sometimes called Volt per Hertz (or V/Hz). The position estimation BEMF observer and tracking observer algorithms run in the background, even if the estimated position information is not directly used. This is useful for the BEMF observer tuning. For more information, see the *Sensorless PMSM Field-Oriented Control* (document [DRM148](#)).

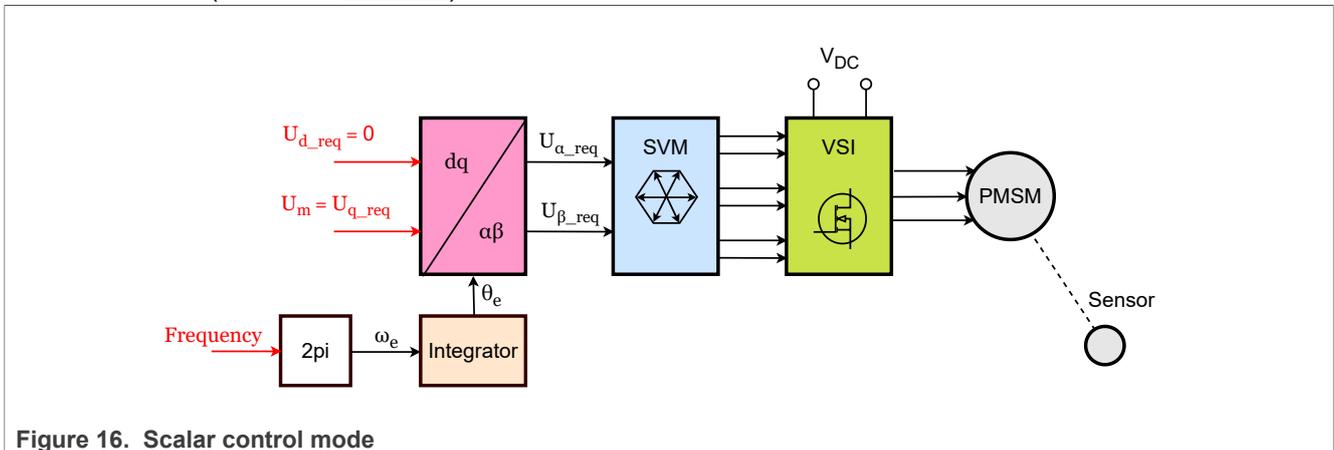


Figure 16. Scalar control mode

For run motor in scalar control, follow these steps:

1. Switch project tree subblock on "Scalar & Voltage Control".
2. Switch variable "M1 MCAT Control" on "SCALAR_CONTROL".
3. In variable "M1 Scalar Freq Required" set required frequency. (i.e. 20Hz)
4. Set variable "M1 Application Switch" to "1". Motor start spinning.
5. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.4.2 Open loop control mode

Open loop mode (its diagram is shown in figure below) is similar in function to the Scalar control mode. However, it provides more flexibility in specifying required parameters. This mode allows you to set specific angle and frequency, according to the following equation:

$$\theta_{el} = \theta_{init} + \int_{t_0}^t 2\pi f dt \tag{4}$$

Besides setting voltage in DQ axis, when using this mode you can also enable current controllers and specify required currents in D and Q axis. Therefore, this function can be utilized for current controller parameter tuning. Please, bear in mind that current controllers cannot be enabled/disabled in SPIN state (user must turn the Application Switch OFF before enabling/disabling current controllers).

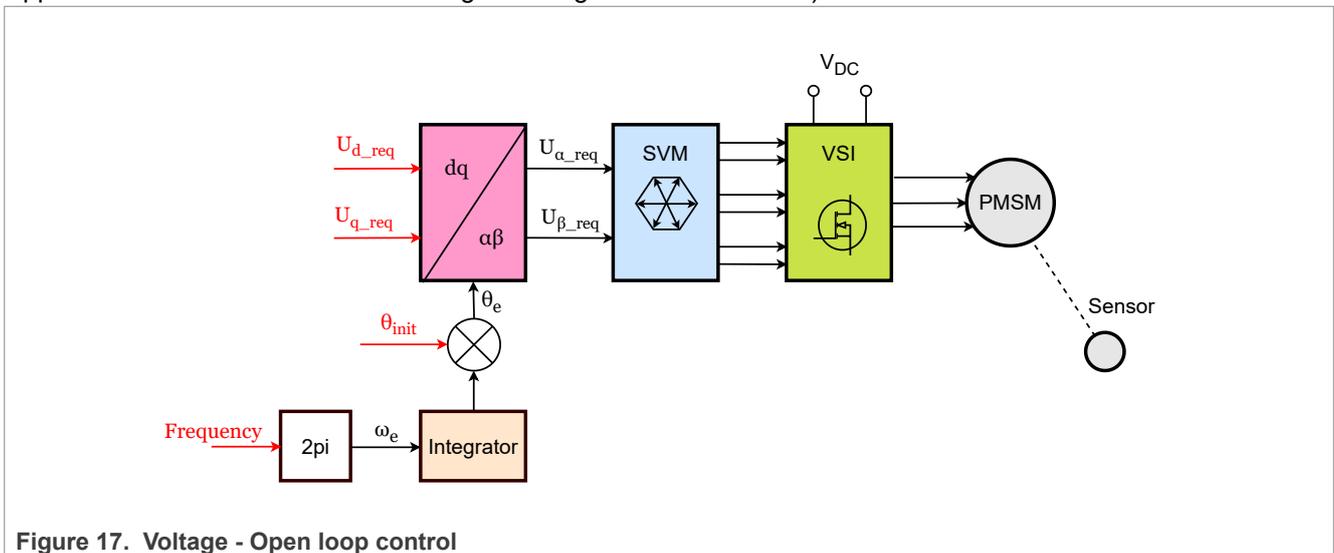


Figure 17. Voltage - Open loop control

For run motor in Voltage - Open loop control, follow these steps:

1. Switch project tree subblock on "Openloop Control".
2. Switch variable "M1 MCAT Control" on "OPEN_LOOP".
3. In variable "M1 Openloop Required Ud" and "M1 Openloop Required Uq" set required values.
4. In variable "M1 Openloop Theta Electrical" set required initial position.
5. In variable "M1 Openloop Required Frequency Electrical" set required frequency.
6. Set variable "M1 Application Switch" to "1". Motor start spinning.
7. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

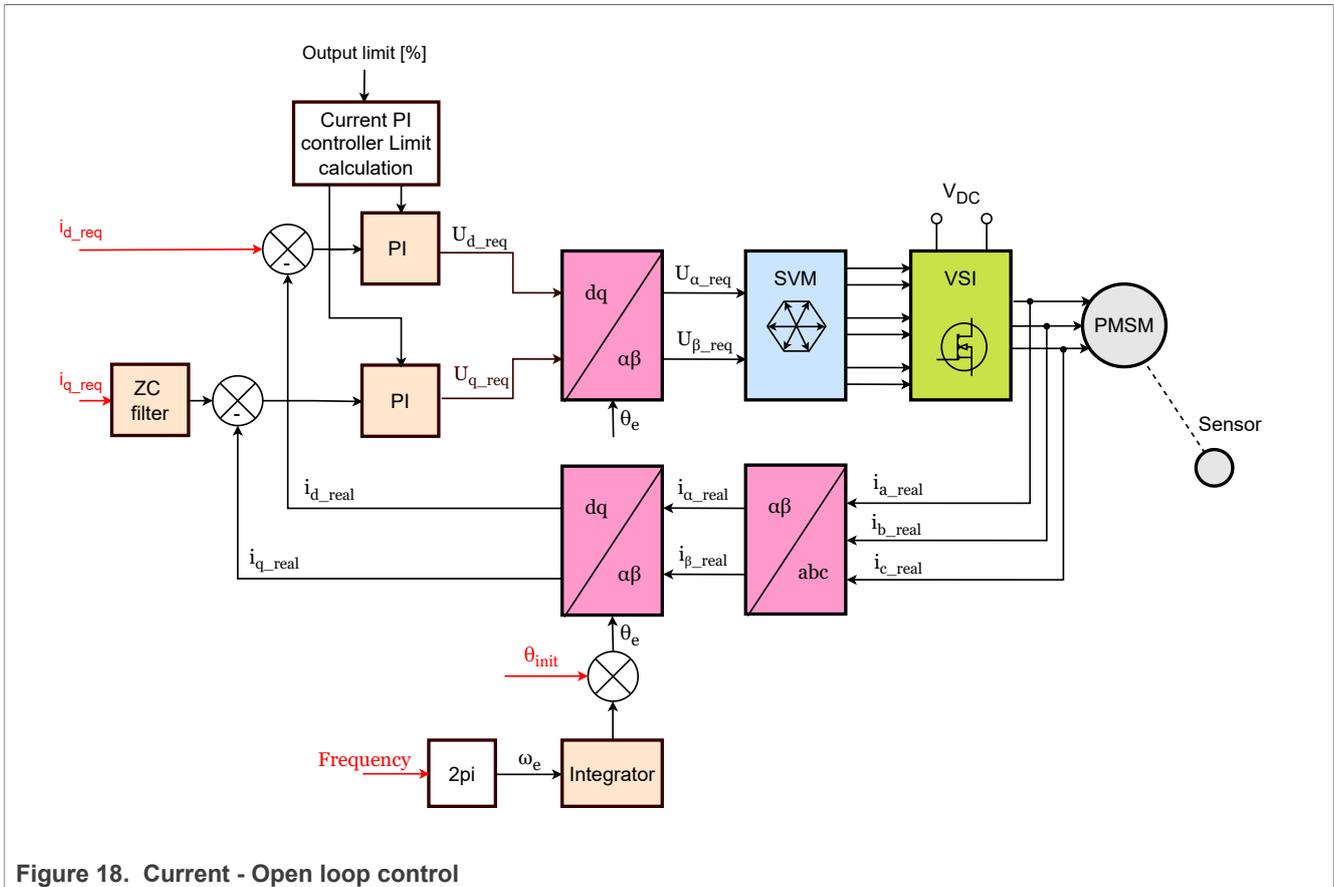


Figure 18. Current - Open loop control

For run motor in Current - Open loop control, follow these steps:

1. Switch project tree subblock on "Openloop Control".
2. Switch variable "M1 MCAT Control" on "OPEN_LOOP".
3. Set variable "M1 Openloop Use I Control" to "1".
4. In variable "M1 Openloop Required Id" and "M1 Openloop Required Iq" set required values.
5. In variable "M1 Openloop Theta Electrical" set required initial position.
6. In variable "M1 Openloop Required Frequency Electrical" set required frequency.
7. Set variable "M1 Application Switch" to "1". Motor start spinning.
8. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.4.3 Voltage control

The block diagram of the voltage FOC is shown in [Figure 19](#). Unlike the scalar control, the position feedback is closed using the BEMF observer and the stator voltage magnitude is not dependent on the motor speed. Both the d-axis and q-axis stator voltages can be specified in the "M1 MCAT Ud Required" and "M1 MCAT Uq Required" fields. This control method is useful for the BEMF observer functionality check.

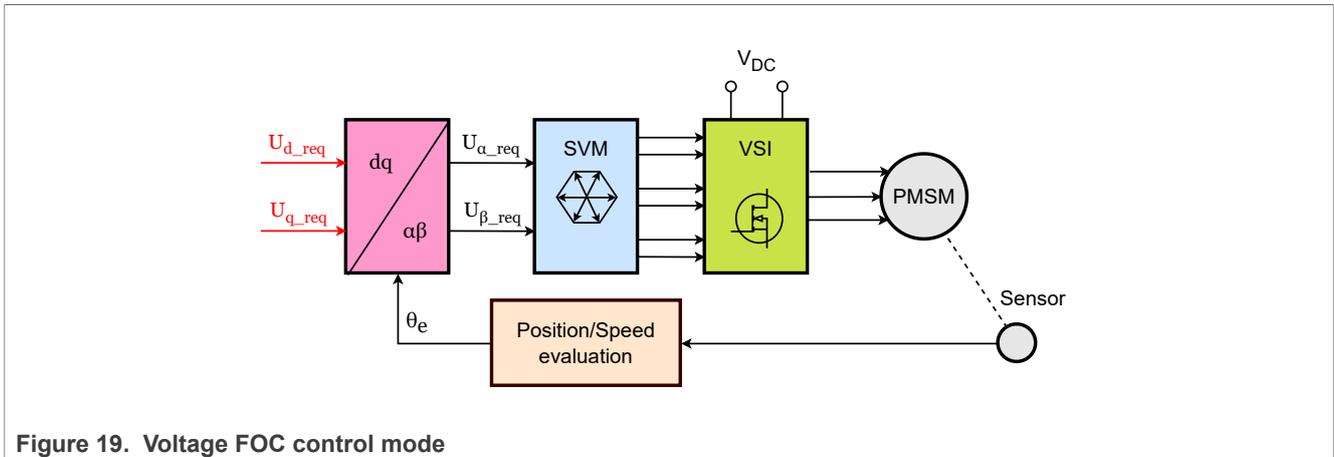


Figure 19. Voltage FOC control mode

For run motor in voltage control, follow these steps:

1. Switch project tree subblock on "Scalar & Voltage Control".
2. Switch variable "M1 MCAT Control" on "VOLTAGE_FOC".
3. In variable "M1 MCAT Uq Required" and "M1 MCAT Ud Required" set required voltages.
4. Set variable "M1 Application Switch" to "1". Motor start spinning.
5. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.4.4 Current/Torque control

The current FOC (or torque) control requires the rotor position feedback and the currents transformed into a d-q reference frame. There are two reference variables ("M1 MCAT Id Required" and "M1 MCAT Iq Required") available for the motor control, as shown in [Figure 20](#). The d-axis current component "M1 MCAT Id Required" controls the rotor flux. The q-axis current component of the current "M1 MCAT Iq Required" generates torque and, by its application, the motor starts running. By changing the polarity of the current "M1 MCAT Iq Required", the motor changes the direction of rotation. Supposing the BEMF observer is tuned correctly, the current PI controllers can be tuned using the current FOC control structure.

