

Index

Note: Page number followed by “*f*,” “*t*,” and “*b*” refer to figures, tables, and boxes, respectively.

A

- Absolute encoder, 375–376
- Active voltage vector, 301–304, 310
- Actual efficiency and ideal efficiency, 120*f*
- Air-gap flux-oriented (AFO) control, 212
- Air-gap power, 114
 - distribution of, 115*f*
- Alnico magnets, 167
- Alternating current (AC) motors, 1, 2*f*, 4–7, 6*f*, 36, 39, 95
 - AC motor drive applications, 266
 - AC power supply applications, 266–267
 - induction motors, 95–142
 - characteristics of, 112–122
 - determining equivalent circuit parameters for, 128–131
 - effect of rotor resistance, 124–127
 - equivalent circuit of, 104–112
 - fundamentals of, 99–104
 - operating modes of, 123–124
 - operation regions of, 139–142
 - speed control of, 131–138
 - structure of, 96–99
 - position sensors, 373–376
 - resolver, 373–375
 - rotary encoder, 375–376
 - sensorless control of, 382–387
 - speed estimation using incremental encoder, 377–381
 - M method, 378–379
 - M/T method, 380–381
 - T method, 379–380
- synchronous motors, 143–152
 - cylindrical rotor synchronous motors, 144–148
 - salient pole rotor synchronous motors, 148–151
 - starting of, 151–152
- Alternating current (AC) motors, current regulator of, 247
 - complex vector current regulator, 263–264
 - feedforward control, 259–262
 - for induction motors, 261
 - for permanent magnet synchronous motors, 261–262
 - hysteresis regulator, 248–250
 - ramp comparison current regulator, 250–251
 - stationary reference frame d – q current regulator, 252–254
 - synchronous frame PI current regulator, gain selection of, 256–259
 - synchronous reference frame d – q PI current regulator, 255–256
- Alternating current (AC) motors, high-speed operation of, 341
 - field-weakening control for induction motors, 343–357
 - classic field-weakening control method, 344
 - maximum torque, producing, 347–357
 - voltage- and current-limit conditions, 344–347
 - permanent magnet synchronous motor, 357–370
 - high-speed operation of, 360–366
 - surface-mounted permanent magnet synchronous motor, 366–370
- Alternating current (AC) motors, vector control of, 203
 - conditions for instantaneous torque control of motors, 204–206
 - induction motor, 206–234
 - combined flux estimation method, 230–232
 - detuning in the indirect vector control, 223–225
 - direct vector control based on the rotor flux, 212–220
 - indirect vector control based on the rotor flux, 220–223
 - instantaneous torque control, 207–212
 - proportional–integral flux controller, 233–234
 - rotor flux linkages estimation based on rotor voltage equations, 228–230
 - rotor flux linkages estimation based on stator voltage equations, 226–228
 - permanent magnet synchronous motors, 234–245
 - Interior Permanent Magnet Synchronous Motor, vector control of, 238–245
 - Surface-Mounted Permanent Magnet Synchronous Motor, vector control of, 236–238
- Alternating current (AC) motors modeling and reference frame theory, 153
 - d – q axes model of an induction motor, 188–197

Alternating current (AC) motors modeling and reference frame theory (*Continued*)
 flux linkage equations in, 190–193
 torque equation in, 193–197
 voltage equations in, 189–190
 d – q axes model of permanent magnet synchronous motor, 197–201
 flux linkage equations in, 198–200
 torque equation in, 200–201
 voltage equations in, 198
 inductance between stator and rotor windings, 160–163
 permanent magnet synchronous motor, modeling of, 163–174
 model of, 169–174
 structure of, 164–169
 reference frame transformation, 174–188
 by complex vector, 185–188
 d – q reference frame, types of, 175–176
 by matrix equations, 176–184
 rotor windings, 158–159
 stator windings, 157–158
 Anti-windup control, 73–74
 Anti-windup controller, 73–74, 90, 262
 proportional–integral current controller, gains selection procedure of, 74
 Arago's Disk, 95–96, 96*f*
 Armature circuit, 42
 Armature voltage control, 45–46, 46*f*
 Armature winding, 39, 41–42, 42*f*, 143–144
 Asynchronous motor, 6, 95
 Average torque control technique, 203
 Axial-flux type BLDC motor, 393–394
 Axial-flux type PMSMs, 165–166

