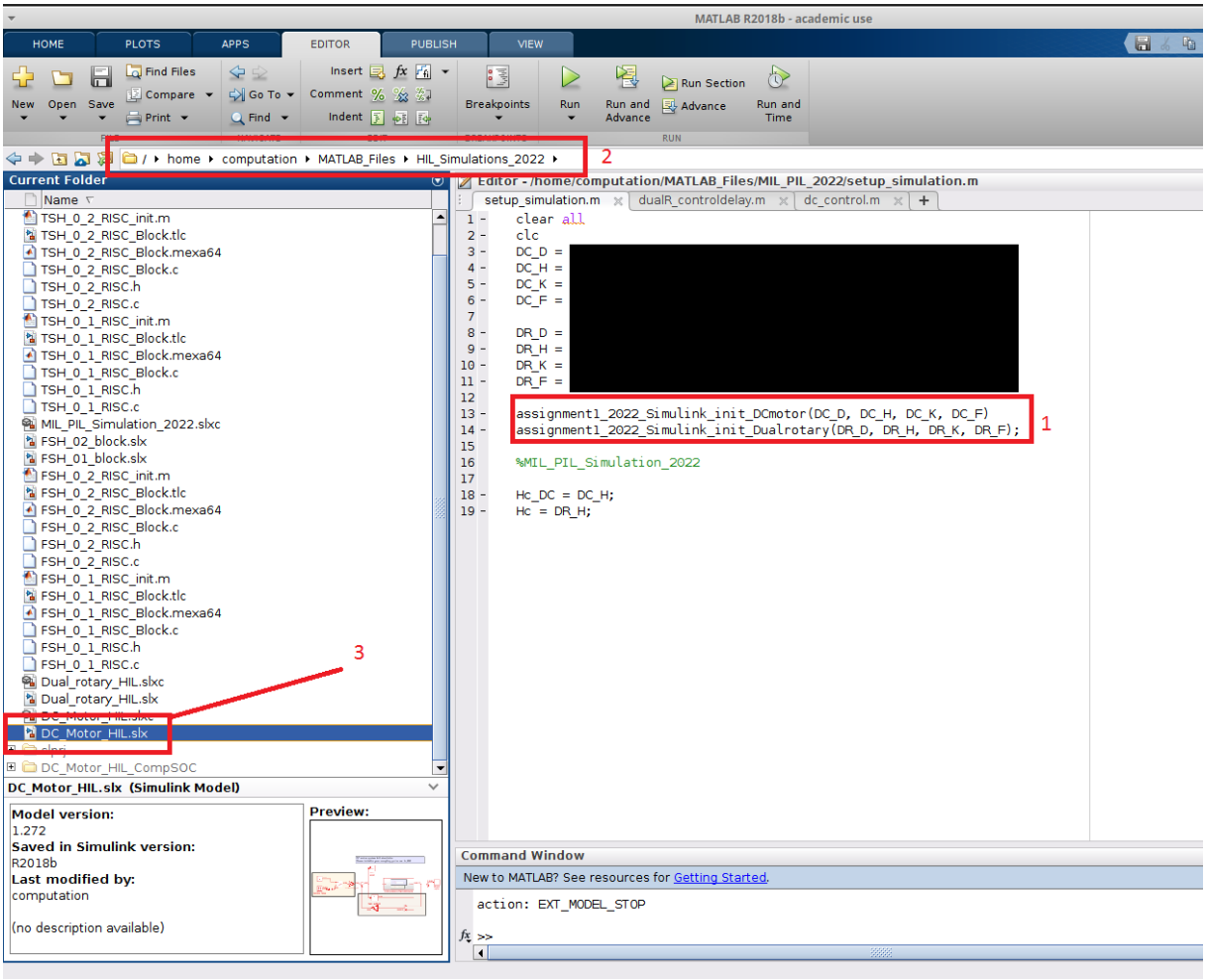
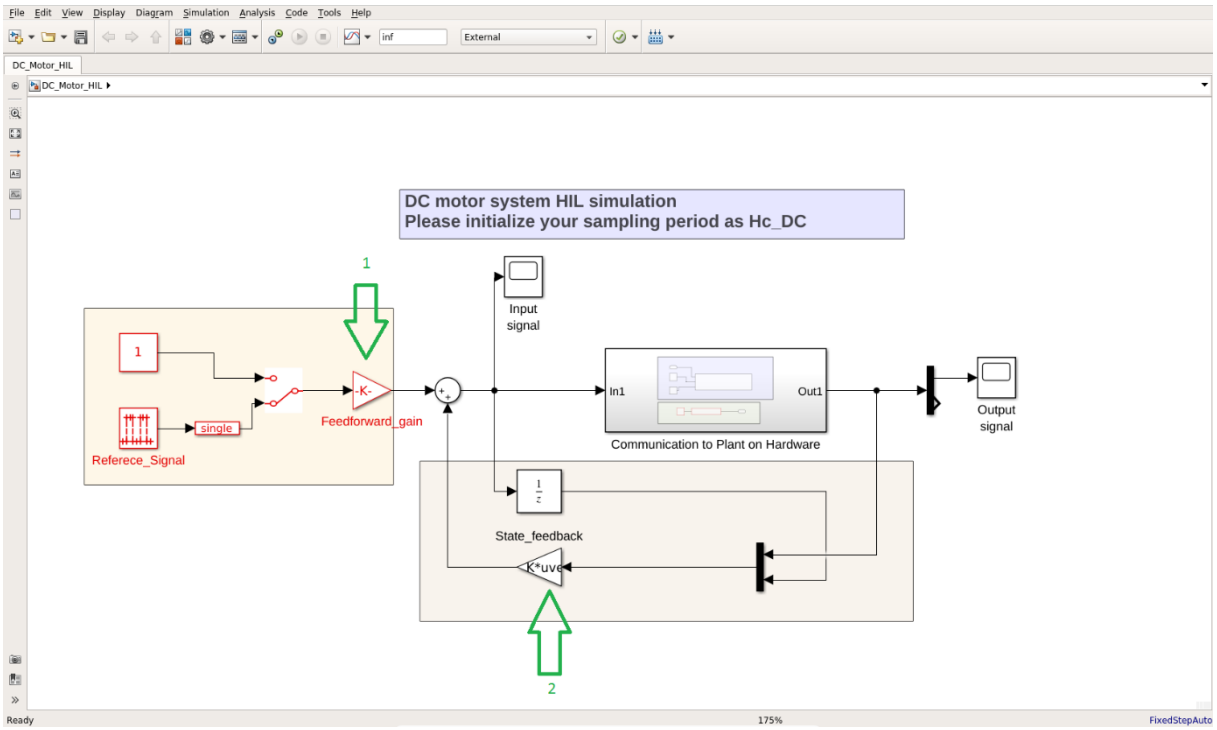
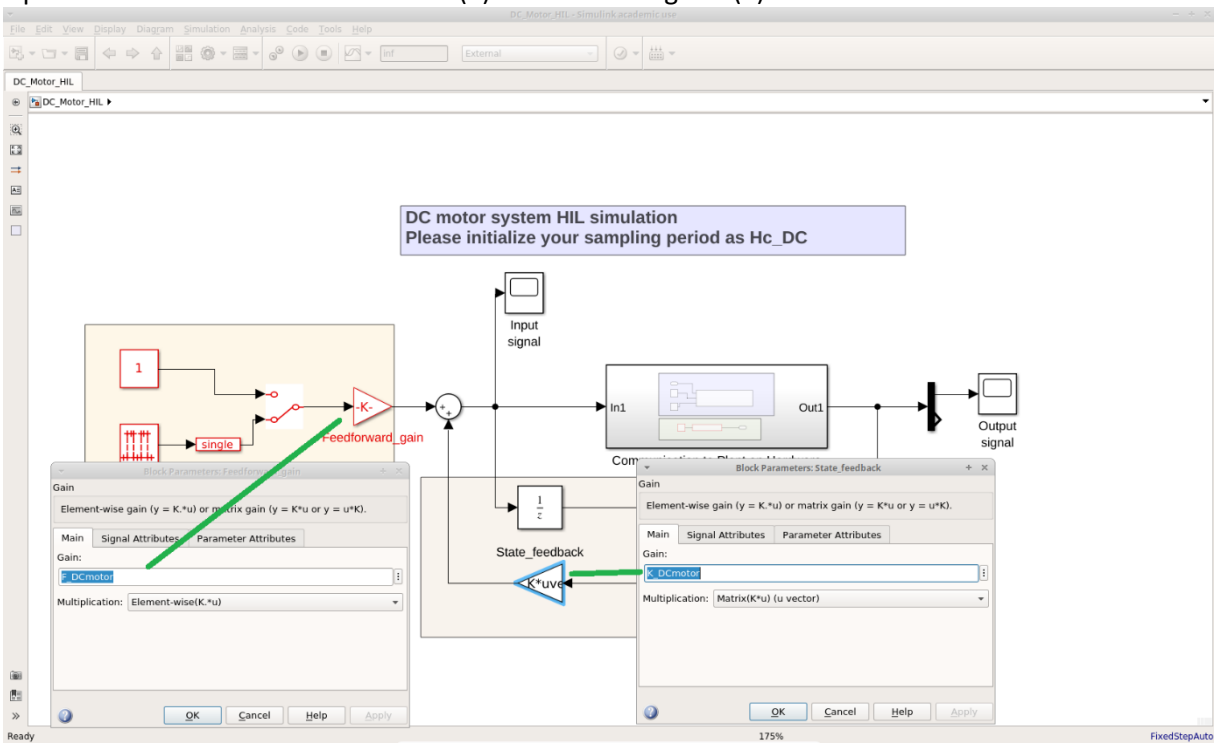
Prepare the initial variables (1 in the image below) :
assignment1_2022_Simulink_init_DCmotor(DC_D, DC_H, DC_K, DC_F);