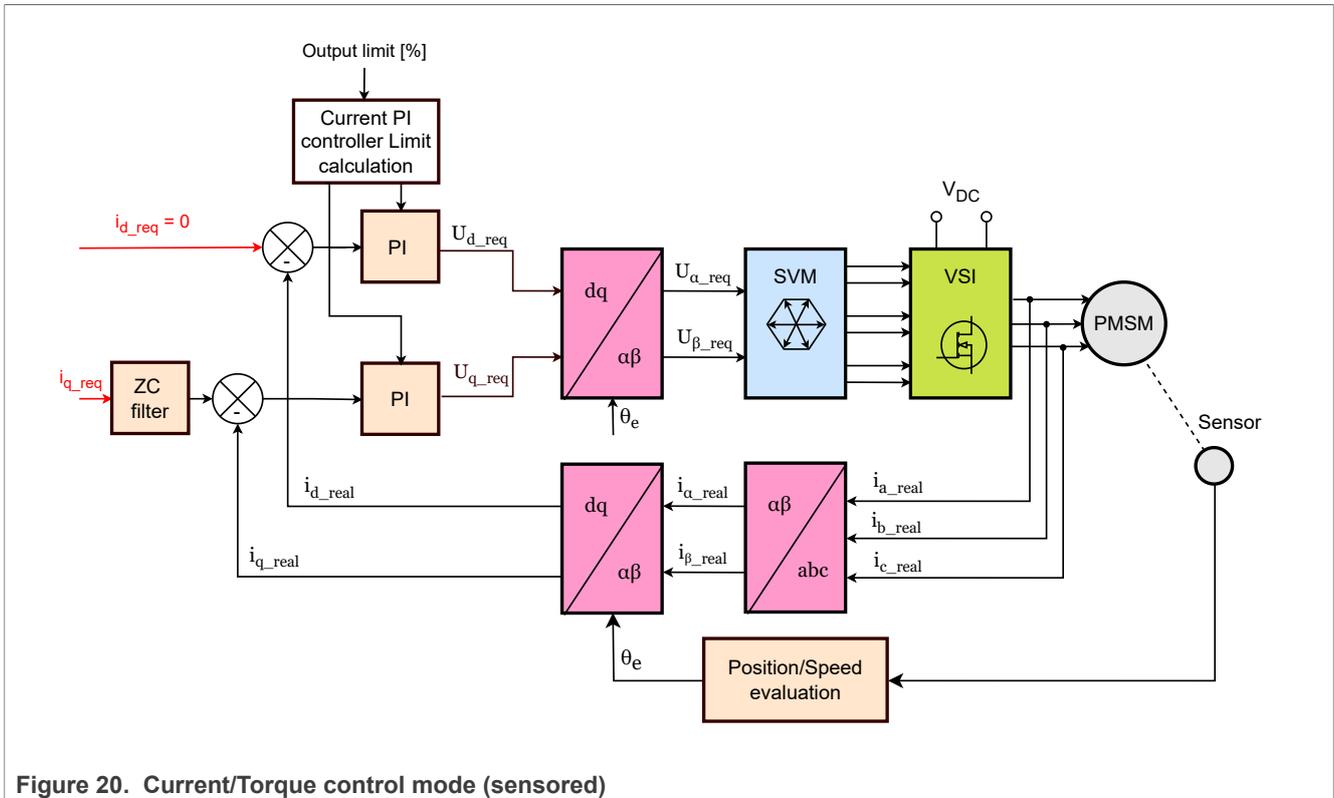


Figure 20. Current/Torque control mode (sensored)

For run motor in current control, follow these steps:

1. Switch project tree subblock on "Current Control".
2. Switch variable "M1 MCAT Control" on "CURRENT_FOC".
3. In variable "M1 MCAT Iq Required" and "M1 MCAT Id Required" set required currents.
4. Set variable "M1 Application Switch" to "1". Motor start spinning.
5. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.4.5 Speed FOC control

As shown in [Figure 21](#), the speed PMSM sensor/sensorless FOC is activated by enabling the speed FOC control structure. Enter the required speed into the "M1 Speed Required" field. The d-axis current reference is held at 0 during the entire FOC operation.

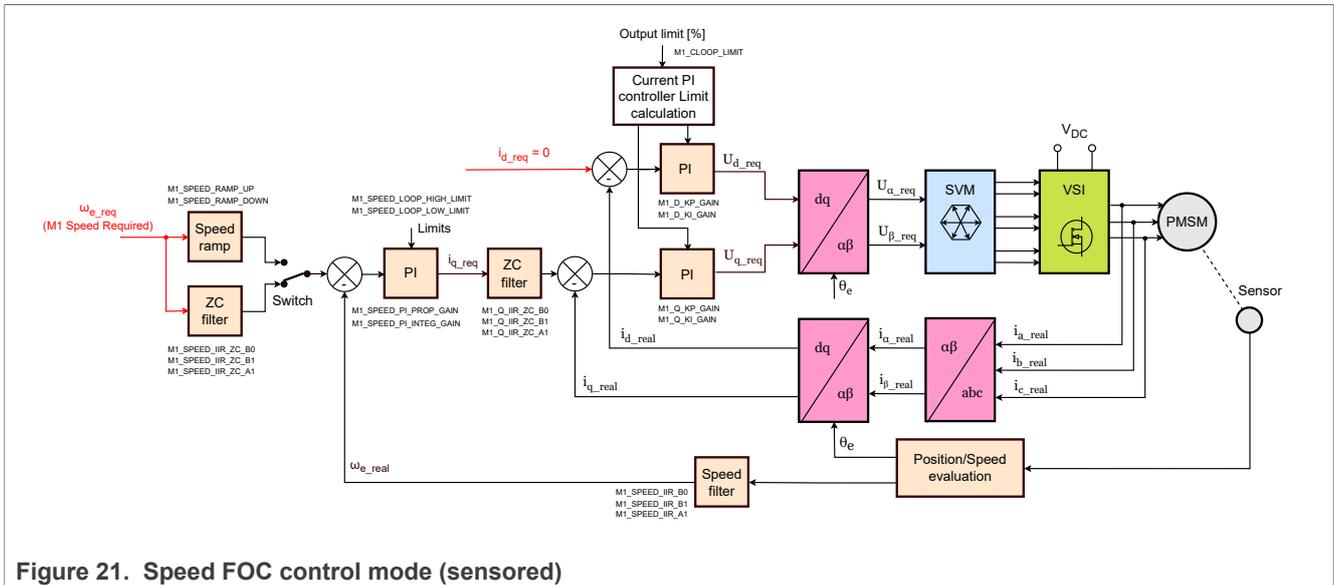


Figure 21. Speed FOC control mode (sensored)

For run motor in speed FOC control, follow these steps:

1. Switch project tree subblock on "Speed Control".
2. Switch variable "M1 MCAT Control" on "SPEED_FOC".
3. Choose between sensed and sensorless control in variable "M1 MCAT POSPE Sensor".
4. In variable "M1 Speed Required" set the required speed. (i.e. 1000rpm). The motor automatically starts spinning.
5. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.4.6 Position (servo) control

The position of PMSM sensor FOC is shown in [Figure 22](#) (available for sensed/encoder based applications only). The position control using the P controller can be tuned in the "Servo control" menu tab. An encoder sensor is required for the feedback. Without the sensor, the position control does not work. A braking resistor is missing on the FRDM-MC-LVPMSM board. Therefore, it is necessary to set a soft parameters of P controller because the voltage on the DC-bus can rise when braking the quickly spinning shaft. It may cause an overvoltage fault.

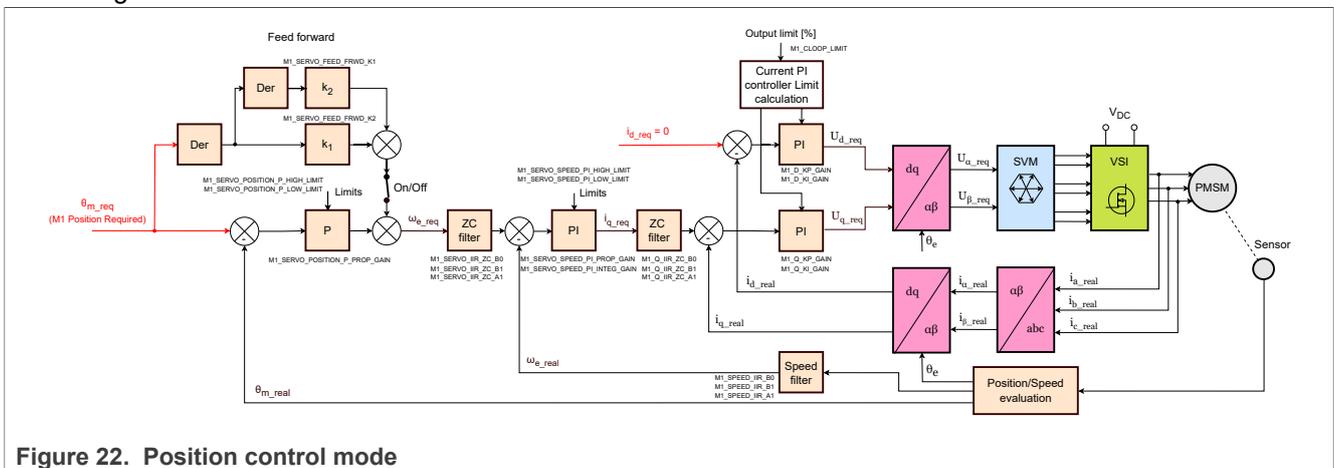


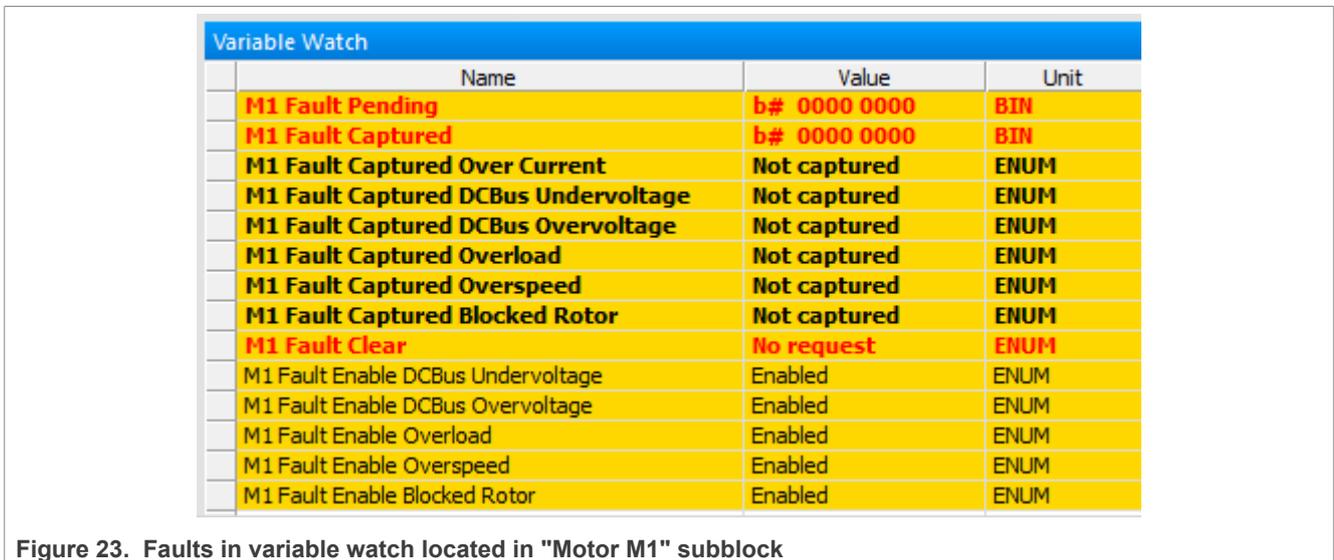
Figure 22. Position control mode

For run motor in position (servo) control, follow these steps:

1. Switch project tree subblock on "Position Control".
2. Switch variable "M1 MCAT Control" on "POSITION_CNTRL".
3. Switch variable "M1 MCAT POSPE Sensor" to "Encoder [1]".
4. In variable "M1 Position Required" set the required position. (i.e. 10 revs).
5. Set variable "M1 Application Switch" to "1". The motor starts and automatically stops in the required position.
6. Change "M1 Encoder Direction" if the motor does not spin. (See chapter [Section 8.10.1](#))
7. Observe motor speed, position, phase currents and other graphs predefined in subblock scopes and recorders.

8.5 Faults explanation

When the motor is running or during the tuning process, there may be several fault conditions. Therefore, the motor-control example has an integrated fault indication located in the variable watch of the "Motor M1" FreeMASTER subblock. If a fault is indicated, state machine enters the FAULT state.



8.5.1 Variable "M1 Fault Pending"

It shows actually persisting faults, which means that the fault indicated during fault conditions is accomplished. For example, if the source voltage is still under the undervoltage fault threshold, the undervoltage pending fault is shown. If the fault condition disappears, the fault pending is cleared automatically. "M1 Fault Pending" is shown in a binary format in the FreeMASTER variable watch. Each place in the variable denotes a different fault condition.

- b 0000 0001 - the overcurrent fault is indicated. If the overcurrent fault is present, the PWMs are automatically disabled. The fault occurs when the DC-Bus current exceeds the **I_{max}** value (current-sensing HW scale).
- b 0000 0010 - the undervoltage fault is indicated. The undervoltage fault occurs when the UDCBus voltage (source voltage) is lower than the **U DCB under** threshold.
- b 0000 0100 - the overvoltage fault is indicated. The overvoltage fault occurs when the UDCBus voltage (source voltage) is higher than the **U DCB over** threshold.
- b 0000 1000 - the overload fault is indicated. The overload fault occurs when the rotor is overloaded.
- b 0001 0000 - the overspeed fault is indicated. The overspeed fault occurs when the rotor speed exceeds the **N over** threshold.

- b 0010 0000 - the block rotor fault is indicated. The block rotor fault occurs when the back-EMF voltage is lower than the **E block** threshold and the duration of the drop is longer than **E block per**.

Variable Watch		
Name	Value	Unit
M1 Fault Pending	b# 0000 0010	BIN
M1 Fault Captured	b# 0000 0010	BIN
M1 Fault Captured Over Current	Not captured	ENUM
M1 Fault Captured DCBus Undervoltage	Captured	ENUM
M1 Fault Captured DCBus Overvoltage	Not captured	ENUM
M1 Fault Captured Overload	Not captured	ENUM
M1 Fault Captured Overspeed	Not captured	ENUM
M1 Fault Captured Blocked Rotor	Not captured	ENUM
M1 Fault Clear	No request	ENUM
M1 Fault Enable DCBus Undervoltage	Enabled	ENUM
M1 Fault Enable DCBus Overvoltage	Enabled	ENUM
M1 Fault Enable Overload	Enabled	ENUM
M1 Fault Enable Overspeed	Enabled	ENUM
M1 Fault Enable Blocked Rotor	Enabled	ENUM

Figure 24. Undervoltage fault is indicated (pending)

8.5.2 Variable "M1 Fault Captured"

If any fault condition appears, the fault captured is indicated. Similar to fault pending, fault captured is shown in the BIN format, but every fault type has its own variable ("M1 Fault Captured Over Current" and others). For example, if the undervoltage fault condition is accomplished, fault captured is indicated. Fault captured is also indicated after the undervoltage fault condition disappears. The captured faults are cleared manually by writing "Clear [1]" to "M1 Fault Clear".