B

Back calculation method, anti-windup control by, 73*f*, 74*f*
 Back-electromotive force (back-EMF), 13*b*, 42–43, 342–343, 345–346, 383
 sensorless control based on, 412–415
 Bandwidth, 65*b*, 72
 of speed control, 77
 Base speed, 140, 142, 341, 350–351
 Bipolar switching method, 83, 84*f*, 409, 409*f*, 410*f*
 Blanking time. *See* Dead time
 Blocked rotor test, 130–131, 130*f*
 Breakdown torque region, 116–117, 139, 142, 142*f*
 Brushless direct current (BLDC) motors, 1, 389
 configuration of, 390–394
 construction of, 393–394
 control of, 406–408

current control, 408
 speed control, 406–408
 versus direct current motors, 390–391
 driving principle of, 394–397
 Matlab/Simulink simulation, 405*b*
 modeling of, 398–405
 torque equation, 401–405
 voltage equations, 398–401
 versus permanent magnet synchronous motors, 391–393
 pulse width modulation techniques, 409–412
 bipolar switching method, 409
 unipolar switching method, 409–412
 sensorless control of, 412–415
 based on back-electromotive force, 412–415
 Butterworth filter, 231, 231*b*

C

Carrier wave, 292*b*
 Clark's transformation, 178
 Classification of electric motors, 1, 2*f*
 Closed-loop control, 58–60, 58*f*
 feedback control, 58–60
 integral controller (I controller), 59, 59*f*
 proportional controller (P controller), 58, 58*f*
 proportional–integral controller, 59, 60*f*
 feedforward control, 60–61, 61*f*
 Closed-loop frequency response, 65, 71*f*
 Closed-loop transfer function, 52*b*, 70, 78
 Commutation, 396
 of phase currents, 402*f*
 torque ripple during, 402–405
 Complex vector current regulator, 263–264
 Complex vector synchronous frame current regulator, 263–264, 264*f*
 Compound motor, 39
 Configuration of electric motors, 3–4, 3*f*
 Constant power region, 48–50, 140–142, 141*f*, 350–352, 361–366, 368–370
 Constant torque region, 48, 139
 operation characteristics in, 140*f*, 349–350, 349*f*, 360–361
 Constant voltage constant frequency (CVCF)
 inverter, 266–267
 Constant volts per Hertz control, 134–136
 Continuous modulation, 310–311
 Continuous pulse width modulation (CPWM)
 methods, 311
 Critical damping, 54
 Current model, 226, 228–230
 Current source inverter (CSI), 265, 266*f*
 Cylindrical motors, 26
 Cylindrical rotor configuration, 23, 23*f*

Cylindrical rotor synchronous motors, 144–148
 output power and torque for, 148*f*
 per phase equivalent circuit of, 146*f*
 torque of, 147–148
 Cylindrical stator and rotor configurations, 23*f*, 96