assignment1_2022_Simulink_init_Dualrotary(DR_D, DR_H, DR_K, DR_F);
Navigate to the HIL folder (2)
Double click the DC_Motor_HIL.slx (3)



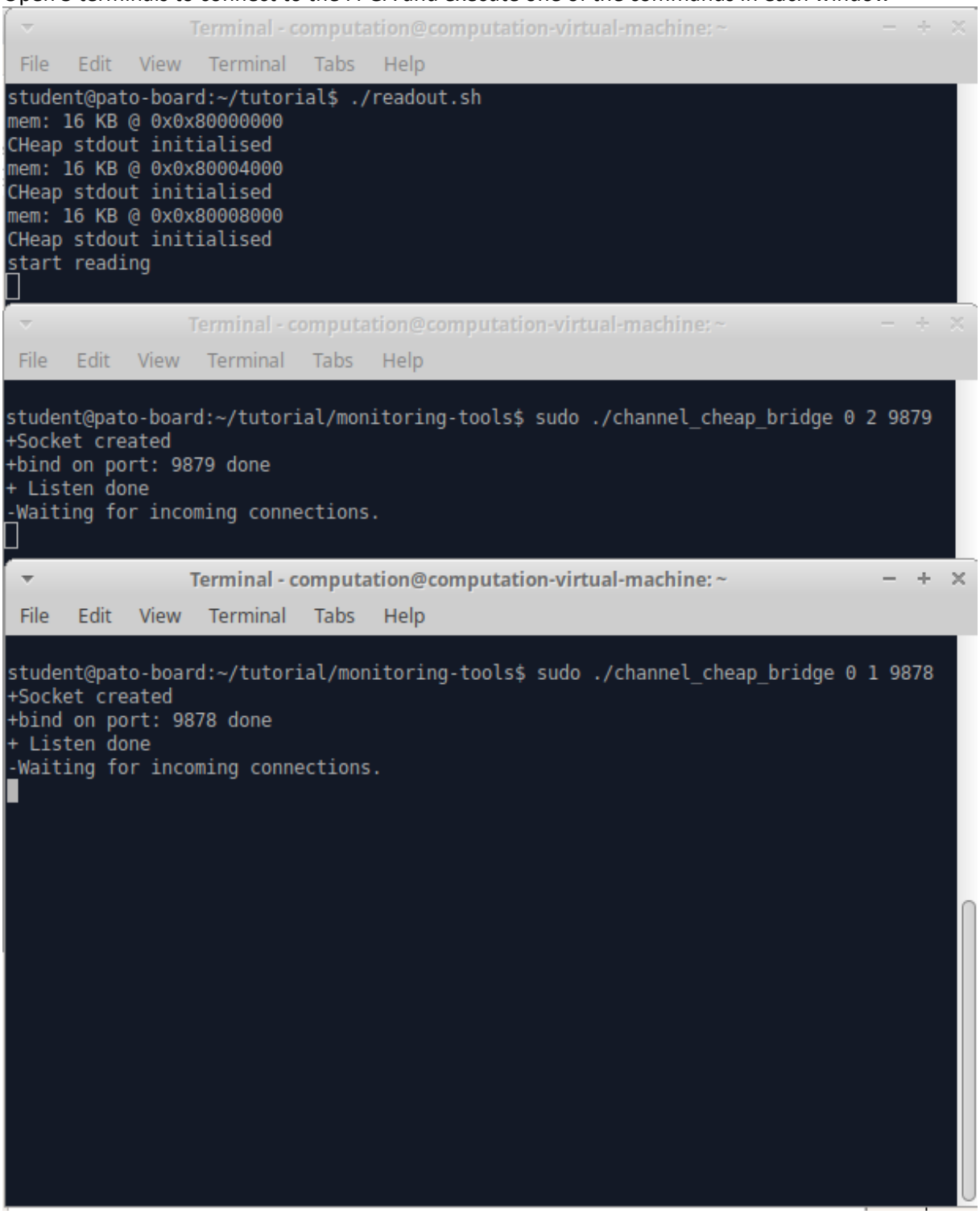