Variable Watch		
Name	Value	Unit
M1 Fault Pending	b# 0000 0000	BIN
M1 Fault Captured	b# 0000 0010	BIN
M1 Fault Captured Over Current	Not captured	ENUM
M1 Fault Captured DCBus Undervoltage	Captured	ENUM
M1 Fault Captured DCBus Overvoltage	Not captured	ENUM
M1 Fault Captured Overload	Not captured	ENUM
M1 Fault Captured Overspeed	Not captured	ENUM
M1 Fault Captured Blocked Rotor	Not captured	ENUM
M1 Fault Clear	No request	ENUM
M1 Fault Enable DCBus Undervoltage	Enabled	ENUM
M1 Fault Enable DCBus Overvoltage	Enabled	ENUM
M1 Fault Enable Overload	Enabled	ENUM
M1 Fault Enable Overspeed	Enabled	ENUM
M1 Fault Enable Blocked Rotor	Enabled	ENUM

Figure 25. Undervoltage fault is captured

8.5.3 Variable "M1 Fault Enable"

The fault indication can be unwanted during the tuning process. Therefore, the fault indication can be disabled by writing "Disabled [0]" to the "M1 Fault Enable" variables.

Note: *The overcurrent fault cannot be disabled.*

Note: Fault thresholds are located in the "MCAT parameters" tab.

8.6 Initial motor parameters and hardware configuration

Motor control examples contain two or more configuration files: `m1_pmsm_appconfig.h`, `m2_pmsm_appconfig.h`, and so on. Each contains constants tuned for the selected motor (see supported motors in [Section 2](#)). The initial motor parameters and the hardware configuration (inverter) are to MCAT loaded from `m1_pmsm_appconfig.h` configuration file. There are three ways to change motor configuration corresponding to the connected motor.

1. The first way is rename the configuration file:
 - In the project example folder, find configuration file to be used.
 - Rename this configuration file to `m1_pmsm_appconfig.h`.
 - Rebuild project and load the code to the MCU.
2. The second way is to change motor configuration, as described in [Section 8.3](#).
3. The last way is change motor and hardware parameters manually:
 - Open the PMSM control application FreeMASTER project containing the dedicated MCAT plug-in module.
 - Select the "Parameters" tab.
 - Specify the parameters manually. The motor parameters can be obtained from the motor data sheet or using the PMSM parameters measurement procedure described in *PMSM Electrical Parameters Measurement* (document [AN4680](#)). All parameters provided in [Table 15](#) are accessible. The motor inertia J expresses the overall system inertia and can be obtained using a mechanical measurement. The J parameter is used to calculate the speed controller constant. However, the manual controller tuning can also be used to calculate this constant.

Table 15. MCAT motor parameters

Parameter	Units	Description	Typical range
pp	[-]	Motor pole pairs	1-10
Rs	[Ω]	1-phase stator resistance	0.3-50
Ld	[H]	1-phase direct inductance	0.00001-0.1
Lq	[H]	1-phase quadrature inductance	0.00001-0.1
Ke	[V.sec/rad]	BEMF constant	0.001-1
J	[kg.m ²]	System inertia	0.00001-0.1
Iph nom	[A]	Motor nominal phase current	0.5-8
Uph nom	[V]	Motor nominal phase voltage	10-300
N nom	[rpm]	Motor nominal speed	1000-2000

- Set the hardware scales—the modification of these two fields is not required when a reference to the standard power stage board is used. These scales express the maximum measurable current and voltage analog quantities.
- Check the fault limits—these fields are calculated using the motor parameters and hardware scales (see [Table 16](#)).

Table 16. Fault limits

Parameter	Units	Description	Typical range
U DCB trip	[V]	Voltage value at which the external braking resistor switch turns on	U DCB Over ~ U DCB max
U DCB under	[V]	Trigger value at which the undervoltage fault is detected	0 ~ U DCB Over
U DCB over	[V]	Trigger value at which the overvoltage fault is detected	U DCB Under ~ U max
N over	[rpm]	Trigger value at which the overspeed fault is detected	N nom ~ N max
N min	[rpm]	Minimal actual speed value for the sensorless control	(0.05~0.2) * N max

- Check the application scales—these fields are calculated using the motor parameters and hardware scales (see [Table 17](#)).

Table 17. Application scales

Parameter	Units	Description	Typical range
N max	[rpm]	Speed scale	>1.1 * N nom
E block	[V]	BEMF scale	ke* Nmax
kt	[Nm/A]	Motor torque constant	-

- Check the alignment parameters—these fields are calculated using the motor parameters and hardware scales. The parameters express the required voltage value applied to the motor during the rotor alignment and its duration.
- To save the modified parameters into the inner file, click the "Store data" button.

8.7 Identifying parameters of user motor

Because the model-based control methods of the PMSM drives provide high performance (for example, dynamic response, efficiency), obtaining an accurate model of a motor is an important part of the drive design and control. For the implemented FOC algorithms, it is necessary to know the value of the stator resistance R_s , direct inductance L_d , quadrature inductance L_q , and BEMF constant K_e . Unless the default PMSM motor described above is used, the motor parameter identification is the first step in the application tuning. This section shows how to identify user motor parameters using MID. MID is written in floating-point arithmetics. Each MID algorithm is detailed in [Section 8.8](#). MID is controlled via the FreeMASTER "Motor Identification" page shown in [Figure 26](#).

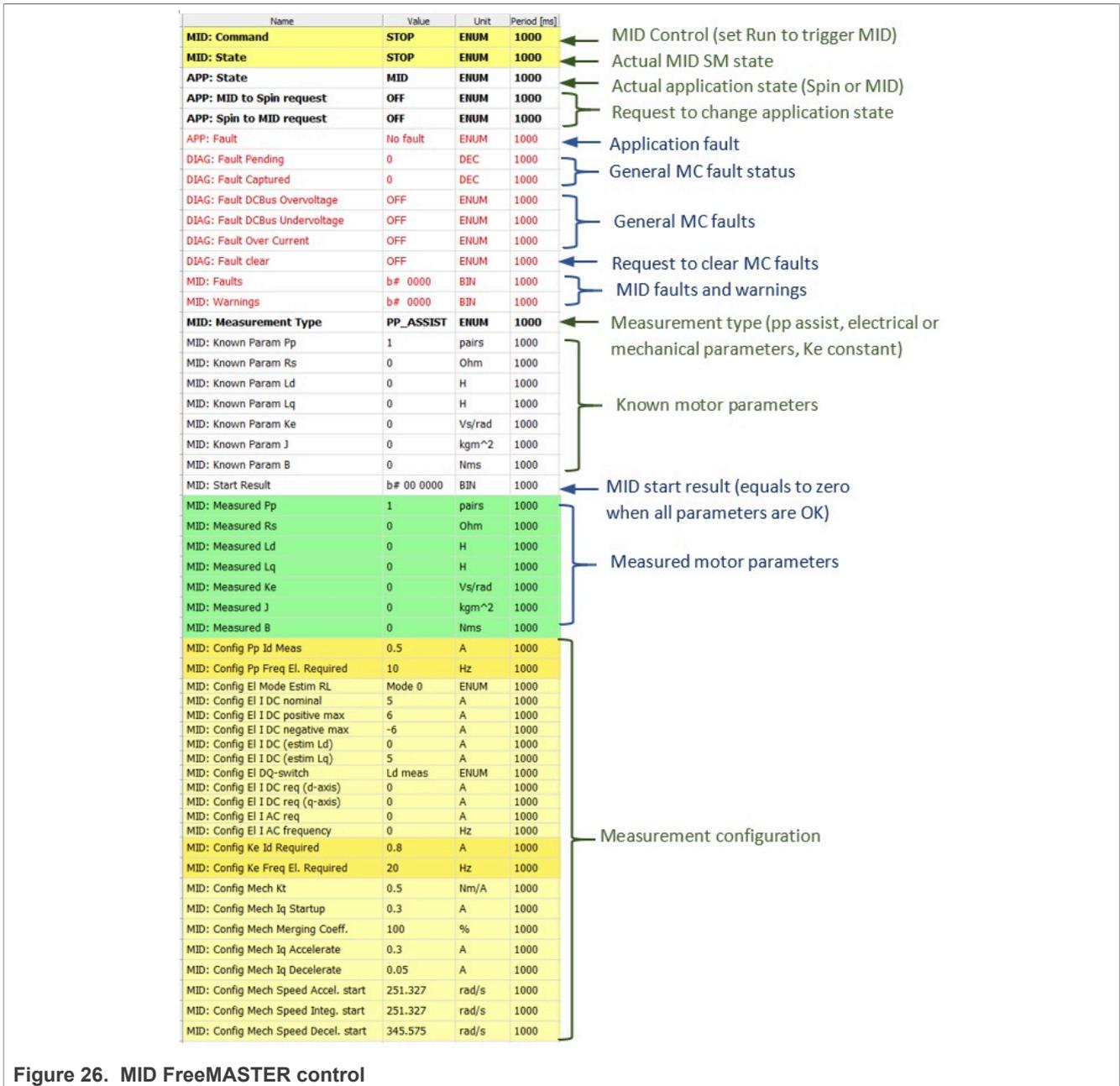


Figure 26. MID FreeMASTER control

8.7.1 Switch between Spin and MID

Users can switch between two modes of application: *Spin* and *MID* (Motor Identification). *Spin* mode is used for control PMSM (see [Section 8.3](#)). *MID* mode is used for motor parameters identification (see [Section 8.7.2](#)). The actual mode of application is shown in *APP: State* variable. The mode is changed by writing one to *APP: MID to Spin request* or *APP: Spin to MID request* variables. The transition between Spin and MID can be done only if the actual mode is in a defined stop state (for example, MID not in progress or motor stopped). The result of the change mode request is shown in *APP: Fault* variable. MID fault occurs when parameters identification still runs, or the MID state machine is in the fault state. A spin fault occurs when *M1 Application switch* variable watch is ON, or *M1 Application state* variable watch is not STOP.

8.7.2 Motor parameter identification using MID

The whole MID is controlled via the FreeMASTER "Variable Watch". The Motor Identification (MID) subblock is shown in [Figure 26](#). Following is the motor parameter identification workflow:

1. Set the *MID: Command* variable to STOP.
2. Select the measurement type that you want to perform via the *MID: Measurement Type* variable:
 - PP_ASSIST - Pole-pair identification assistant
 - EL_PARAMS - Electrical parameters measurement
 - Ke - BEMF constant measurement
 - MECH_PARAMS - Mechanical parameters measurement
3. Insert the known motor parameters via the *MID: Known Param* set of variables. All parameters with a non-zero known value are used instead of measured parameters (if necessary).
4. Set the measurement configuration parameters in the *MID: Config* set of variables.
5. Start the measurement by setting *MID: Command* to RUN.
6. Observe the *MID Start Result* variable for the MID measurement plan validity (see [Table 20](#)) and the actual *MID: State*, *MID: Faults* (see [Table 18](#)), and *MID: Warnings* (see [Table 19](#)) variables.
7. If the measurement finishes successfully, the measured motor parameters are shown in the *MID: Measured* set of variables and *MID: State* goes to STOP.

8.7.3 MID faults and warnings

The MID faults and warnings are saved in the format of masks in the *MID: Faults* and *MID: Warnings* variables. Faults and warnings are cleared automatically when starting a new measurement. If a MID fault appears, the measurement process immediately stops and brings the MID state machine safely to the STOP state. If a MID warning appears, the measurement process continues. Warnings report minor issues during the measurement process. For more details on individual faults and warnings, see [Table 18](#) and [Table 19](#).

Table 18. Measurement faults

Fault mask	Fault description	Fault reason	Troubleshooting
b#0001	Electrical parameters measurement fault	Some required value cannot be reached or wrong measurement configuration	Check whether measurement configuration is valid
b#0010	Mechanical measurement timeout	Some part of the mechanical measurement (acceleration, deceleration) took too long and exceeded 10 seconds	Raise the MID: Config Mech Iq Accelerate or lower the MID: Config Mech Iq Decelerate

Table 19. Measurement warnings

Warning mask	Warning description	Warning reason	Troubleshooting
b#0001	K_e is out of range	The measured K_e is negative	Visually check whether the motor was spinning properly during the K_e measurement

The MID measurement plan is checked after starting the measurement process. If a necessary parameter is not scheduled for the measurement and not set manually, the MID is not started and an error is reported via the *MID: Start Result* variable.

Table 20. MID Start Result variable

MID Start Result mask	Description	Troubleshooting
b#00 0001	Error during initialization electrical parameters measurement	Check whether inputs to the <code>MCAA_EstimRLInit_FLT</code> are valid
b#00 0010	The R_s value is missing	Schedule electrical measurement or enter R_s value manually
b#00 0100	The L_d value is missing	Schedule electrical measurement or enter L_d value manually
b#00 1000	The L_q value is missing	Schedule electrical measurement or enter L_q value manually
b#01 0000	The K_e value is missing	Schedule K_e for measurement or enter its value manually
b#10 0000	The Pp value is missing	Enter the Pp value manually

8.8 MID algorithms

This section describes how each MID algorithm works.

8.8.1 Stator resistance measurement

The stator resistance R_s is averaged from the DC steps generated by the algorithm. The DC step levels are automatically derived from the currents inserted by the user. For more details, refer to the documentation of `AMCLIB_EstimRL` function from [AMMCLib](#).

8.8.2 Stator inductances measurement

Injection of the AC-DC currents is used for the inductances (L_d and L_q) estimation. Injected AC-DC currents are automatically derived from the currents inserted by the user. The default AC current frequency is 500 Hz. For more detail, refer to the documentation of `AMCLIB_EstimRL` function from [AMMCLib](#).

8.8.3 BEMF constant measurement

Before the actual BEMF constant K_e measurement, the BEMF and Tracking observers parameters are recalculated from the previously measured or manually set R_s , L_d , and L_q parameters. To measure K_e , the motor must spin. During the measurement, the motor is open-loop driven at the user-defined frequency `MID: Config Ke Freq El. Required` with the user-defined current `MID: Config Ke Id Required` value. When the motor reaches the required speed, the BEMF voltages obtained by the BEMF observer are filtered and K_e is calculated:

$$K_e = \frac{U_{BEMF}}{\omega_{el}} \left[\Omega \right] \tag{5}$$

When K_e is being measured, you must visually check whether the motor is spinning properly. If the motor is not spinning properly, perform the steps below:

- Ensure that the number of pp is correct. The required speed for the K_e measurement is also calculated from pp . Therefore, inaccuracy in pp causes inaccuracy in the resulting K_e .
- Increase `MID: Config Ke Id Required` variable to produce higher torque when spinning during the open loop.
- Decrease `MID: Config Ke Freq El. Required` variable to decrease the required speed for the K_e measurement.

8.8.4 Number of pole-pair assistant

The number of pole-pairs can only be measured with a position sensor. However, there is a simple assistant to determine the number of pole-pairs (`PP_ASSIST`). The number of the pp assistant performs one electrical revolution, stops for a few seconds, and then repeats. Because the pp value is the ratio between the electrical and mechanical speeds, it can be determined as the number of stops per one mechanical revolution. It is recommended to refrain from counting the stops during the first mechanical revolution because the alignment occurs during the first revolution and affects the number of stops. During the `PP_ASSIST` measurement, the current loop is enabled, and the I_d current is controlled to *MID: Config Pp Id Meas*. The electrical position is generated by integrating the open-loop frequency *MID: Config Pp Freq El. Required*. If the rotor does not move after the start of `PP_ASSIST` assistant, stop the assistant, increase *MID: Config Pp Id Meas*, and restart the assistant.