D

Damping ratio, system responses according to, 53–54, 54*f*
 Dead time, 269–270, 331–338
 compensation, 336–338
 negative current, 337–338
 positive current, 336–337
 effect, 333–336
 Decoupling control. *See* Feedforward control
 Deep-bar rotor, 125–126
 effective resistance and output torque in, 126*f*
 versus normal rotor, 125*f*
 Detuning effects, 224, 224*f*
 reference frame error due to, 225*f*
 Digital controllers, 37
 Direct current (DC) motors, 1, 2*f*, 4–5, 5*f*, 25, 36, 39
 block diagram for, 51*f*
 and brushless direct current motors, 390–391
 capability curve of, 49*f*
 closed-loop control, 58–60, 58*f*
 feedback control, 58–60
 feedforward control, 60–61, 61*f*
 configuration, 39–42, 40*f*
 control system, configuration of, 56
 control system, design consideration of, 61–66
 gain margin and phase margin, 63–64
 response time/speed of response, 64–65
 stability, 62–64
 steady-state error, 65–66
 current controller design for, 66–74
 anti-windup controller, 73–74
 PI controller, 66
 proportional–integral current controller, 69–72
 current control system, 68*f*
 direct current motor drive system, simulation of, 86–92
 direct current motor modeling, 86–87
 four-quadrant chopper modeling, 91–92
 mechanical system modeling, 87–89
 proportional–integral current controller modeling, 89
 proportional–integral speed controller modeling, 90
 equivalent circuit of, 43*f*
 modeling of, 42–44
 armature circuit, 42
 back-electromotive force, 42–43
 mechanical load system, 44
 torque, 43–44
 open-loop control, 57–58, 57*f*
 operation regions of, 48–50
 constant power region, 48–50
 constant torque region, 48
 power electronic converter for, 82–85
 four-quadrant chopper, 82
 switching schemes, 83–85
 simple driving circuit for, 82*f*
 speed controller design, 75–81, 75*f*
 integral-proportional controller, 79–81
 proportional–integral speed controller, 75–79
 steady-state characteristics of, 45–50
 armature voltage control, 46, 46*f*
 field flux control, 47–48, 47*f*
 transient response characteristics of, 50–55
 Direct current (DC) power, 36, 95
 Discontinuous modulation, 310–311
 Discontinuous PWM techniques, 311–317
 30-degree, 313–317
 60-degree, 311–312
 60-degree (± 30 -degree), 312
 ± 120 -degree, 312–313
 Distributed winding, 97–98, 100–101, 164, 164*f*
 Double sampling, 338
 Double-cage rotor, 126, 127*f*
 Doubly fed machine, 20, 21*f*, 25*f*
 d – q axes current regulators, 252–259
 stationary reference frame d – q current regulator, 252–254
 synchronous frame PI current regulator, gain selection of, 256–259
 for induction motors, 257–258
 for permanent magnet synchronous motors, 258–259
 synchronous reference frame d – q PI current regulator, 255–256
 d – q axes model
 of induction motor, 188–197
 flux linkage equations, 190–193
 torque equation, 193–197
 voltage equations, 189–190
 of permanent magnet synchronous motor, 197–201
 flux linkage equations, 198–200
 torque equation, 200–201
 voltage equations, 198
 d – q transformation, 174
 Dynamic braking, 33

Dynamic equation of motion, 27–32
 gears/pulleys, system with, 31–32
 translational motion and rotational motion,
 combination system of, 30–31
 Dynamic overmodulation methods, 325–327
 minimum-magnitude-error pulse width
 modulation method, 326
 minimum-phase-error pulse width modulation
 method, 325–326
 overmodulation method considering the
 direction of current, 327

E

Efficiency, defined, 119
 Electric and magnetic parts of electric
 motors, 3*f*
 Electric drive system, 35–37, 56*f*
 configuration of, 35*f*
 digital controllers, 37
 electric motors, 36
 power electronic converters, 36–37
 power supply, 36
 sensors and other ancillary circuits, 37
 Electromagnetic induction, 1, 6, 95
 Electromechanical energy conversion, 7, 7*f*
 Electromotive force (EMF), 95–96

F

Faraday's law, 13*b*, 99, 107–108
 Feedback control, 58–60
 integral controller, 59, 59*f*
 proportional controller, 58, 58*f*
 proportional–integral controller, 59, 60*f*
 Feedforward compensation technique, 336
 Feedforward control, 60–61, 61*f*, 259–262
 for induction motors, 261
 for permanent magnet synchronous motors,
 261–262
 Feedforward field-oriented control, 223
 Feedforward field-weakening control method,
 355–357
 Ferrite (or ceramic) magnets, 167
 Ferromagnetic materials, 8, 96
 Field flux control, 45, 47–48, 47*f*
 Field winding, 39, 143–144
 Field-oriented control, 203–204, 209–210
 Field-weakening control for induction motors,
 343–357
 classic field-weakening control method, 344
 feedback method, 343
 feedforward method, 343
 maximum torque, producing, 347–357

 constant torque region, 349–350
 field-weakening region I, 350–352
 field-weakening region II, 352–357
 voltage- and current-limit conditions,
 344–347
 current-limit condition, 346–347
 voltage-limit condition, 344–346, 346*f*
 Field-weakening region, 48–50, 139
 Final value theorem, 65
 Flux angle, 210–212
 Flux estimation method, combined, 230–232
 Flux linkage equations, in d – q axes, 190–193,
 198–200
 Flux–current characteristic, 9*f*
 magnetic energy in, 13*f*
 Flux-producing current, 207–209, 214
 Flux-weakening operation, 364–365
 concept of, 358*f*
 onset of, 364*f*
 optimal currents in, 365*f*
 optimal current vector in, 365*f*
 Flux-weakening region, optimal current trajectory
 in, 366*f*
 Force for a current carrying conductor, 44*f*
 Force on a conductor, 40*f*
 Forward braking (generating) mode, 35
 Forward motoring mode, 34
 Four-quadrant chopper, 82, 91–92
 Four-quadrant operation modes, 33–34, 33*f*
 in elevator drive, 34*f*
 Fractional-pitch winding, 108
 Frequency modulation index, 295
 Frequency response, 61*b*
 closed-loop, 71*f*
 open-loop, 70*f*, 75–76
 Full-bridge inverter, 275, 275*f*