This gives the initial screen:



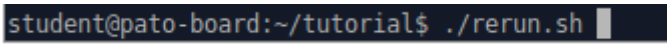
Update the values in the feedforward (1) and feedback gains (2)



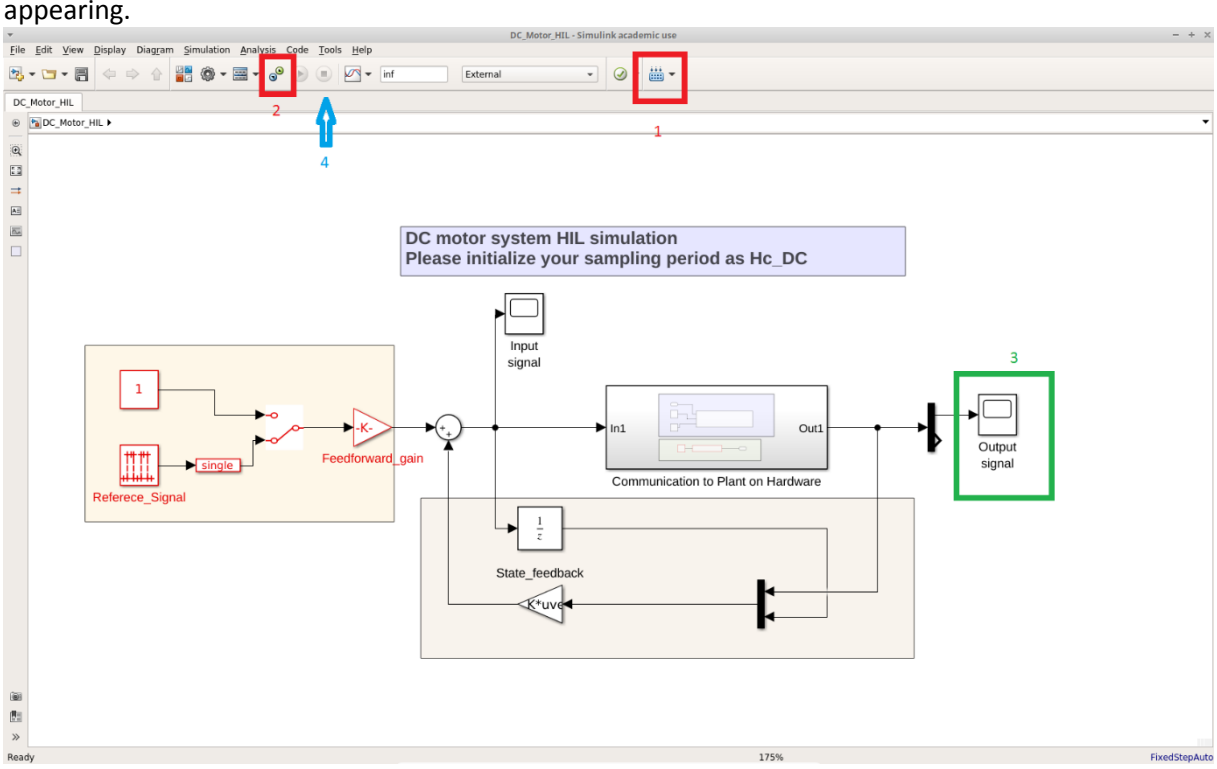
