Summary

[1 INTRODUCTION 3](#_Toc4437216)

[2 SYSTEM AND CONTROL SCHEME 4](#_Toc4437217)

[2.1 PMSM modelling 5](#_Toc4437218)

[2.2 Field-Oriented control 6](#_Toc4437219)

[2.3 PI controller 7](#_Toc4437220)

[3 SCRIPT MATLAB 8](#_Toc4437221)

[3.1 Definition of the parameters of the vehicle 8](#_Toc4437222)

[3.2 Characterization of a PMAC Brushless electric motor 8](#_Toc4437223)

[3.3 Characterization of the aerodynamic force of a car 9](#_Toc4437224)

[3.4 Creation of the speed profile 10](#_Toc4437225)

[4 SIMULINK MODEL 11](#_Toc4437226)

[4.1 Velocity reference of the PMSM controller 11](#_Toc4437227)

[4.2 Application of the aerodynamic force as inertia to the motor 12](#_Toc4437228)

[4.3 Implementation of a not ideal behaviour following and applying its characteristic torque curve 12](#_Toc4437229)

[4.4 Modification of the control parameters 13](#_Toc4437230)

[5 CODE GENERATION 13](#_Toc4437231)

[6 CONCLUSION 15](#_Toc4437232)

[7 REFERENCES 15](#_Toc4437233)

# INTRODUCTION

The aim of this project is to exploit so some simulation and automatic tool in order to define the control parameter of PMSM and to generate the code for a C environment using a Model-Based Design.

Starting from a predefined system model made in Simulink and Simscape of a Permanent Magnet Synchronous Machine (PMSM) and inverter sized for use in a typical hybrid vehicle, we modelled some non-ideal behaviour of the system and we applied an external torque.

![Immagine che contiene testo

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzM3AACSkgACAAAAAzM3AADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Figure 1 predefined model

The model can be used to design the PMSM controller, selecting architecture and gains to achieve desired the desired performances. The control strategy is based on a Field-Oriented Control that exploit a PI controller in order to follow a reference speed. Usually the reference for an electric vehicle is calculated on the torque request coming from the driver, while we considered a speed reference because we wanted to model the behaviour of a driverless car.

The project is based on two main components:

1. a MATLAB script that plots the motor torque and power as function of the speed of the rotor, together with the resistive torque modelled starting from the aerodynamic force as function of the actual vehicle speed
2. a SIMULINK model that takes the curves as input in order simulate the behaviour of the entire system.