G

Gain margin, 62–64, 63*f*
 Gate turn-off (GTO) thyristor, 36–37, 268
 Gears/pulleys, system with, 31–32
 Generalized rotating transformation, 176
 Generating mode, 32–33

H

Hall effect sensors, 37, 217–220, 226, 395–396,
 395*b*, 408, 412
 Harmonic distortion factor (HDF),
 313–315, 314*f*
 H-bridge circuit, 82, 83*f*
 Hysteresis regulator, 248–250
 operation principle of, 249*f*

- I
- Ideal efficiency, 120–122, 120*f*
- Incremental encoder, 236, 375–376, 375*f*
 - speed estimation using, 377–381
- Induced voltage, 13*b*, 106, 109
 - for a moving conductor, 252*f*
- Inductance of the coil, 10*f*
- Induction motor, 5–6, 26, 95–142
 - back-electromotive force of, 140
 - capability curve of, 143*f*
 - characteristics of, 112–122
 - efficiency, 119–122
 - input power factor, 113
 - output torque, 113–117
 - stable operating point, 117–119
 - stator current, 112–113
 - combined flux estimation method, 230–232
 - determining equivalent circuit parameters for, 128–131
 - blocked rotor test, 130–131
 - measurement of stator resistance, 128–129
 - no-load test, 129–130
 - detuning in indirect vector control, 223–225
 - direct vector control based on rotor flux, 212–220
 - induction motor drive system by the direct vector control, 215–220
 - relation between d -axis stator current and rotor flux linkage, 213–214
 - relationship between q -axis stator current and output torque, 214–215
 - d - q axes model of, 188–197
 - flux linkage equations in, 190–193
 - torque equation in, 193–197
 - voltage equations in, 189–190
 - effect of rotor resistance, 124–127
 - equivalent circuit of, 104–112
 - rotor circuit, 109–112
 - stator circuit, 105–108
 - feedforward control for, 261
 - field-weakening control for, 343–357
 - classic field-weakening control method, 344
 - maximum torque, producing, 347–357
 - voltage- and current-limit conditions, 344–347
 - flux controller of, 232–234
 - proportional–integral flux controller, 233–234
 - fundamentals of, 99–104
 - rotating magnetic field, 100–104
 - generation mode, 123
 - indirect vector control based on rotor flux, 220–223
 - instantaneous torque control, 207–212
 - flux angle, 210–212
 - instantaneous torque control method of, 210*f*
 - modeling of, 154–163
 - inductance between stator and rotor windings, 160–163
 - rotor windings, 158–159
 - stator windings, 157–158
 - motoring mode, 123
 - operating modes of, 123–124
 - operation regions of, 139–142, 139*f*
 - breakdown torque region, 142
 - constant power region, 140–141
 - constant torque region, 139
 - plugging mode, 124
 - power-flow diagram in, 114*f*
 - proportional–integral gains for, 257–258
 - regenerative braking, 123–124
 - rotor flux linkages estimation
 - based on rotor voltage equations, 228–230
 - based on stator voltage equations, 226–228
 - speed control of, 131–138
 - closed-loop speed control, 136–138
 - slip control, 131–133
 - synchronous speed control, 133–136
 - stator and rotor windings of, 154*f*, 155*f*
 - structure of, 96–99, 97*f*
 - rotor, 98–99
 - stator, 97–98
- Inner rotor type, 167–169, 393–394
- Instantaneous torque control, 203–204
 - of induction motor, 207–212
- Insulated gate bipolar transistor (IGBT), 36–37, 268
 - switching characteristics of, 332*f*
- Integral controller, 59, 59*f*
- Integral windup, 73
- Integral-proportional (IP) controller, 79–81
- Integrated gate-commutated thyristor (IGCT), 36–37, 268
- Interior permanent magnet synchronous motor (IPMSM), 166–167, 169–170, 357–358, 360, 362
 - high-speed operation of, 360–366
 - constant power region, 361–366
 - constant torque region, 360–361
 - rotor and its equivalent of, 170*f*
 - rotor configurations of, 167*f*
 - self-inductance of, 171
 - surface-mounted permanent magnet synchronous motor, 366–370
 - constant power region, 368–370
- International Electrotechnical Commission (IEC), 127