Open 3 terminals to connect to the FPGA and execute one of the commands in each window



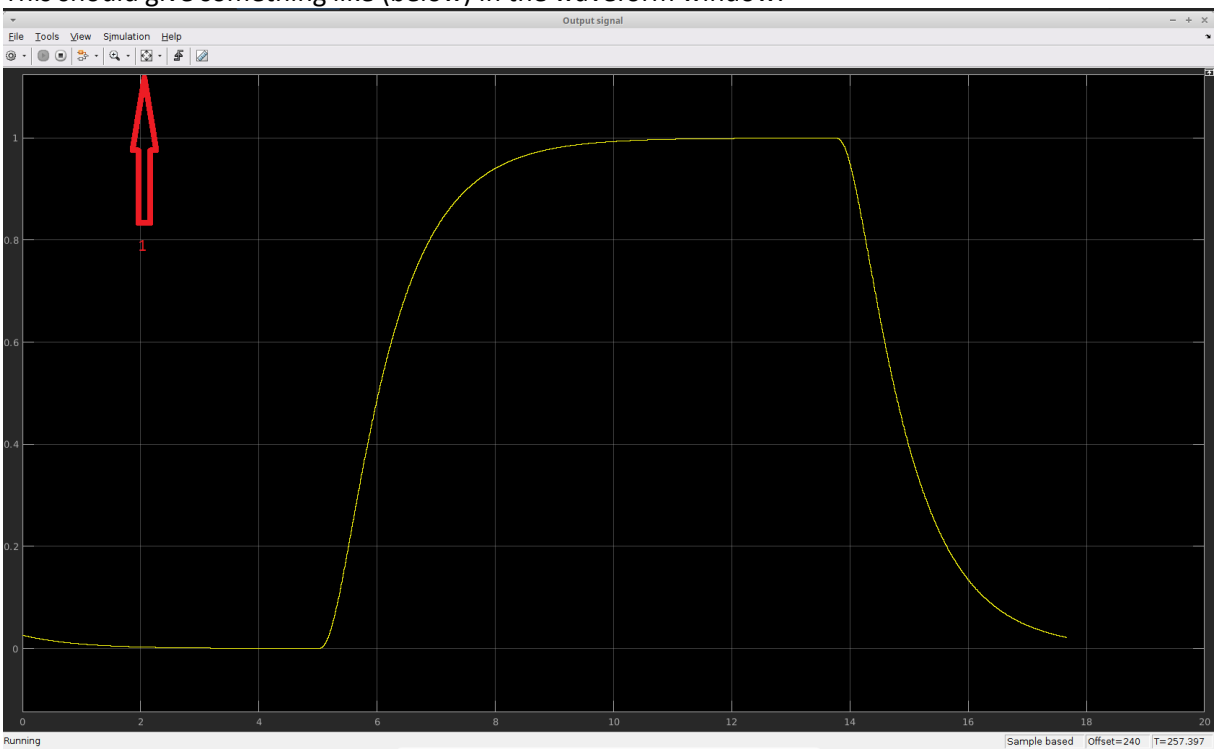
To be sure no problems occur, reset stuff on the fpga with
Go to the tutorial folder
./rerun.sh
Screenshot