# SYSTEM AND CONTROL SCHEME

## PMSM modelling

![Immagine che contiene albero

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzMyAACSkgACAAAAAzMyAADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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MFujEd6RZAIIx1BBBxXVCz1nxaEk1F30nSm+ZbWJv304/wBtv4R7DBoAp+Nrq38XaTd+F9ItjqU9wu150P7m1YHIdn7kHBwuTkV1mi2dxp+h2dpe3AuZ4IlR5QMbiB1qWw0600y1W30+3jt4l6Ki4z7n1Puas0ARz7Tbyb3ZF2nLKcFRjqD2rhfhxplzMt3rdzrOrXkM9zKtrBdXryIkakp90nB5UkH3Fa3j7W7jSfDNzHp+mahqF3cxmKJLO1eXaTwS20cYGTWb4Y8SeVpWl6NY6FrEdwqIkkl1pssMSH+NizADqSaEHQ7qis6z1qG81S4sI7e7V7fh5nt2WJj6K5GCfpWjQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQBkeIdM1HVbOOLStTTTnV8yM9v5wdcdMbhj1z7Vp28bQ2sUUj+YyIFL4xuIHWpKKACiiigAooooA8u8c/D3wzrfxM8O3up2BluLt5BKVfCyeWoZdwxz6fSvUFUIgVRgKMAVyniT/AJHzwl/10uv/AEWK6ygAooooAKDyOOKKKAMXQNI1LTHuX1XVV1FpmBQrb+VsAz1+Y5PPXjpW1RRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQByfiZgvjzwkWIA8y66n/AKZius69KxPEfhLSfFQtf7Xid2tGZ4WR9pQkYJB/Cuc8OT33hvx+3hKe+m1Gxns2u7WW4ctJAEZQUJ7j5xj6GgDvqKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooA57xfJ4qSxhHg2GylnLHzftRIwMcbeQOvrXL/AA1YPrWpHxH9oHizaPtK3W3iPnHlbQAUz3Htmuw8R+LdF8JwQS69epai4cpCCMmRh1A/Oua8OR3Pib4gN4u+xy2Wnw2bWlqJhh7gOykuR2A2DH1NAHfUUVzGoeOrbTvFEegto+rz3Uq70eC3Vo2UdTncOB9KAOnooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKAMnXvDOleJYYotYtROIWLRHOGQnqQe1cl4ba58N/EiTwpbX09/pklk10guJDI9oysoCFjk4bccA/3TV74haN4u1iO0TwlqhsIoyTcLGVV5fbcwIA/Cqfw5m0+wvrvRrnTZtP19VEtz9pl817hem9X4yM9hwM0Aeg1xnh4HVfiDrursweG1CWEPP3SuWY/jvX8q6rULSS+sJbeG7ms3kXAng2709xuBH6Vxem/C+XSbaS3sPGniGKGWQySKGtzvY9SSYs9qA6HeK6uuUYMPUHNLXFXN3YW/inS/Dtn4gubSa2UbrKFkLTjbkF9ykkYHUY5xXa0AFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFAHOeIfFcmj6jHp2n6NfateyRCXZa7MIuSMsWYdwemazPDmg6xfeLpPFfiaKG0uBbm1tLOFy/lRsQWLNgckqvHtUsF1BP8AGW6jhlSR4NHiSVVYEo3myHB9Dgg/jXY0AFFFFADdib9+1d397HNOoooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKy/EuuW/hvw1favdnEdrCX+p6AfiSBWpVe+0+z1O1a21G2iuoG+9HMgZT+BoA+Uvgv8AEWX/AIXVeXOsMca+/llm/gbPyD9QK+ta8x0v4e+HdM+MGpTR2dm63NjFcpbNAMQMGZMrxgfcz9a9OAwMDpQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRVTVUvpNKuE0mWOG9KYheVdyq3uKAOP8aJfaBr48X2mpWEEUVktrLbXp2CUB2bh8jB+aur0HVDrWg2motbtbG4jD+UzZK57Zrzexnt/Dd+t78ULOY3wb5NUkk861X0CcAp9MH616fp19aalp8N5p0qTWsyhopE6MPUUAWc0V5p8Wk8OT3ehW/iVkiiNz5jylGYrGgLEHbzg4wfrTvhxZoPE2q33hm3e18KTxR/ZUbhJZQW3ui9hjaOfTpQB6TRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAVU1R76PS7htJiilvQn7lJThWb3NW6qapqEek6XcX08cskcCb2SJdzEewoA8ysZ7S91hR8Umuob5W/d214NtgB2AZf3b/8AAiTXqNpFbW9jHHp0UKW6r+6SABUA7AY4xXnsF3e/FGArFc22m6Och448S3Tjp1IxGfbB+td7pOmW+jaTb6dZ7/It0CJvbJwPU0AcdaWGt6t8Rru+1zw/Jbab9ja0t5HuoXGD1YqrE/Nz26Hmp/Ch17w1oV1puqaPJJDp5c2lwlxGftCE5AxuypGe+K7as7W9IGtWAtTe3dlhw4ltHVXGO2WBGPwoGTaZd3F7p8VxeWTWMrjJgaVZCv8AwJSQfwNW6r2Fmmn2EFpG8kiwoEDyHLNjuT61YoEFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFAHGw2yW/xmuGgjjjWTRomk2jBZvOkGT+AFdlXE22p2N38aLmC2u4ZZYtHjR0RwSrCWQkEeuCD+NdtQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABVbUoJrrSruC2k8uaWB0jf8AusVIB/OrNVdR1Oy0ixkvdTuorW2iGXklcKB+dAHy/wDD74T+P9L+MNrqGoW80FrbXglnvXf5Z0DZIHc5FfVVYcfjLQpvCL+Job3zNJjjeRrhY2OFUkE7cZ7HtWrZXtvqNjDd2cglgmUPG4/iBoAnooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACq99ZW+oWclteQxzxSKQUkUMD+BqxRQB5L8LSsPhrWPDTKrtFqc9ukTAEJGcNnHoA1eqWlrFZWcVtbqEjiUKqgdBWfo/hjSdCury6020SK4vZPMuJsZaQ+5qtruqX32xNL0aSKCdkMs13MMrbIO+3+InPAOBgHmmHU36K53wfqF9qdlcXF3fw38AlMcE0UWwPt+Vmx7sCa6KkAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABWLq3hLSNb1CG81CGZpolKgx3MkasD2ZVYBh9Qa2qKAM7RNB0/w7YGy0iAwW+9nEfmMwUscnGScDJ6DgVo0UUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQB//9k=)