Inverters, 265–288
 basic circuit, 267*f*
 single-phase full-bridge inverters, 275–277
 single-phase half-bridge inverters, 271–274
 switching devices for, 268*f*
 three-phase inverter using switching functions, 283–288
 three-phase square wave inverter (six-step inverter), 277–283
 voltage source inverters, 267–271
 output voltage of basic circuit, 269–271

K

Kramer drive system, 133

L

Leakage flux, 105
 Lenz's law, 13*b*, 100
 Linear modulation range, 293
 Linear motion device, 13–17, 14*f*
 Linear region, 9
 Line-to-line voltages, 278, 279*f*, 282
 Load torque, 29, 30*b*
 Lorentz force, 95–96
 Lower switch PWM scheme, 410, 411*f*, 414*f*

M

M method, 378–379, 378*f*
 M/T method, 380–381, 381*f*
 Magnetic energy, 8–13
 in the flux–current characteristic, 13*f*
 Magnetic field energy increment, 21
 Magnetic flux, 3–4, 8–9, 11*b*
 Magnetic system, 7, 11*f*
 Magnetization curve, 9
 Magnetizing flux, 105, 145, 157–158
 Magnetomotive force (mmf), 10, 11*b*
 Magnitude invariance transformation, 178
 MATLAB/Simulink, 86–92, 195*b*, 219*b*, 244*b*
 direct current motor modeling, 86–87
 four-quadrant chopper modeling, 91–92
 mechanical system modeling, 87–89
 proportional–integral current controller modeling, 89
 proportional–integral speed controller modeling, 90
 Maximum torque per ampere (MTPA), 237, 348*f*, 349, 360
 control, 238–239
 current-limit circle and MTPA trajectory, 363*f*
 d–*q* Axes current commands for, 360*f*

Maximum torque per voltage (MTPV), 352, 364–365
 Mechanical load system, 27–35, 44, 87*f*
 dynamic equation of motion, 27–32
 gears/pulleys, system with, 31–32
 translational motion and rotational motion, combination system of, 30–31
 operation modes of electric motor, 32–35
 Mechanical system, 7, 87–89
 Metal oxide semiconductor field effect transistor (MOSFET), 268
 Minimum-magnitude-error pulse width modulation method, 326, 326*f*
 Minimum-phase-error pulse width modulation method, 325–326, 325*f*
 Model reference adaptive control (MRAC) method, 385
 Modulating wave, 292*b*
 Modulation index (MI), 290
 Moment of inertia, 28, 28*b*
 Motor characteristics according to speed, 342*f*, 343*f*
 Motor control system, configuration of, 57*f*
 Movable part, movement of, 14, 14*f*
 Multilevel inverter, 268
 Mutual-inductance, 19*b*, 153
 between stator as winding and the rotor *ar* winding, 160*f*
 between stator winding and magnet, 173*f*

N

National Electrical Manufacture's Association (NEMA), 127
 Naturally sampled PWM, 297
 Neodymium magnet, 165
 Neodymium–iron–boron (NdFeB) magnets, 168
 Neutral voltage, in Y-connected three-phase load, 282–283, 283*f*
 Neutral-point clamped inverter, 268
 Newton's second law of motion, 27
 No-load test, 129–130, 129*f*
 Nonfeedback control. *See* Open-loop control
N-turn coil, flux linkage of, 9

O

Off-going PWM scheme, 410, 411*f*, 414*f*
 “ $1/\omega_r$ ” method, 354
 On-going PWM scheme, 410, 411*f*, 414*f*
 Open-loop control, 57–58, 57*f*
 Open-loop frequency response, 69–70, 70*f*, 75–76
 Open-loop transfer function, 69, 75
 Operating principle of electric motors, 3–7