8.8.5 Mechanical parameters measurement

The moment of inertia J and the viscous friction B can be identified using a test with the known generated torque T and the loading torque T_{load} .

$$\frac{d\omega_m}{dt} = \frac{1}{J} (T - T_{load} - B\omega_m) \left[\text{rad} / \text{s}^2 \right] \quad (6)$$

The ω_m character in the equation is the mechanical speed. The mechanical parameter identification software uses the torque profile. The loading torque is (for simplicity reasons) said to be 0 during the whole measurement. Only the friction and the motor-generated torque are considered. During the measurement phase, the constant torque T_{meas} is applied and the motor accelerates to 50 % of its nominal speed in time t_1 . These integrals are calculated during the period from t_0 (the speed estimation is accurate enough) to t_1 :

$$T_{int} = \int_{t_0}^{t_1} T dt \left[\text{Nms} \right] \quad (7)$$

$$\omega_{int} = \int_{t_0}^{t_1} \omega_m dt \left[\text{rad} / \text{s} \right] \quad (8)$$

During the second phase, the rotor decelerates freely with no generated torque, only by friction. This enables you to measure the mechanical time constant $\tau_m = J/B$ as the time the rotor decelerates from its original value by 63 %.

The final mechanical parameter estimation can be calculated by integrating:

$$\omega_m(t_1) = \frac{1}{J} T_{int} - \frac{B}{J} \omega_{int} + \omega_m(t_0) \left[\text{rad} / \text{s} \right] \quad (9)$$

The moment of inertia is:

$$J = \frac{\tau_m T_{int}}{\tau_m [\omega_m(t_1) - \omega_m(t_0)] + \omega_{int}} \left[\text{kgm}^2 \right] \quad (10)$$

The viscous friction is then derived from the relation between the mechanical time constant and the moment of inertia. To use the mechanical parameters measurement, the current control loop bandwidth $f_{0,Current}$, the speed control loop bandwidth $f_{0,Speed}$, and the mechanical parameters measurement torque Trq_m must be set.

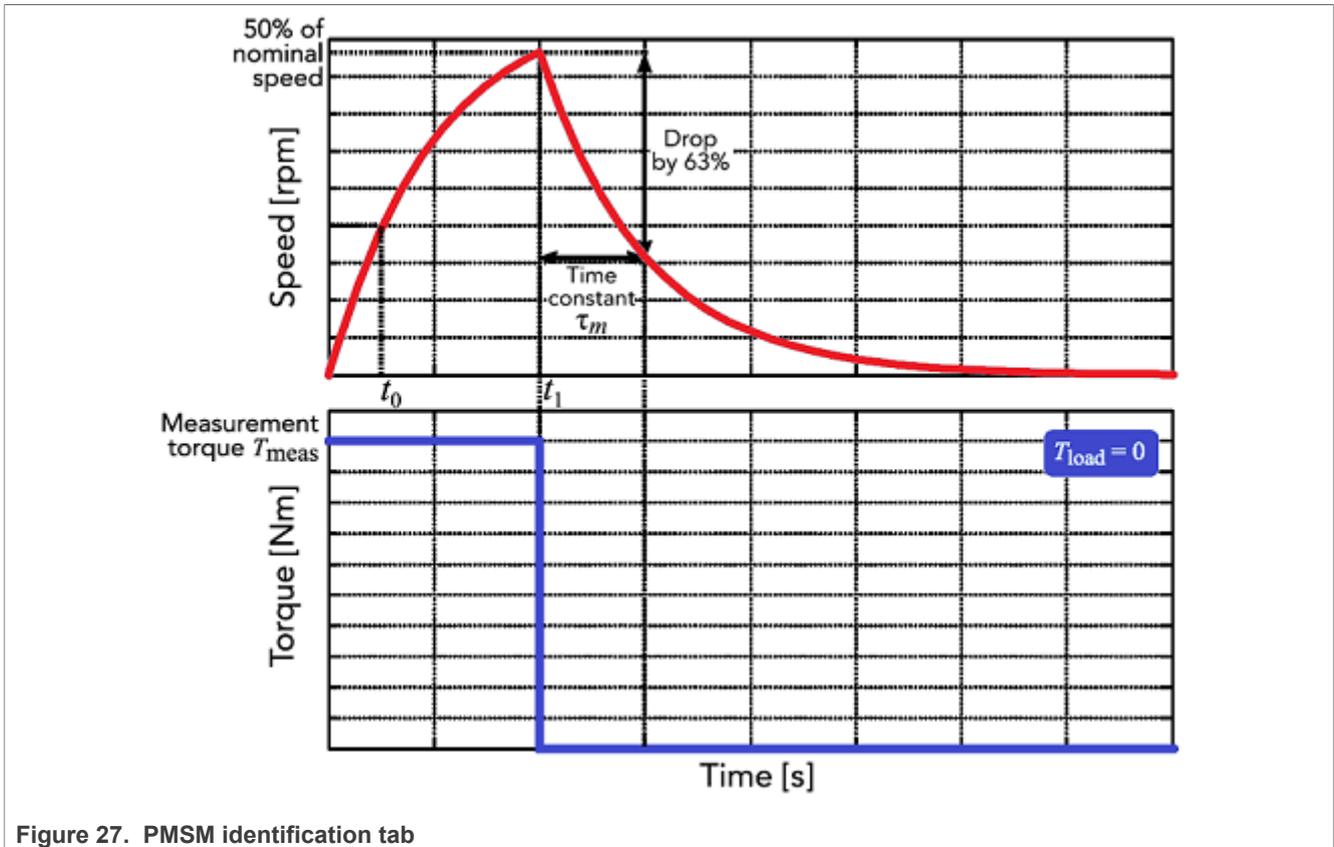


Figure 27. PMSM identification tab

8.9 Electrical parameters measurement control

This section describes how to control electrical parameters measurement, which contains measuring stator resistance R_s , direct inductance L_d , and quadrature inductance L_q . There are available 4 modes of measurement which MID: Config El Mode Estim RL variable can select.

Function `MCAA_EstimRLInit_FLT` must be called before the first use of `MCAA_EstimRL_FLT`. Function `MCAA_EstimRL_FLT` must be called periodically with sampling period `F_SAMPLING`, which can be defined by the user. Maximum sampling frequency `F_SAMPLING` is 10 kHz. In the scopes under "Motor identification", FreeMASTER subblock can be observed in measured currents, estimated parameters, and so on.

8.9.1 Mode 0

This mode is automatic. Inductances are measured at a single operating point. The rotor is not fixed. The user has to specify nominal current (MID: Config El I DC nominal variable). The AC and DC currents are automatically derived from the nominal current. The frequency of the AC signal is set to 500 Hz.

The function outputs stator resistance R_s , direct inductance L_d , and quadrature inductance L_q .

8.9.2 Mode 1

DC stepping is automatic in this mode. The rotor is not fixed. Compared to the Mode 0, an automatic measurement of the inductances for a defined number (`NUM_MEAS`) of different DC current levels is performed using positive values of the DC current. The L_{dq} dependency map can be seen in the "Inductances (Ld, Lq)" recorder. The user has to specify the following parameters before parameters estimation:

- MID: Config El I DC (estim Lq) - Current to determine L_q . In most cases, nominal current.

- *MID: Config EI I DC positive max* - Maximum positive DC current for the L_{dq} dependency map measurement.

Injected AC and DC currents are automatically derived from the *MID: Config EI I DC (estim Lq)* and *MID: Config EI I DC positive max* currents. The frequency of the AC signal is set to 500 Hz.

The function outputs stator resistance R_s , direct inductance L_d , quadrature inductance L_q , and L_{dq} dependency map.

8.9.3 Mode 2

DC stepping is automatic in this mode. The rotor must be mechanically fixed after initial alignment with the first phase. Compared to the Mode 1, an automatic measurement of the inductances for a defined number (*NUM_MEAS*) of different DC current levels is performed using both positive and negative values of the DC current. The estimated inductances can be seen in the "Inductances (Ld, Lq)" recorder. The user has to specify following parameters before parameters estimation:

- *MID: Config EI I DC (estim Ld)* - Current to determine L_d . In most cases, 0 A.
- *MID: Config EI I DC (estim Lq)* - Current to determine L_q . In most cases, nominal current.
- *MID: Config EI I DC positive max* - Maximum positive DC current for the L_{dq} dependency map measurement. In most cases, nominal current.
- *MID: Config EI I DC negative max* - Maximum negative DC current for the L_{dq} dependency map measurement.

Injected AC and DC currents are automatically derived from the *MID: Config EI I DC (estim Ld)*, *MID: Config EI I DC (estim Lq)*, *MID: Config EI I DC positive max*, and *MID: Config EI I DC negative max* currents. The frequency of the AC signal is set to 500 Hz.

The function outputs stator resistance R_s , direct inductance L_d , quadrature inductance L_q , and L_{dq} dependency map.

8.9.4 Mode 3

This mode is manual. The rotor must be mechanically fixed after alignment with the first phase. R_s is not calculated at this mode. The estimated inductances can be observed in the "Ld" or "Lq" scopes. The following parameters can be changed during the runtime:

- *MID: Config EI DQ-switch* - Axis switch for AC signal injection (0 for injection AC signal to d-axis, 1 for injection AC signal to q-axis).
- *MID: Config EI I DC req (d-axis)* - Required DC current in d-axis.
- *MID: Config EI I DC req (q-axis)* - Required DC current in q-axis.
- *MID: Config EI I AC req* - Required AC current injected to the d-axis or q-axis.
- *MID: Config EI I AC frequency* - Required frequency of the AC current injected to the d-axis or q-axis.

8.10 Control parameters tuning

To check correct current measuring and proper working of back EMF observer, follow the steps below:

1. Select the scalar control in the "M1 MCAT Control" FreeMASTER variable watch.
2. Set the "M1 Application Switch" variable to "ON". The application state changes to "RUN".
3. Set the required frequency value in the "M1 Scalar Freq Required" variable; for example, 15 Hz in the "Scalar & Voltage Control" FreeMASTER project tree. The motor starts running.
4. Select the "Phase Currents" recorder from the "Scalar & Voltage Control" FreeMASTER project tree.
5. The optimal ratio for the V/Hz profile can be found by changing the V/Hz factor directly using MCAT input "Scalar V/Hz factor ratio". The shape of the motor currents should be close to a sinusoidal shape ([Figure 28](#)).

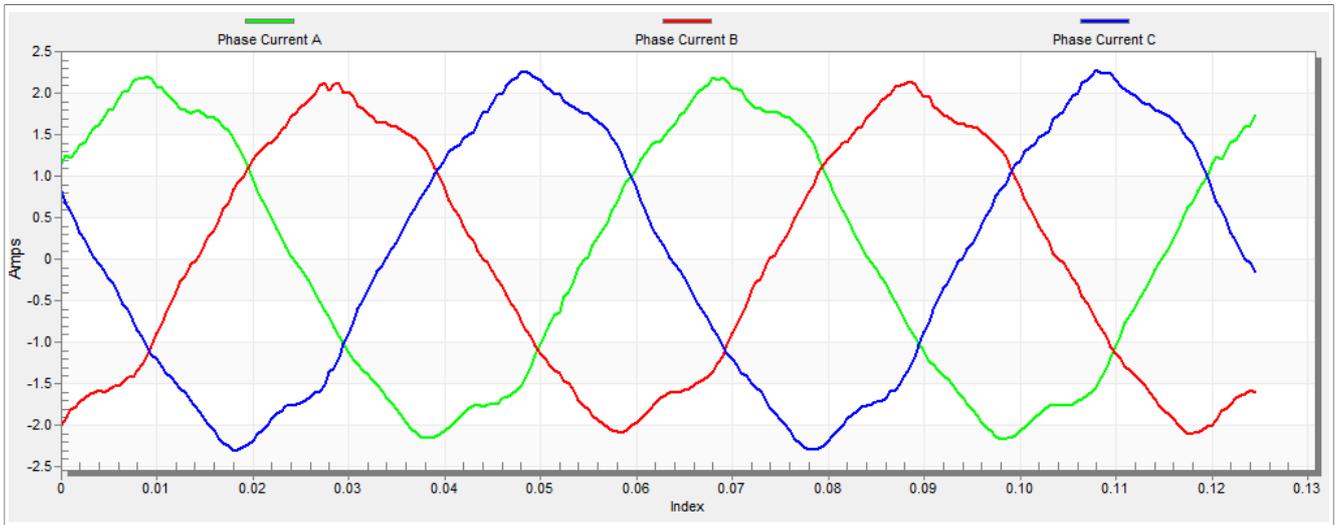


Figure 28. Phase currents

6. Select the "Position" recorder to check the observer functionality. The difference between the "Position Electrical Scalar" and the "Position Estimated" should be minimal (see Figure 29) for the Back-EMF position and speed observer to work properly. The position difference depends on the motor load. The higher the load, the bigger the difference between the positions due to the load angle.

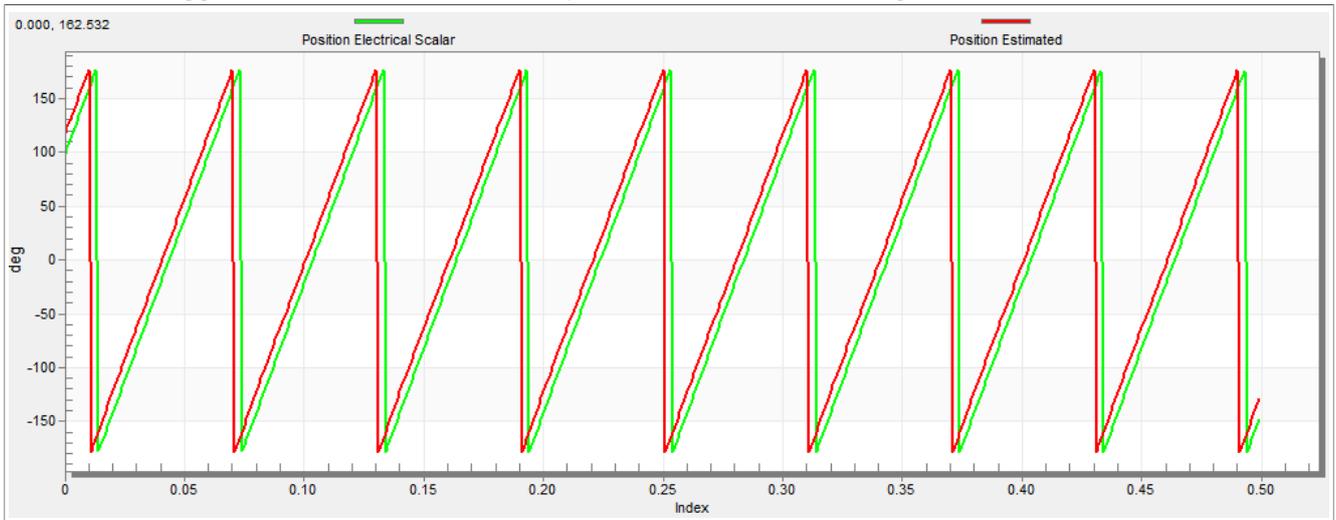


Figure 29. Generated and estimated positions

7. If an opposite speed direction is required, set a negative speed value into the "M1 Scalar Freq Required" variable.
8. The proper observer functionality and the measurement of analog quantities is expected at this step.
9. Enable the voltage FOC mode in the "M1 MCAT Control" variable while the main application switch "M1 Application Switch" is turned off.
10. Switch on the main application switch on and set a non-zero value in the "M1 MCAT Uq Required" variable. The FOC algorithm uses the estimated position to run the motor.