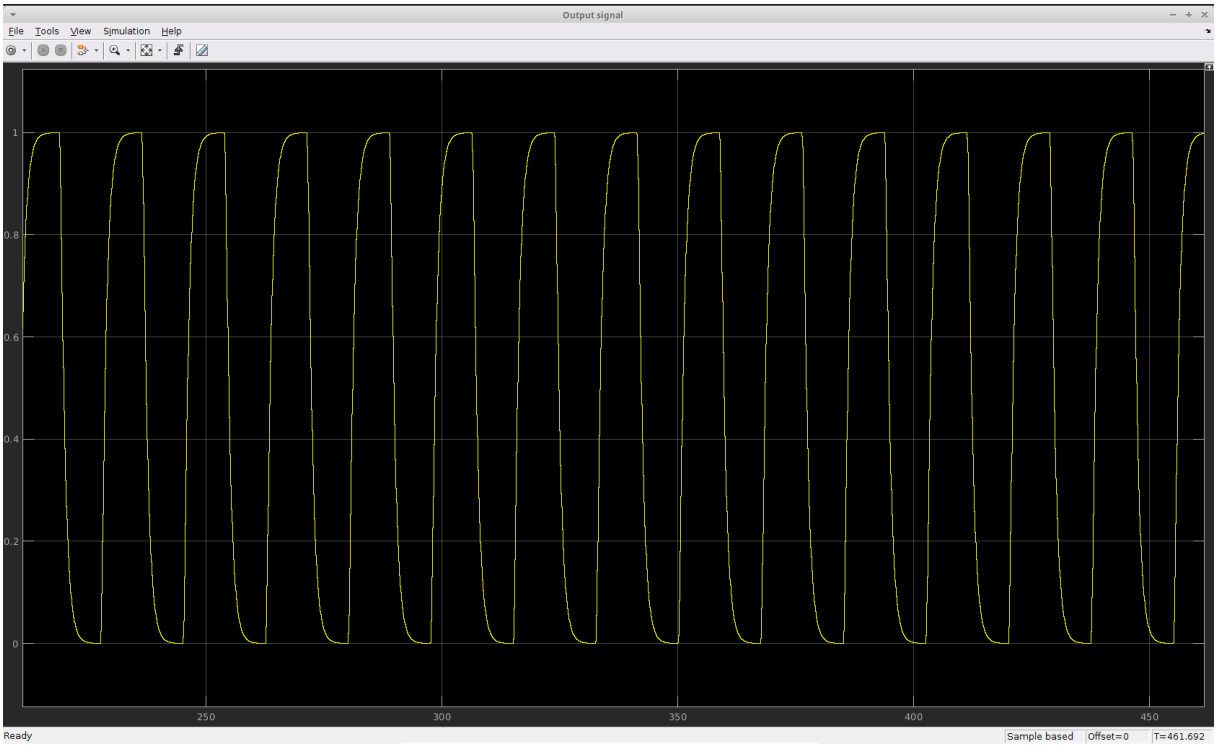
Build the model (1) and then connect to the target (2). After some time stop the simulation by pressing (4). Afterwards, double click the output signal block (3). You should see some waveform appearing.



This should give something like (below) in the waveform window:



Pressing the button (1) above will fit the waveform to the screen:



Note: the input waveform is a square wave.