- alternating current motor, 5–7, 6*f*
- configuration of electric motors, 3–4, 3*f*
- direct current motor, 5, 5*f*
- Operation modes of electric motor, 32–35, 33*f*
- Optical incremental encoder, operating principle of, 376, 376*f*
- Optimal PWM, 291
- Outer rotor type, 164, 393–394
- Output torque of three-phase BLDC motor, 401–405
 - torque ripple during the commutation, 402–405
- Output voltage control of an inverter, 289*f*
- Output voltage of basic circuit, 269–271
- Overdamping, 54
- Overmodulation, 323–331
 - considering the direction of current, 327
 - dynamic overmodulation methods, 325–327
 - minimum-magnitude-error pulse width modulation method, 326
 - minimum-phase-error pulse width modulation method, 325–326
 - overmodulation method considering the direction of current, 327
 - steady-state overmodulation methods, 327–331

P

- Park's transformation, 176, 180
- Permanent magnet synchronous motor (PMSM), 34, 143, 152, 163, 225, 234–245, 258–259, 373, 382, 390
 - and brushless direct current motors, 391–393
 - configurations, 166*f*
 - different structures for the stator and rotor of, 164*f*
 - d – q axes model of, 197–201
 - flux linkage equations in, 198–200
 - torque equation in, 200–201
 - voltage equations in, 198
 - feedforward control for, 261–262
 - flux-weakening control for, 357–370
 - modeling of, 163–174
 - rotor, 165–169
 - stator, 164–165
 - structure of, 164–169
 - operation region of, 358, 358*f*
 - output power according to speed regions of, 359*f*
 - proportional–integral gains for, 258–259
 - rotor of, 165
 - rotor topologies of, 166*f*
 - speed regions of, 359
 - vector control of Interior Permanent Magnet Synchronous Motor, 238–245
 - vector control of Surface-Mounted Permanent Magnet Synchronous Motor, 236–238
- Permanent magnets, 167*b*
 - temperature effects on, 168
- Phase margin, 62–64, 63*f*
- Pole voltage, 268
 - and phase voltage, 281*t*
 - Fourier series, 272*b*
 - of three-phase inverter, 278*f*
- Pole-zero cancellation, 69, 256–257, 263
- Position observer, 381
- Position sensors, 373–376
 - resolver, 373–375
 - rotary encoder, 375–376
 - optical incremental encoder, operating principle of, 376
- Power bipolar junction transistor (BJT), 36–37
- Power electronic converter for DC motors, 36–37, 82–85
 - four-quadrant chopper, 82
 - switching schemes, 83–85
 - bipolar switching scheme, 83
 - unipolar switching scheme, 83–85, 85*f*
- Power invariance transformation, 178
- Power metal oxide semiconductor field effect transistor (MOSFET), 36–37
- Power supply, 36
- Powering mode, 271
- Prime mover, 1
- Programmed PWM technique, 290–291
- Proportional controller, 58
- Proportional–integral current controller, 59, 60*f*, 66, 69–72, 231
 - gains selection procedure of, 74
 - modeling, 89
 - selection of the bandwidth for current control, 71–72
- Proportional–integral flux controller, 233–234
- Proportional–integral speed controller, 75–79
 - drawback of, 78–79
 - gains selection procedure of, 77
 - selection of the bandwidth of speed control, 77
- Proportional–integral speed controller modeling, 90
- Pull-out torque, 116–117, 147–148
- Pulse per revolution (PPR), 375
- Pulse width modulation (PWM) inverters, 265, 288–310
 - current measurement, 338–339
 - dead time, 331–338
 - compensation, 336–338
 - effect, 333–336
 - discontinuous PWM techniques, 311–317
 - 30-degree, 313–317

Pulse width modulation (PWM) inverters

(Continued)

- 60-degree, 311–312
 - 60-degree (± 30 -degree), 312
 - ± 120 -degree, 312–313
 - inverters, 265–288
 - basic circuit of, 267f
 - single-phase full-bridge inverters, 275–277
 - single-phase half-bridge inverters, 271–274
 - switching devices for, 268f
 - three-phase inverter using switching functions, 283–288
 - three-phase square wave inverter (six-step inverter), 277–283
 - voltage source inverter, 267–271
 - overmodulation, 323–331
 - dynamic overmodulation methods, 325–327
 - steady-state overmodulation methods, 327–331
 - programmed PWM technique, 290–291
 - PWM technique based on offset voltage, 317–323
 - space vector PWM technique implementation, 319–323
 - sinusoidal PWM technique, 291–297
 - space vector PWM technique, 300–310
 - principle of, 302–304
 - symmetrical space vector pulse width modulation technique, 304–310
 - third harmonic injection PWM technique, 298–300
- Pulse width modulation (PWM) technique, 82, 344–345
- Pulse width modulation (PWM) waveform, 227, 385
- Pulse-based compensation technique, 336
- PWM_ON_PWM scheme, 410–412