8.10.1 Encoder sensor setting

The encoder sensor settings are in the "Sensors" tab. The encoder sensor enables you to compute speed and position for the sensed speed. For a proper encoder counting, set the number of encoder pulses per one revolution and the proper counting direction. The number of encoder pulses is based on information about the

encoder from its manufacturer. If the encoder sensor has more pulses per revolution, the speed and position computing is more accurate. The counting direction is provided by connecting the encoder signals to the NXP Freedom board and also by connecting the motor phases.

To determine the direction of rotation, follow the steps below:

1. Navigate to the "Scalar & Voltage Control" tab in the project tree and select "SCALAR_CONTROL" in the "M1 MCAT Control" variable.
2. Turn on the application switch. The application state changes to "RUN".
3. Set the required frequency value in the "M1 Scalar Freq Required" variable; for example, 15 Hz. The motor starts running.
4. Check the encoder direction. Select the "Encoder Direction Scope" from the "Scalar & Voltage Control" project tree. If the encoder direction is right, the estimated speed is equal to the measured mechanical speed. If the measured mechanical speed is opposite to the estimated speed, the direction must be changed. The first way is to change "M1 Encoder Direction" variable - only 0 or 1 value is allowed. The second way is invert the encoder wires—phase A and phase B (or the other way round).

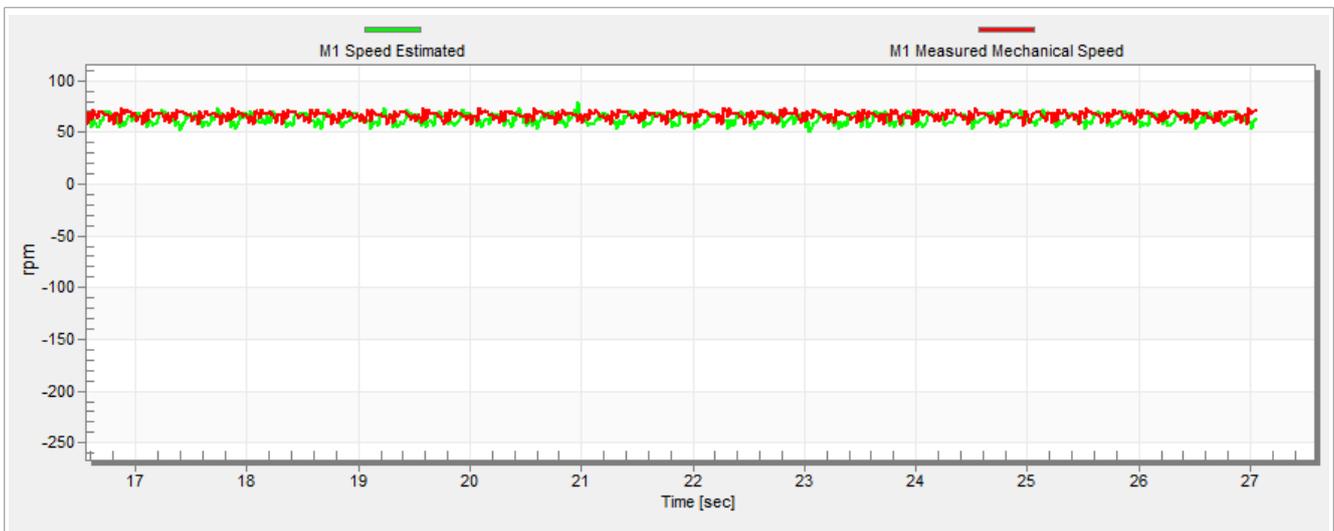


Figure 30. Encoder direction—right direction

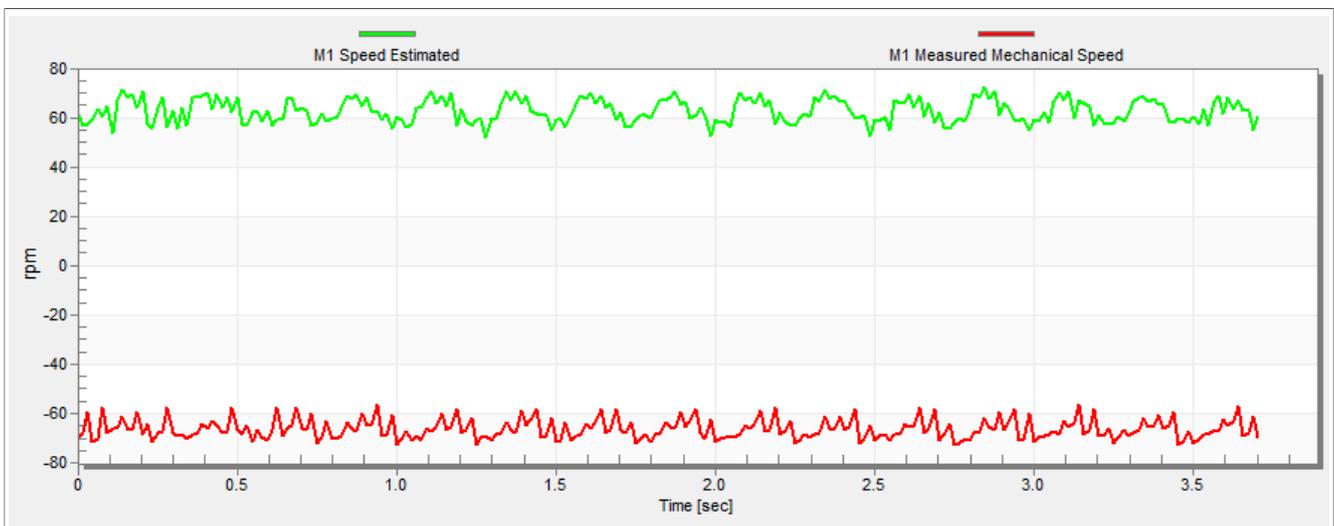


Figure 31. Encoder direction—wrong direction

8.10.2 Alignment tuning

For the alignment parameters, navigate to the "Parameters" MCAT tab. The alignment procedure sets the rotor to an accurate initial position and enables you to apply full startup torque to the motor. A correct initial position is needed mainly for high startup loads (compressors, washers, and so on). The alignment aims to have the rotor in a stable position, without any oscillations before the startup.

- The alignment voltage is the value applied to the d-axis during the alignment. Increase this value for a higher shaft load.
- The alignment duration expresses the time when the alignment routine is called. Tune this parameter to eliminate rotor oscillations or movement at the end of the alignment process.

8.10.3 Current loop tuning

The parameters for the current D, Q, and PI controllers are fully calculated using the motor parameters and no action is required in this mode. If the calculated loop parameters do not correspond to the required response, the bandwidth and attenuation parameters can be tuned.

1. Select "Openloop Control" in the FreeMASTER project tree, set "M1 MCAT Control" to "OPENLOOP_CTRL" and switch "M1 Openloop Use I Control" on.
2. Turn the application on by switching "M1 Application Switch" on and then set "M1 Openloop Required Id" for rotor alignment. (Rotor alignment always uses Id, even when you are tuning the Q axis regulator)
3. Mechanically lock the motor shaft and turn the application off.
4. Set the required loop bandwidth and attenuation in MCAT "Current loop" tab and then click the "Update target" button. The tuning loop bandwidth parameter defines how fast the loop response is while the tuning loop attenuation parameter defines the actual overshoot magnitude.
5. Select "Current Controller Id" recorder in project tree, turn the application on and set the required step amplitude in "M1 Openloop Required Id". Observe the step response in the recorder.
6. Tune the loop bandwidth and attenuation until you achieve the required response. The example waveforms show the correct and incorrect settings of the current loop parameters:
 - The loop bandwidth is low (100 Hz) and the settling time of the Id current is long (Figure 32).

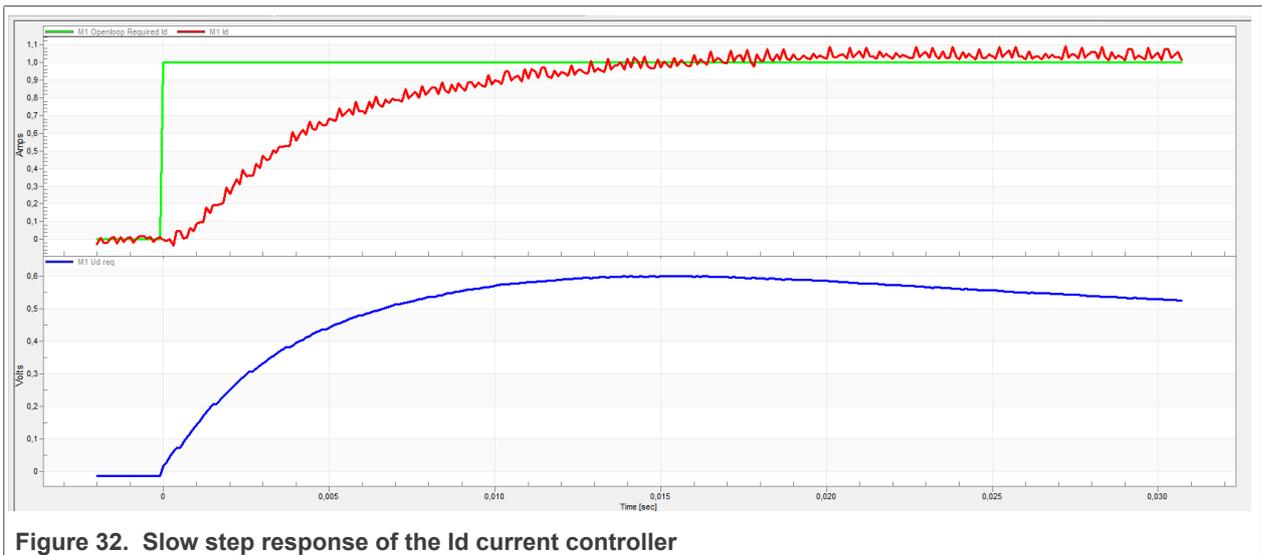


Figure 32. Slow step response of the Id current controller

- The loop bandwidth (300 Hz) is optimal and the response time of the Id current is sufficient (Figure 33).

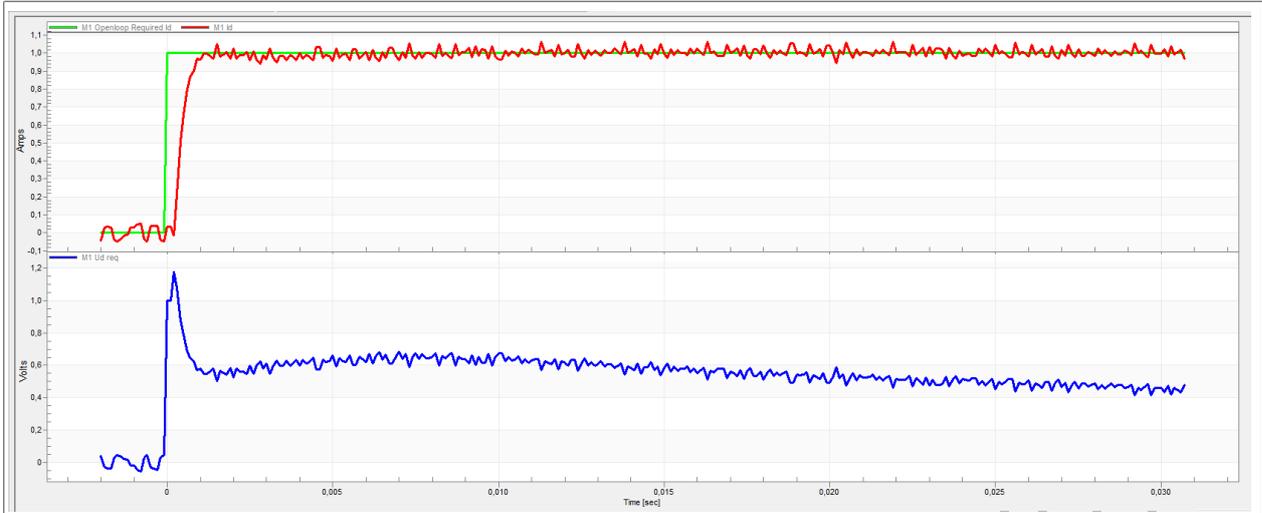


Figure 33. Optimal step response of the Id current controller

- The loop bandwidth is high (700 Hz) and the response time of the Id current is very fast, but with oscillations and overshoot (Figure 34).