R

- Radial-flux type BLDC motor designs, 393–394
- Radial-flux type PMSMs, 165–166
- Ramp comparison current regulator, 250–251, 251f
- Rare-earth magnets, 167–168
- Reference frame transformation, 153–154, 174–188
 - by complex vector, 185–188
 - d – q reference frame, types of, 175–176
 - by matrix equations, 176–184
 - transformation between reference frames, 179–184
 - transformation of abc variables into dqn variables in the stationary reference frame, 178–179

- Reference winding, 374
- Regeneration mode, 271
- Regenerative braking, 33, 123–124
- Regular-sampled PWM, 297, 297f
- Reluctance, 10, 17
- Reluctance motor, 4, 18, 26
- Reluctance torque, 18, 238
- Remanence, 168
- Residual flux density, 168
- Resolver, 373–375, 374f
- Reverse braking (generating) mode, 35
- Reverse motoring mode, 35
- Rotary encoder, 375–376
- Rotating machine, 18–26, 18f
 - direct current motor, 25
 - induction motor, 26
 - synchronous motor, 26
- Rotating magnetic field, 100–104, 111f
- Rotating reference frame, 175–176
- Rotation of electric motors, 4, 4f
- Rotor, 3
- Rotor equivalent circuit, 110, 110f
- Rotor flux angle, 212f, 213, 216–220, 223
- Rotor flux linkage, 21, 212, 214
- Rotor flux linkage vector, 212
- Rotor flux–oriented (RFO) control, 212
- Rotor reference frame, 176
- Rotor voltage equations, rotor flux linkages estimation based on, 228–230
- Rotor windings, 99, 104, 111–112, 143–144
 - inductance of, 158–159

S

- Salient pole rotor synchronous motors, 144, 148–151
 - equivalent circuit of, 150f
 - phasor diagram of, 150f
 - torque of, 149–151
- Samarium–cobalt (SmCo) magnets, 167–168
- Saturation region, 9
- Scalar control method, 203
- Scherbius drive system, 133
- Self-excited DC motor, 39
- Self-inductance, 19, 19b, 19f, 153
- Sensorless control, 223
 - of AC motors, 382–387
 - of brushless DC motors, 412–415
- Sensorless techniques
 - using characteristics of motor, 385–387
 - using motor model, 383–385
- Sensors and other ancillary circuits, 37
- Separately excited DC motor, 39, 204, 205f, 206
- Series motor, 39