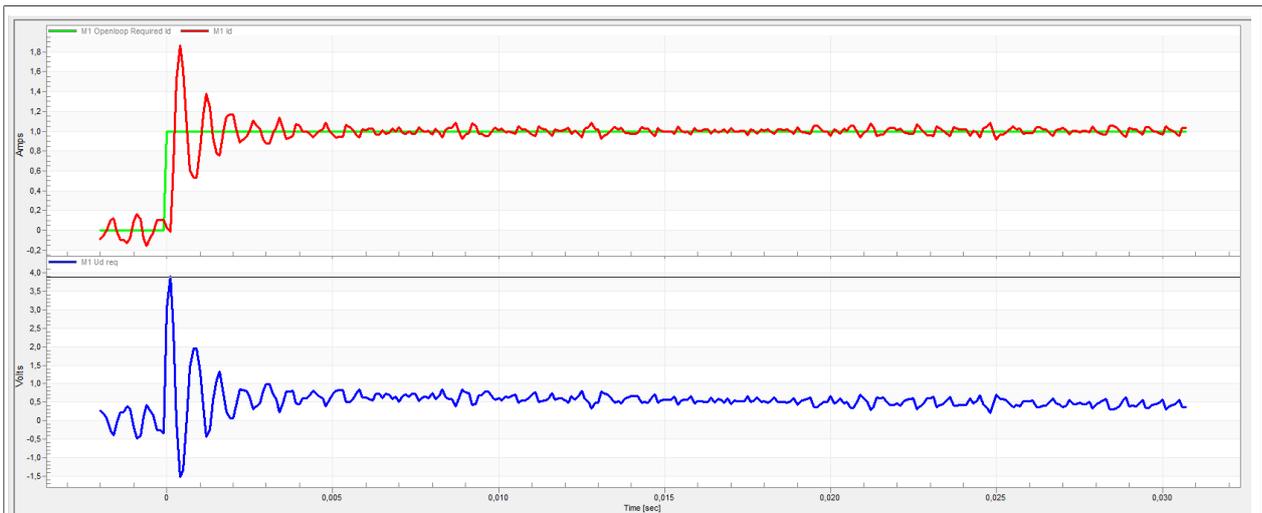


Figure 34. Fast step response of the Id current controller

8.10.4 Speed ramp tuning

To tune speed ramp parameters, follow the steps below:

1. The speed command is applied to the speed controller through a speed ramp. The ramp function contains two increments (up and down) which express the motor acceleration and deceleration per second. If the increments are very high, they can cause an overcurrent fault during acceleration and an overvoltage fault during deceleration. In the "Speed" scope, you can see whether the "Speed Actual Filtered" waveform shape equals the "Speed Ramp" profile.
2. The increments are common for the scalar and speed control. The increment fields are in the "Speed loop" tab and accessible in both tuning modes. Clicking the "Update target" button applies the changes to the MCU. An example speed profile is shown in Figure 35. The ramp increment down is set to 500 rpm/sec and the increment up is set to 3000 rpm/sec.
3. The startup ramp increment is in the "Sensorless" tab and its value is higher than the speed loop ramp.

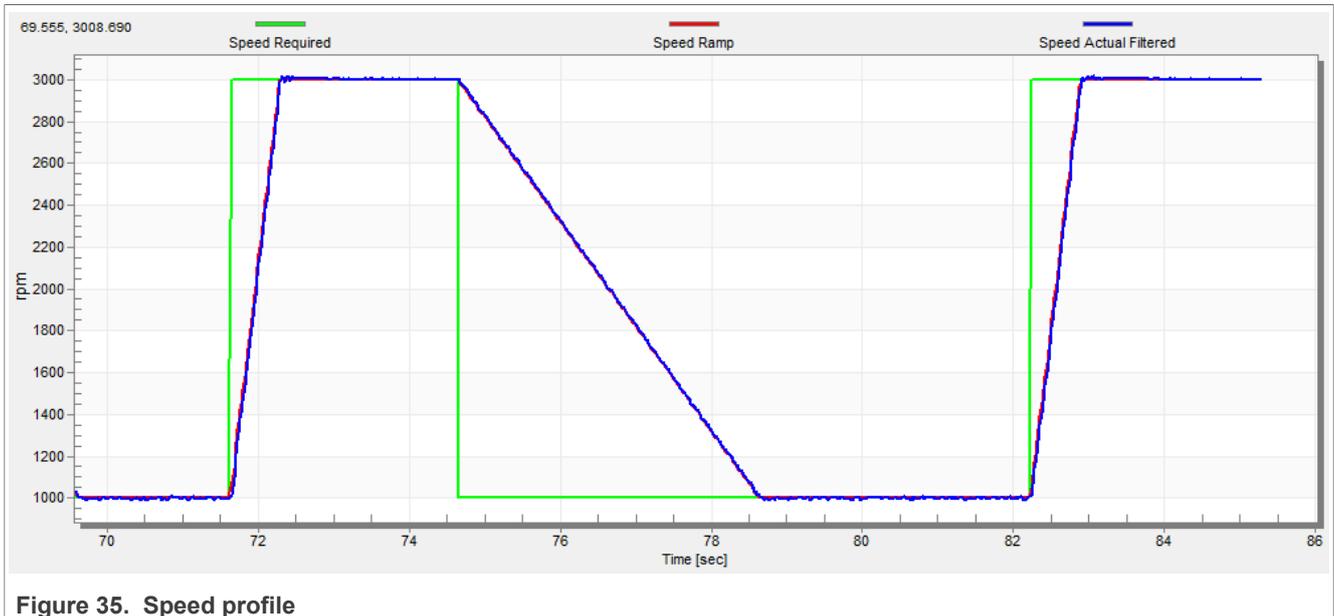


Figure 35. Speed profile

8.10.5 Open loop startup

To tune open loop startup parameters, follow the steps below:

1. The startup process can be tuned by a set of parameters located in the "Sensorless" tab. Two of them (ramp increment and current) are accessible in both tuning modes. The startup tuning can be processed in all control modes besides the scalar control. Setting the optimal values results in a proper motor startup. An example startup state of low-dynamic drives (fans, pumps) is shown in [Figure 36](#).
2. Select the "Startup" recorder from the FreeMASTER project tree.
3. Set the startup ramp increment typically to a higher value than the speed-loop ramp increment.
4. Set the startup current according to the required startup torque. For drives such as fans or pumps, the startup torque is not very high and can be set to 15 % of the nominal current.
5. Set the required merging speed. When the open-loop and estimated position merging starts, the threshold is mostly set in the range of 5 % ~ 10 % of the nominal speed.
6. Set the merging coefficient—in the position merging process duration, 100 % corresponds to a one of an electrical revolution. The higher the value, the faster the merge. Values close to 1 % are set for the drives where a high startup torque and smooth transitions between the open loop and the closed loop are required.
7. To apply the changes to the MCU, click the "Update Target" button.
8. Select "SPEED_FOC" in the "M1 MCAT Control" variable.
9. Set the required speed higher than the merging speed.
10. Check the startup response in the recorder.
11. Tune the startup parameters until you achieve an optimal response.
12. If the rotor does not start running, increase the startup current.
13. If the merging process fails (the rotor is stuck or stopped), decrease the startup ramp increment, increase the merging speed, and set the merging coefficient to 5 %.

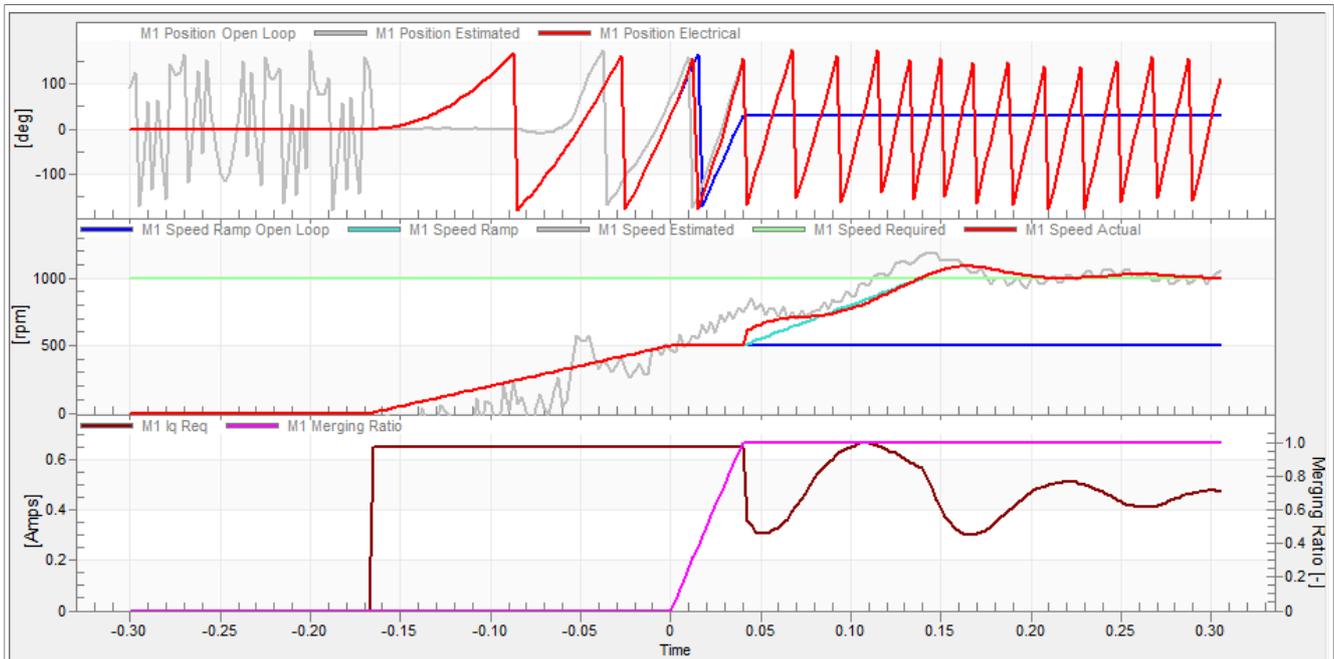


Figure 36. Motor startup

8.10.6 BEMF observer tuning

The bandwidth and attenuation parameters of the BEMF and tracking observer can be tuned. To tune the bandwidth and attenuation parameters, follow the steps below:

1. Navigate to the "Sensorless" MCAT tab.
2. Set the required bandwidth and attenuation of the BEMF observer. The bandwidth is typically set to a value close to the current loop bandwidth.
3. Set the required bandwidth and attenuation of the tracking observer. The bandwidth is typically set in the range of 10 – 20 Hz for most low-dynamic drives (fans, pumps).
4. To apply the changes to the MCU, click the "Update target" button.
5. Select the "Observer" recorder from the FreeMASTER project tree and check the observer response in the "Observer" recorder.

8.10.7 Speed PI controller tuning

The motor speed control loop is a first-order function with a mechanical time constant that depends on the motor inertia and friction. If the mechanical constant is available, the PI controller constants can be tuned using the loop bandwidth and attenuation. Otherwise, the manual tuning of the P and I portions of the speed controllers is available to obtain the required speed response (see [Figure 37](#)). There are dozens of approaches to tune the PI controller constants. To set and tune the speed PI controller for a PM synchronous motor, follow the steps below:

1. Select the "Speed Controller" option from the FreeMASTER project tree.
2. Select the "Speed loop" tab.
3. Check the "Manual Constant Tuning" option—that is, the "Bandwidth" and "Attenuation" fields are disabled and the "SL_Kp" and "SL_Ki" fields are enabled.
4. Tune the proportional gain:
 - Set the "SL_Ki" integral gain to 0.
 - Set the speed ramp to 1000 rpm/sec (or higher).

- Run the motor at a convenient speed (about 30 % of the nominal speed).
- Set a step in the required speed to 40 % of N_{nom} .
- Adjust the proportional gain "SL_Kp" until the system responds to the required value properly and without any oscillations or excessive overshoot:
 - If the "SL_Kp" field is set low, the system response is slow.
 - If the "SL_Kp" field is set high, the system response is tighter.
 - When the "SL_Ki" field is 0, the system most probably does not achieve the required speed.
 - To apply the changes to the MCU, click the "Update Target" button.
- 5. Tune the integral gain:
 - Increase the "SL_Ki" field slowly to minimize the difference between the required and actual speeds to 0.
 - Adjust the "SL_Ki" field such that you do not see any oscillation or large overshoot of the actual speed value while the required speed step is applied.
 - To apply the changes to the MCU, click the "Update target" button.
- 6. Tune the loop bandwidth and attenuation until the required response is received. The example waveforms with the correct and incorrect settings of the speed loop parameters are shown in the following figures:
 - The "SL_Ki" value is low and the "Speed Actual Filtered" does not achieve the "Speed Ramp".

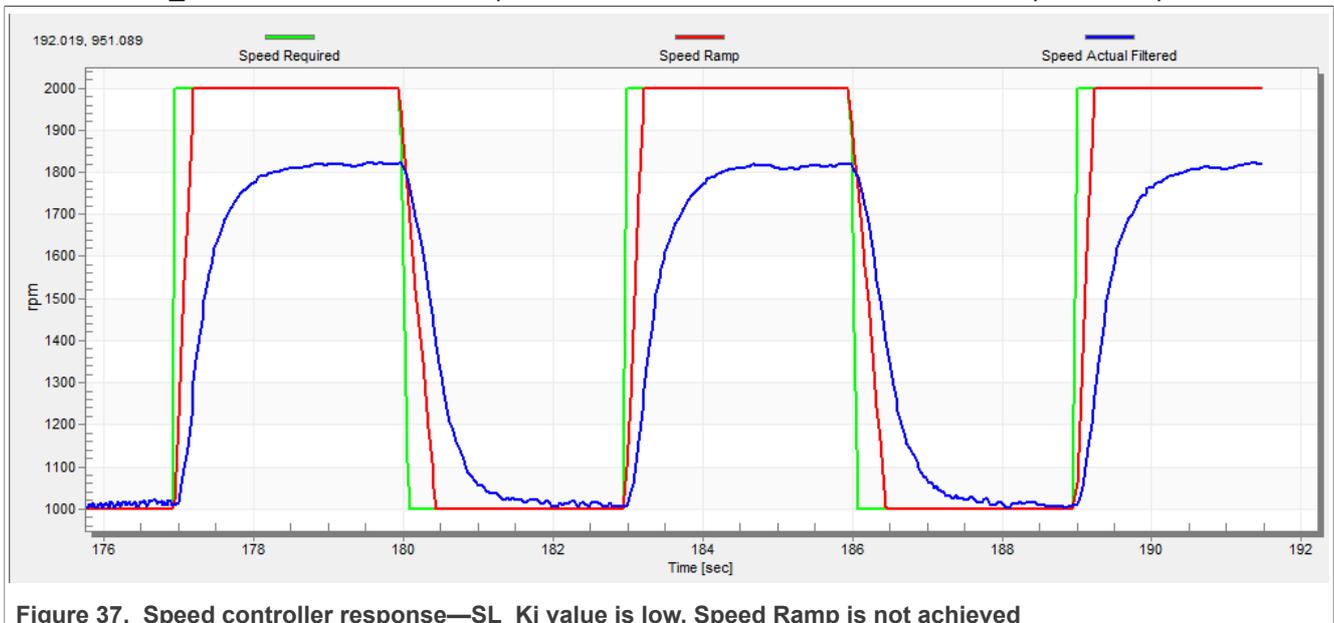


Figure 37. Speed controller response—SL_Ki value is low, Speed Ramp is not achieved

- The "SL_Kp" value is low, the "Speed Actual Filtered" greatly overshoots, and the long settling time is unwanted.

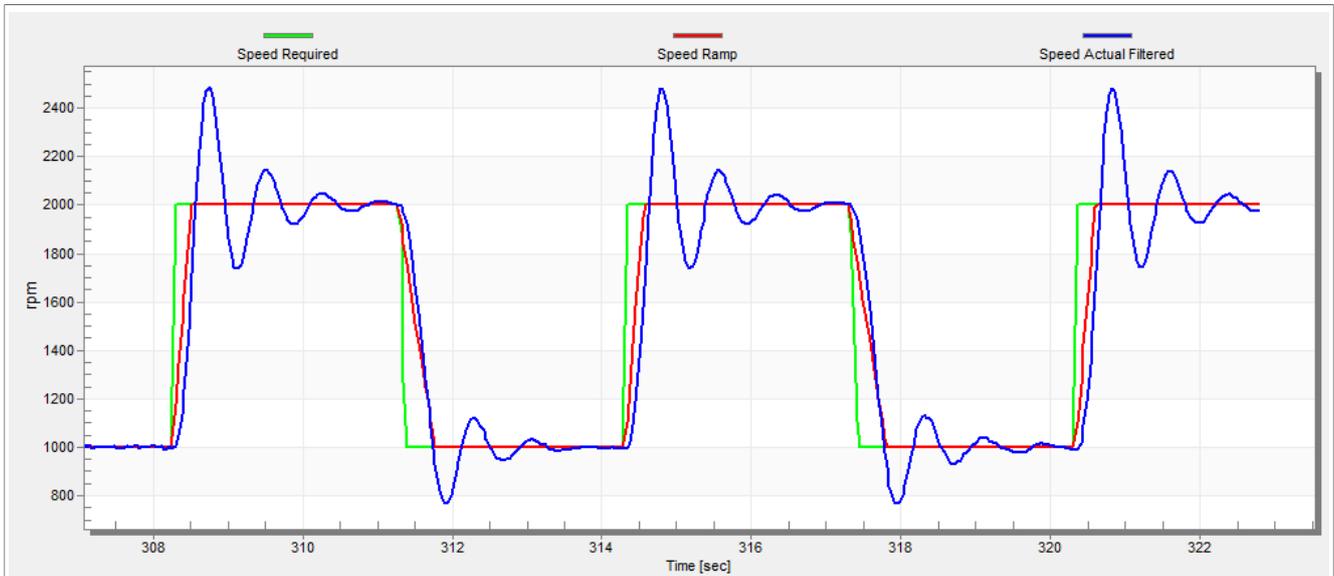


Figure 38. Speed controller response—SL_Kp value is low, Speed Actual Filtered greatly overshoots

- The speed loop response has a small overshoot and the "Speed Actual Filtered" settling time is sufficient. Such response can be considered optimal.

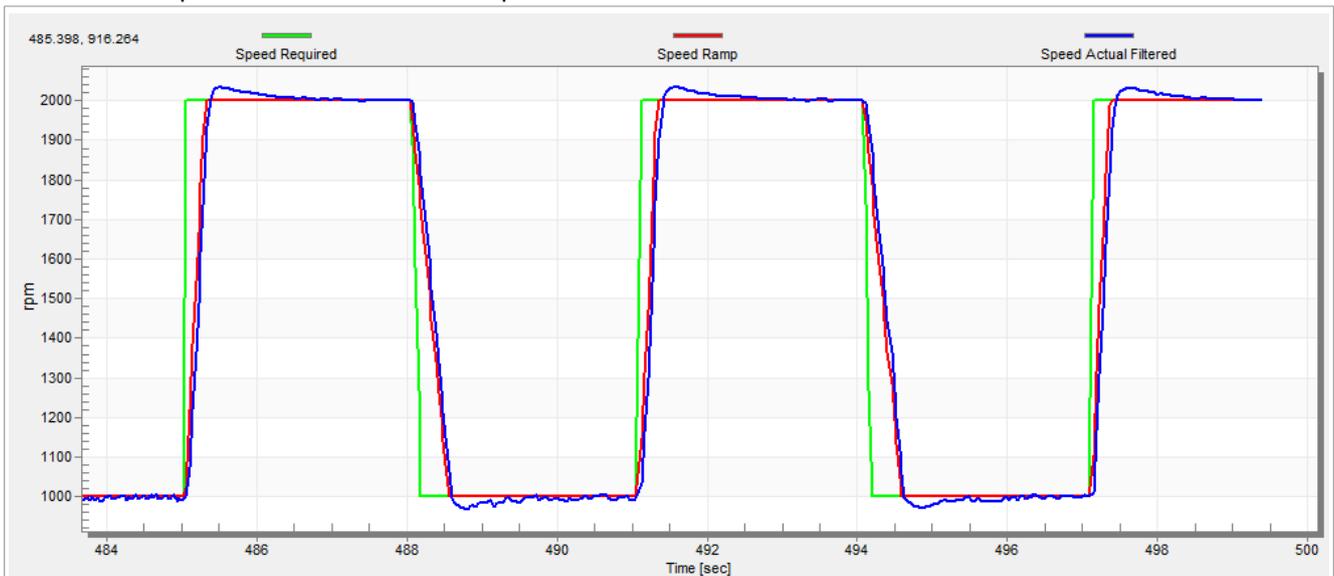


Figure 39. Speed controller response—speed loop response with a small overshoot

8.10.8 Position P controller tuning

The position control loop can be tuned Bandwidth F0 and Attenuation ξ in Servo control tab. A proportional controller can be used to unpretend the position-control systems. The key for the optimal position response is a proper value of the controller, which multiplies the error by the proportional gain (K_p) to get the controller output. An encoder sensor must be used for a working position control. The following steps provide an example of how to set the position P controller for a PM synchronous motor:

MCUXpresso SDK Field-Oriented Control of 3-Phase PMSM and BLDC Motors (MIMXRT1180-EVK)

1. Select the "Position Controller" scope in "Position Control" tab in the FreeMASTER project tree.
2. Tune the proportional gain by Bandwidth F0 and Attenuation ξ :
 - Set preferred value of Bandwidth F0 and Attenuation ξ . The MCAT automatically compute position controller gain and feed forward constants.
 - Select the position control, and set the required position in "M1 Position Required" variable (for example; 10 revolutions).
 - Select the "Position Controller" scope and watch the actual position response.
3. Repeat the previous steps until you achieve the required position response.

The "PL_Kp" value is low and the actual position response on the required position is very slow.

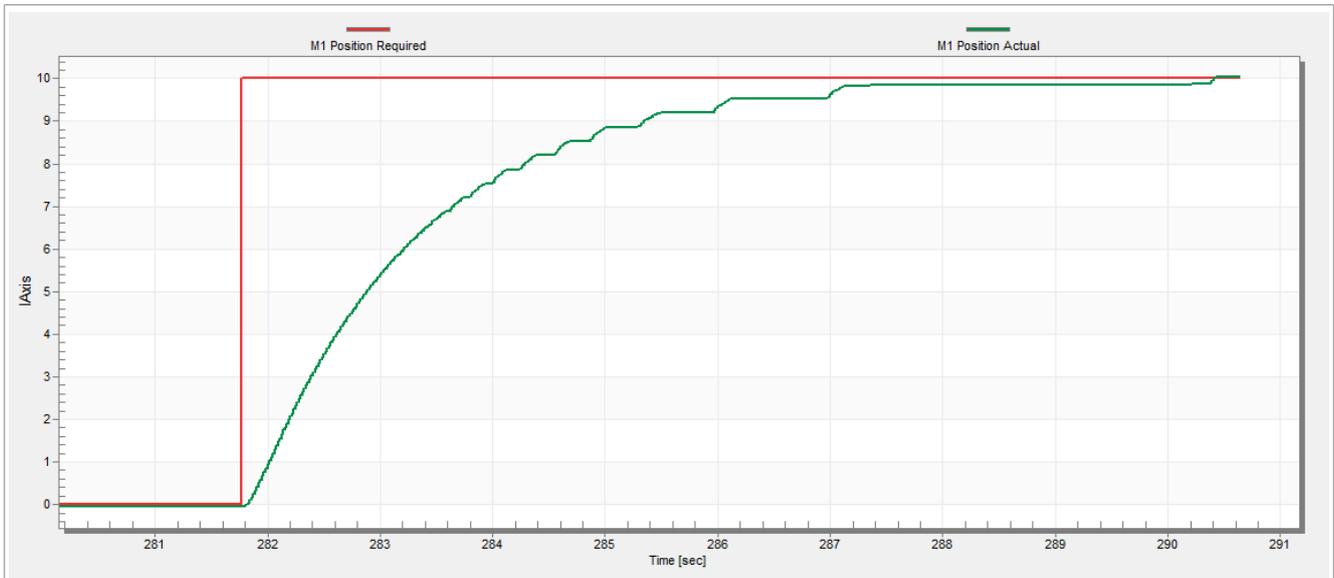


Figure 40. Position controller response—PL_Kp value is low, the actual position response is very slow

The "PL_Kp" value is too high and the actual position overshoots the required position.

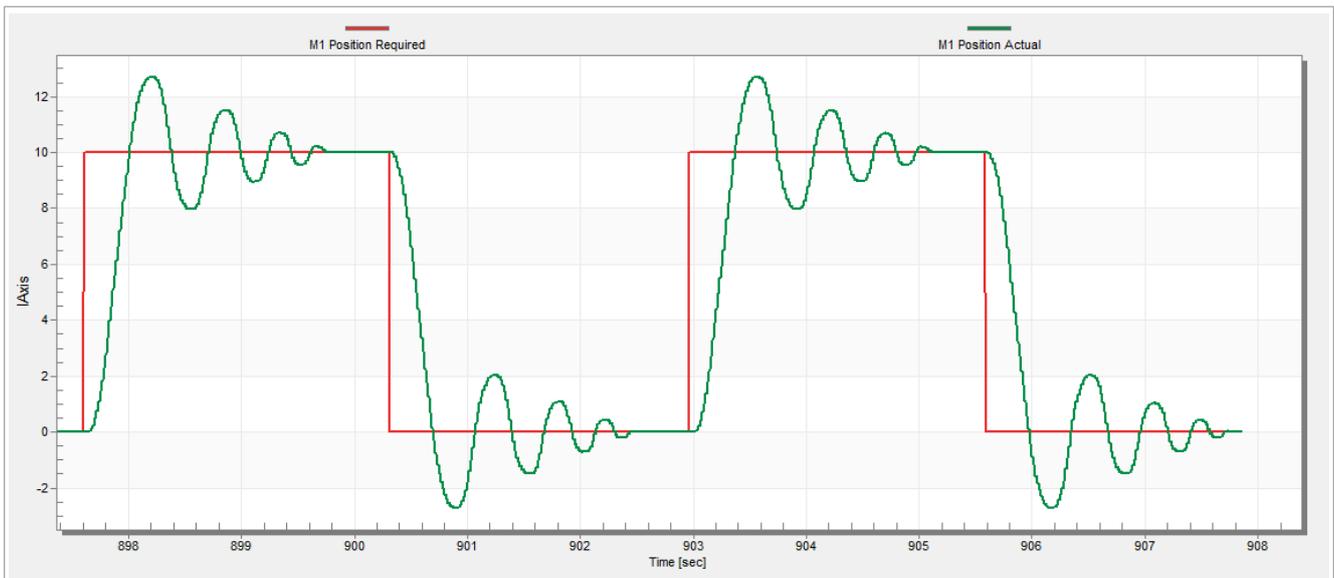


Figure 41. Position controller response—PL_Kp value is too high and the actual position overshoots

The "PL_Kp" value and the actual position response are optimal.

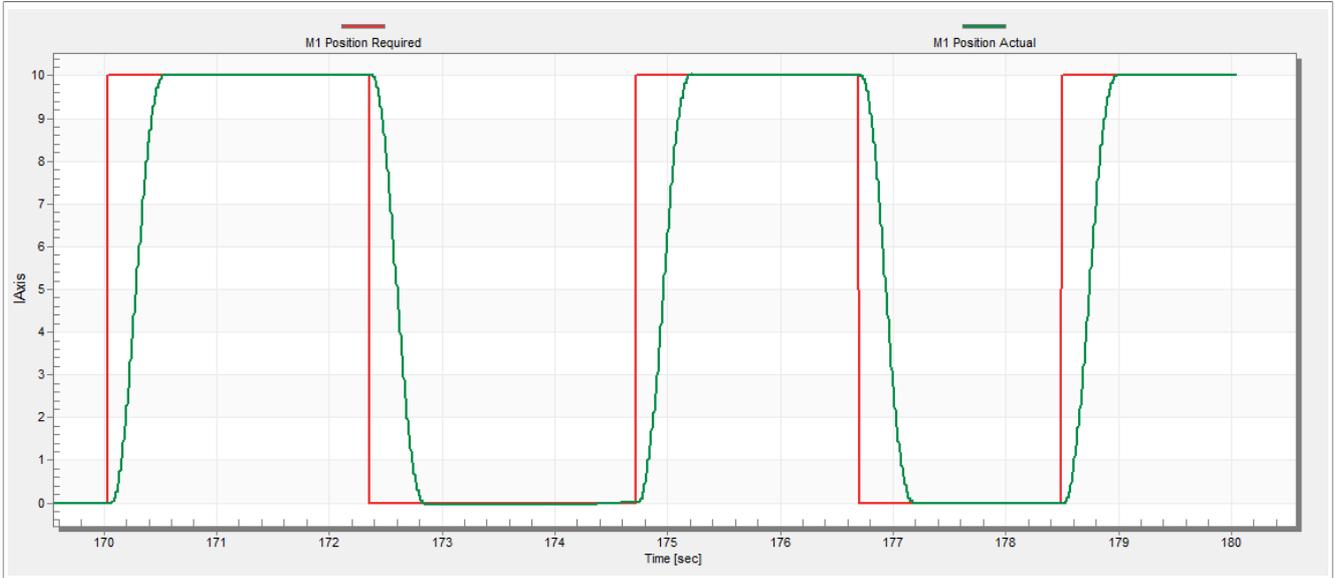


Figure 42. Position controller response—the actual position response is good

9 Conclusion

This application note describes the implementation of the sensor and sensorless field-oriented control of a 3-phase PMSM. The motor control software is implemented on NXP MIMXRT1180-EVK board with the FRDM-MC-LVPMSM NXP Freedom development platform . The hardware-dependent part of the control software is described in [Section 2](#). The motor-control application timing, and the peripheral initialization are described in [Section 3](#). The motor user interface and remote control using FreeMASTER are described in [Section 7](#). The motor parameters identification theory and the identification algorithms are described in [Section 8.8](#).

10 Acronyms and abbreviations

[Table 21](#) lists the acronyms and abbreviations used in this document.