- Shaft type rotary encoders, 375
 - Shoot-through condition, 269, 269*f*
 - Short-pitch winding, 108
 - Shunt motor, 39
 - Silicon carbide, 36–37
 - Simulink block diagram of mechanical load system, 87*f*
 - Single-phase full-bridge inverters, 275–277, 275*f*
 - load voltage, 276*f*
 - operation, 276*f*
 - Single-phase half-bridge inverter, 271–274, 271*f*
 - Single-phase or three-phase AC voltage sources, 36
 - Sinusoidal PWM (SPWM), 289, 291–297, 344–345
 - line-to-line voltage for, 296*f*
 - overmodulation on, 298*f*
 - pole voltage for, 295*f*
 - voltage modulation range for, 293*f*
 - Six-step inverter, 279–280
 - MATLAB/Simulink simulation, 287*b*
 - phase voltage of, 290*f*
 - Slip energy, 133
 - Slip energy recovery system, 133
 - Slip frequency, 110, 136–138
 - Slip speed, 109
 - Space vector PWM (SVPWM) technique, 290, 300–310, 344–345
 - principle of, 302–304
 - symmetrical space vector pulse width modulation technique, 304–310
 - Speed control, selection of the bandwidth of, 77
 - Speed controller design, 75–81, 75*f*
 - integral-proportional controller, 79–81
 - proportional–integral speed controller, 75–79
 - drawback of, 78–79
 - gains selection procedure of, 77
 - speed control bandwidth, selection of, 77
 - Speed estimation using incremental encoder, 377–381
 - M method, 378–379
 - M/T method, 380–381
 - T method, 379–380
 - Speed voltages, 189, 255
 - Speed–torque characteristic of a DC motor in the steady-state, 45*f*
 - Square wave inverter, 267, 271, 277–278
 - Squirrel-cage induction motors, 124–125
 - Squirrel-cage rotor, 98–99, 98*f*
 - State feedback decoupling control, 262–264, 263*f*
 - State filter, 381
 - Stationary reference frame, 175, 178–179
 - d – q current regulator, 252–254
 - Stator, 3
 - Stator and rotor windings, 104
 - inductance between, 21, 160–163
 - Stator flux linkage, 21, 105, 144
 - Stator flux-oriented (SFO) control, 212
 - Stator phase winding, 98*f*
 - Stator voltage equations, 170
 - rotor flux linkages estimation based on, 226–228
 - Stator windings, 97, 97*f*
 - equivalent circuit of, 106*f*
 - inductance of, 157–158, 159*f*
 - Steady-state overmodulation methods, 325, 327–331
 - Step speed command, transient response to, 50, 51*f*
 - Stray-load loss, 119
 - Surface-mounted permanent magnet synchronous motor (SPMSM), 165–166, 169, 357–358
 - high-speed operation of, 366–370
 - Switching schemes, 83–85
 - bipolar switching scheme, 83, 84*f*
 - unipolar switching scheme, 83–85, 85*f*
 - Switching sequence in two-phase modulation, 310*f*
 - Symmetrical space vector pulse width modulation technique, 304–310
 - Synchronous frame current regulator, 255*f*, 256
 - and stationary frame regulators, 256*f*
 - Synchronous frame PI current regulator, gain selection of, 256–259
 - proportional–integral gains
 - for induction motors, 257–258
 - for permanent magnet synchronous motors, 258–259
 - Synchronous motors, 5–6, 26, 95, 143–152
 - categories of, 164*f*
 - cylindrical rotor synchronous motors, 144–148
 - phasor diagram for, 148*f*
 - salient pole rotor synchronous motors, 148–151
 - starting of, 151–152
 - synchronization in, 152*f*
 - Synchronous reference frame d – q PI current regulator, 255–256
 - Synchronous reluctance motor, 20
 - Synchronous speed, 6, 20, 104
 - Synchronously rotating reference, 176
- ## T
- T method, 379–380, 379*f*
 - Third harmonic injection PWM (THIPWM), 297–300, 299*f*
 - Three-level inverter, 268
 - basic circuit used in, 269*f*
 - Three-phase AC voltage source, 36, 99

Three-phase inverter, 278*f*, 283*f*
 pole voltages of, 278*f*
 using switching functions, 283–288
 Three-phase load, 247, 252–253, 253*f*
 current control of, 248*f*
 Three-phase modulation, 310
 Three-phase square wave inverter (six-step inverter), 277–283
 Three-phase windings, 102–104, 102*f*
 Torque control system of a DC motor, 206*f*
 Torque production, continuous, 7–26
 linear motion device, 13–17
 magnetic energy, 8–13
 rotating machine, 18–26
 direct current motor, 25
 induction motor, 26
 synchronous motor, 26
 Torque production in the motor, 204*f*
 Torque-producing current, 214–215
 Total harmonic distortion (THD), 273–274
 Traction drives, 341
 Translational motion and rotational motion, combination system of, 30–31
 Two-level inverter, 268
 Two-phase modulation, 310, 310*f*

U

Underdamping, 54
 Unipolar switching method, 409–412, 409*f*
 Unipolar switching scheme, 83–85, 85*f*
 Unit feedback system, 65, 65*f*
 Unsaturated region, 9

Unstable system, 64*f*
 Upper switch PWM scheme, 410, 411*f*, 414*f*

V

Variable Voltage Variable Frequency (VVVF)
 inverter, 138, 266
 Vector control, 138, 204, 217
 of Interior Permanent Magnet Synchronous Motor, 238–245
 of Surface-Mounted Permanent Magnet Synchronous Motor, 236–238
 Voltage equation
 in d – q axes, 189–190, 198
 for a motor, 153
 Voltage model, 226–228
 Voltage source inverter (VSI), 265, 266*f*
 basic circuit configuration of, 267–271
 Voltage source inverter, 267–271
 output voltage of basic circuit, 269–271
 Voltage vector, rotation of, 302*f*
 Voltage-limit condition, 344–346, 346*f*, 364–365

W

Wound rotor, 99, 99*f*
 Wound-rotor type induction motors, 99, 132–133

Z

Zero voltage vector, 301, 305
 Ziegler–Nichols method, 69