Table 21. Acronyms and abbreviations

Acronym	Meaning
ADC	Analog-to-Digital Converter
ACIM	Asynchronous Induction Motor
ADC_ETC	ADC External Trigger Control
AN	Application Note
BLDC	Brushless DC motor
CCM	Clock Controller Module
CPU	Central Processing Unit
DC	Direct Current
DRM	Design Reference Manual
ENC	Encoder
FOC	Field-Oriented Control
GPIO	General-Purpose Input/Output
LPIT	Low-power Periodic Interrupt Timer
LPUART	Low-power Universal Asynchronous Receiver/Transmitter
MCAT	Motor Control Application Tuning tool
MCDRV	Motor Control Peripheral Drivers
MCU	Microcontroller
PDB	Programmable Delay Block
PI	Proportional Integral controller
PLL	Phase-Locked Loop
PMSM	Permanent Magnet Synchronous Machine
PWM	Pulse-Width Modulation
QD	Quadrature Decoder
TMR	Quad Timer
USB	Universal Serial Bus
XBAR	Inter-Peripheral Crossbar Switch
IOPAMP	Internal operational amplifier

11 References

These references are available on www.nxp.com:

- *Sensorless PMSM Field-Oriented Control* (document [DRM148](#))
- *Motor Control Application Tuning (MCAT) Tool for 3-Phase PMSM* (document [AN4642](#))

12 Useful links

- MCUXpresso SDK for Motor Control www.nxp.com/sdkmotorcontrol
- [Motor Control Application Tuning \(MCAT\) Tool](#)
- [i.MX RT Crossover MCUs](#)
- [FRDM-MC-PMSM Freedom Development Platform](#)
- [MCUXpresso IDE - Importing MCUXpresso SDK](#)
- [MCUXpresso Config Tool](#)
- [MCUXpresso SDK Builder](#) (SDK examples in several IDEs)
- [Model-Based Design Toolbox \(MBDT\)](#)

13 Revision history

This section summarizes the changes done to the document since the initial release.

Table 22. Revision history

Document ID	Release date	Description
UG10259 v.1.0	03 July 2025	New document ID (before PMSMRT1180)

Legal information

Definitions

Draft — A draft status on a document indicates that the content is still under internal review and subject to formal approval, which may result in modifications or additions. NXP Semiconductors does not give any representations or warranties as to the accuracy or completeness of information included in a draft version of a document and shall have no liability for the consequences of use of such information.

Disclaimers

Limited warranty and liability — Information in this document is believed to be accurate and reliable. However, NXP Semiconductors does not give any representations or warranties, expressed or implied, as to the accuracy or completeness of such information and shall have no liability for the consequences of use of such information. NXP Semiconductors takes no responsibility for the content in this document if provided by an information source outside of NXP Semiconductors.

In no event shall NXP Semiconductors be liable for any indirect, incidental, punitive, special or consequential damages (including - without limitation - lost profits, lost savings, business interruption, costs related to the removal or replacement of any products or rework charges) whether or not such damages are based on tort (including negligence), warranty, breach of contract or any other legal theory.

Notwithstanding any damages that customer might incur for any reason whatsoever, NXP Semiconductors' aggregate and cumulative liability towards customer for the products described herein shall be limited in accordance with the Terms and conditions of commercial sale of NXP Semiconductors.

Right to make changes — NXP Semiconductors reserves the right to make changes to information published in this document, including without limitation specifications and product descriptions, at any time and without notice. This document supersedes and replaces all information supplied prior to the publication hereof.

Suitability for use — NXP Semiconductors products are not designed, authorized or warranted to be suitable for use in life support, life-critical or safety-critical systems or equipment, nor in applications where failure or malfunction of an NXP Semiconductors product can reasonably be expected to result in personal injury, death or severe property or environmental damage. NXP Semiconductors and its suppliers accept no liability for inclusion and/or use of NXP Semiconductors products in such equipment or applications and therefore such inclusion and/or use is at the customer's own risk.

Applications — Applications that are described herein for any of these products are for illustrative purposes only. NXP Semiconductors makes no representation or warranty that such applications will be suitable for the specified use without further testing or modification.

Customers are responsible for the design and operation of their applications and products using NXP Semiconductors products, and NXP Semiconductors accepts no liability for any assistance with applications or customer product design. It is customer's sole responsibility to determine whether the NXP Semiconductors product is suitable and fit for the customer's applications and products planned, as well as for the planned application and use of customer's third party customer(s). Customers should provide appropriate design and operating safeguards to minimize the risks associated with their applications and products.

NXP Semiconductors does not accept any liability related to any default, damage, costs or problem which is based on any weakness or default in the customer's applications or products, or the application or use by customer's third party customer(s). Customer is responsible for doing all necessary testing for the customer's applications and products using NXP Semiconductors products in order to avoid a default of the applications and the products or of the application or use by customer's third party customer(s). NXP does not accept any liability in this respect.

Terms and conditions of commercial sale — NXP Semiconductors products are sold subject to the general terms and conditions of commercial sale, as published at <https://www.nxp.com/profile/terms>, unless otherwise agreed in a valid written individual agreement. In case an individual agreement is concluded only the terms and conditions of the respective agreement shall apply. NXP Semiconductors hereby expressly objects to applying the customer's general terms and conditions with regard to the purchase of NXP Semiconductors products by customer.

Export control — This document as well as the item(s) described herein may be subject to export control regulations. Export might require a prior authorization from competent authorities.

Suitability for use in non-automotive qualified products — Unless this document expressly states that this specific NXP Semiconductors product is automotive qualified, the product is not suitable for automotive use. It is neither qualified nor tested in accordance with automotive testing or application requirements. NXP Semiconductors accepts no liability for inclusion and/or use of non-automotive qualified products in automotive equipment or applications.

In the event that customer uses the product for design-in and use in automotive applications to automotive specifications and standards, customer (a) shall use the product without NXP Semiconductors' warranty of the product for such automotive applications, use and specifications, and (b) whenever customer uses the product for automotive applications beyond NXP Semiconductors' specifications such use shall be solely at customer's own risk, and (c) customer fully indemnifies NXP Semiconductors for any liability, damages or failed product claims resulting from customer design and use of the product for automotive applications beyond NXP Semiconductors' standard warranty and NXP Semiconductors' product specifications.

HTML publications — An HTML version, if available, of this document is provided as a courtesy. Definitive information is contained in the applicable document in PDF format. If there is a discrepancy between the HTML document and the PDF document, the PDF document has priority.

Translations — A non-English (translated) version of a document, including the legal information in that document, is for reference only. The English version shall prevail in case of any discrepancy between the translated and English versions.

Security — Customer understands that all NXP products may be subject to unidentified vulnerabilities or may support established security standards or specifications with known limitations. Customer is responsible for the design and operation of its applications and products throughout their lifecycles to reduce the effect of these vulnerabilities on customer's applications and products. Customer's responsibility also extends to other open and/or proprietary technologies supported by NXP products for use in customer's applications. NXP accepts no liability for any vulnerability. Customer should regularly check security updates from NXP and follow up appropriately. Customer shall select products with security features that best meet rules, regulations, and standards of the intended application and make the ultimate design decisions regarding its products and is solely responsible for compliance with all legal, regulatory, and security related requirements concerning its products, regardless of any information or support that may be provided by NXP.

NXP has a Product Security Incident Response Team (PSIRT) (reachable at PSIRT@nxp.com) that manages the investigation, reporting, and solution release to security vulnerabilities of NXP products.

NXP B.V. — NXP B.V. is not an operating company and it does not distribute or sell products.

Trademarks

Notice: All referenced brands, product names, service names, and trademarks are the property of their respective owners.

NXP — wordmark and logo are trademarks of NXP B.V.

MCUXpresso SDK Field-Oriented Control of 3-Phase PMSM and BLDC Motors (MIMXRT1180-EVK)

AMBA, Arm, Arm7, Arm7TDMI, Arm9, Arm11, Artisan, big.LITTLE, Cordio, CoreLink, CoreSight, Cortex, DesignStart, DynamIQ, Jazelle, Keil, Mali, Mbed, Mbed Enabled, NEON, POP, RealView, SecurCore, Socrates, Thumb, TrustZone, ULINK, ULINK2, ULINK-ME, ULINK-PLUS, ULINKpro, μ Vision, Versatile — are trademarks and/or registered trademarks of Arm Limited (or its subsidiaries or affiliates) in the US and/or elsewhere. The related technology may be protected by any or all of patents, copyrights, designs and trade secrets. All rights reserved.

BISS — is a trademark of iC-Haus GmbH.

CodeWarrior — is a trademark of NXP B.V.

EdgeLock — is a trademark of NXP B.V.

EdgeVerse — is a trademark of NXP B.V.

IAR — is a trademark of IAR Systems AB.

J-Link — is a trademark of SEGGER Microcontroller GmbH.

Kinetis — is a trademark of NXP B.V.

Tower — is a trademark of NXP B.V.

Tables

Tab. 1.	Available example type, supported motors and control methods	2	Tab. 12.	Speed loop tab input	28
Tab. 2.	Linix 45ZWN24-40 motor parameters	3	Tab. 13.	Servo control tab input	30
Tab. 3.	Teknic M-2310P-LN-04K motor parameters	3	Tab. 14.	Sensorless tab input	31
Tab. 4.	Teknic M-2311P-LN-08D motor parameters	4	Tab. 15.	MCAT motor parameters	40
Tab. 5.	MIMXRT1180-EVK jumper settings	7	Tab. 16.	Fault limits	41
Tab. 6.	Add and remove resistors	8	Tab. 17.	Application scales	41
Tab. 7.	Maximum CPU load (fast loop)	12	Tab. 18.	Measurement faults	43
Tab. 8.	Memory usage	12	Tab. 19.	Measurement warnings	43
Tab. 9.	Constants used in equations	25	Tab. 20.	MID Start Result variable	44
Tab. 10.	Parameters tab inputs	25	Tab. 21.	Acronyms and abbreviations	59
Tab. 11.	Current loop tab input	28	Tab. 22.	Revision history	62

Figures

Fig. 1.	Linux 45ZWN24-40 permanent magnet synchronous motor	3	Fig. 24.	Undervoltage fault is indicated (pending)	39
Fig. 2.	Teknic permanent magnet synchronous motor	4	Fig. 25.	Undervoltage fault is captured	39
Fig. 3.	Teknic motor connector type 1	5	Fig. 26.	MID FreeMASTER control	42
Fig. 4.	Teknic motor connector type 2	5	Fig. 27.	PMSM identification tab	46
Fig. 5.	Motor-control development platform block diagram	6	Fig. 28.	Phase currents	48
Fig. 6.	FRDM-MC-LVPMSM	6	Fig. 29.	Generated and estimated positions	48
Fig. 7.	MIMXRT1180-EVK board with highlighted jumper settings	7	Fig. 30.	Encoder direction—right direction	49
Fig. 8.	Assembled Freedom system	9	Fig. 31.	Encoder direction—wrong direction	49
Fig. 9.	Hardware timing and synchronization on i.MX RT1180	10	Fig. 32.	Slow step response of the Id current controller	50
Fig. 10.	Directory tree	14	Fig. 33.	Optimal step response of the Id current controller	51
Fig. 11.	Green “GO” button placed in top left-hand corner	20	Fig. 34.	Fast step response of the Id current controller	51
Fig. 12.	FreeMASTER—communication is established successfully	20	Fig. 35.	Speed profile	52
Fig. 13.	FreeMASTER communication setup window	21	Fig. 36.	Motor startup	53
Fig. 14.	Default symbol file	22	Fig. 37.	Speed controller response—SL_Ki value is low, Speed Ramp is not achieved	54
Fig. 15.	FreeMASTER + MCAT layout	24	Fig. 38.	Speed controller response—SL_Kp value is low, Speed Actual Filtered greatly overshoots	55
Fig. 16.	Scalar control mode	32	Fig. 39.	Speed controller response—speed loop response with a small overshoot	55
Fig. 17.	Voltage - Open loop control	33	Fig. 40.	Position controller response—PL_Kp value is low, the actual position response is very slow	56
Fig. 18.	Current - Open loop control	34	Fig. 41.	Position controller response—PL_Kp value is too high and the actual position overshoots	56
Fig. 19.	Voltage FOC control mode	35	Fig. 42.	Position controller response—the actual position response is good	57
Fig. 20.	Current/Torque control mode (sensored)	36			
Fig. 21.	Speed FOC control mode (sensored)	37			
Fig. 22.	Position control mode	37			
Fig. 23.	Faults in variable watch located in "Motor M1" subblock	38			

Contents

1	Introduction	2	8.7.3	MID faults and warnings	43
2	Hardware setup	3	8.8	MID algorithms	44
2.1	Linux motor	3	8.8.1	Stator resistance measurement	44
2.2	Teknic motor	3	8.8.2	Stator inductances measurement	44
2.3	FRDM-MC-LVPMSM	5	8.8.3	BEMF constant measurement	44
2.4	i.MX RT1180 Evaluation Kit	6	8.8.4	Number of pole-pair assistant	45
2.4.1	Hardware assembling	8	8.8.5	Mechanical parameters measurement	45
3	Processors features and peripheral settings	10	8.9	Electrical parameters measurement control	46
3.1	i.MX RT1180	10	8.9.1	Mode 0	46
3.1.1	RT1180 - Hardware timing and synchronization	10	8.9.2	Mode 1	46
3.1.2	RT1180 - Peripheral settings	11	8.9.3	Mode 2	47
3.1.2.1	PWM generation - PWM1	11	8.9.4	Mode 3	47
3.1.2.2	Analog sensing - ADC1 and ADC2	11	8.10	Control parameters tuning	47
3.1.2.3	Quadrature Decoder (eQDC) module	11	8.10.1	Encoder sensor setting	48
3.1.2.4	Peripheral interconnection for - XBAR	11	8.10.2	Alignment tuning	50
3.1.2.5	Slow-loop interrupt generation - TMR1	12	8.10.3	Current loop tuning	50
3.2	CPU load and memory usage	12	8.10.4	Speed ramp tuning	51
4	SDK package project file and IDE workspace structure	14	8.10.5	Open loop startup	52
4.1	PMSM project structure	14	8.10.6	BEMF observer tuning	53
5	Github project structure	16	8.10.7	Speed PI controller tuning	53
6	Motor-control peripheral initialization	17	8.10.8	Position P controller tuning	55
7	User interface	19	9	Conclusion	58
8	Remote control using FreeMASTER	20	10	Acronyms and abbreviations	59
8.1	Establishing FreeMASTER communication	20	11	References	60
8.2	TSA replacement with ELF file	21	12	Useful links	61
8.3	Motor Control Application Tuning interface (MCAT)	22	13	Revision history	62
8.3.1	MCAT tabs description	24		Legal information	63
8.3.1.1	Application concept	25			
8.3.1.2	Parameters	25			
8.3.1.3	Current loop	28			
8.3.1.4	Speed loop	28			
8.3.1.5	Servo control	30			
8.3.1.6	Sensorless	31			
8.4	Motor Control Modes - How to run motor	32			
8.4.1	Scalar control	32			
8.4.2	Open loop control mode	33			
8.4.3	Voltage control	34			
8.4.4	Current/Torque control	35			
8.4.5	Speed FOC control	36			
8.4.6	Position (servo) control	37			
8.5	Faults explanation	38			
8.5.1	Variable "M1 Fault Pending"	38			
8.5.2	Variable "M1 Fault Captured"	39			
8.5.3	Variable "M1 Fault Enable"	39			
8.6	Initial motor parameters and hardware configuration	40			
8.7	Identifying parameters of user motor	41			
8.7.1	Switch between Spin and MID	42			
8.7.2	Motor parameter identification using MID	43			

Please be aware that important notices concerning this document and the product(s) described herein, have been included in section 'Legal information'.