Figure 2 equivalent circuit of a PMSM in the abc reference frame

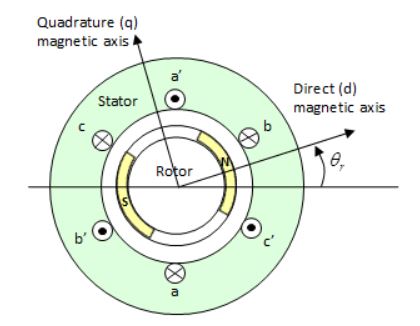


Figure 3 PMSM physical description

A PMSM is composed of three phase’s stator windings and permanent magnets mounted on the rotor surface or buried inside the rotor. The electrical equations of the PM synchronous motor can be described in the rotor rotating reference frame, written in the (*dq*) rotor flux reference frame.

The mathematic model of PMSM is based on the following assumptions:

* Neglecting the saturation of armature;
* Neglecting the wastages of eddy and magnetic hysterics;
* There is no rotor damp resistance.

Accordingly, the rotor reference plane of the PMSM equivalent circuit can be:



Figure 4 equivalent circuit in the dq reference frame

Stator *dq* equations can be written in the rotor reference plane as:

The dq-axis fluxes are described in the equations:

The expression of *λ*m represents mutual magnetic flux caused by the permanent magnet and the expression of the induced torque is:

The first term in the expression is the torque produced by the magnet and the second term is the reluctance torque due to the difference in reluctances.

The mechanical expression is provided by:

and the expression of ωr is given by:

In this reference frame, the maximum torque is obtained for which corresponds to the case when the rotor and the stator fluxes are perpendicular. The drive behaviour can be adequately described by a simplified model expressed by the mechanical torque equation.

## Field-Oriented control

Vector control is a method in which the stator currents are identified as two orthogonal components that can be visualized with a vector. One component defines the magnetic flux of the motor, the other the torque.

The control system of the drive calculates the corresponding current component references from the flux and torque references given by the drive's speed control. Typically, proportional-integral (PI) controllers are used to keep the measured current components at their reference values. The pulse-width modulation of the variable-frequency drive defines the transistor switching according to the stator voltage references that are the output of the PI current controllers.

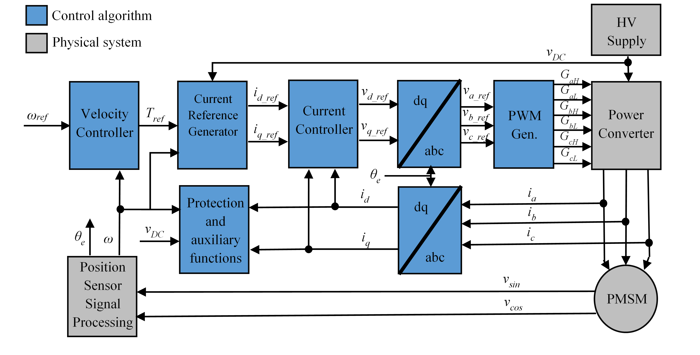


Figure 5 FOC scheme

As we chose to implement a velocity control, in the system there are two different control loop:

* Outer loop -> speed loop: a PI controller that set the torque reference starting from the error between the actual and the reference, that is the input of the entire system
* Inner loop -> current loop: a PI controller that set the voltage values in the dq reference frame starting from the current references generated considering a lookup table function of the torque

Than the voltages are used to generate di PWM that drives the gates of the inverter, generating the proper phase displacement on the three axes.

## PI controller

A proportional-integral controller (PI controller) is a feedback control loop mechanism which is widely used in control systems in industries. A PI controller calculates the difference between a measured process variable and a desired set-point which is considered as an error. By manipulating the variables, the error can be reduced by the controller.

![Immagine che contiene screenshot

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzc2AACSkgACAAAAAzc2AADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Figure 6 PI control loop

The error *e*(*t*), which exists between the given value *R*(*t*) and the actual output value *Y*(*t*), is used by PI controller to constitute the control through the linear combination of proportion (P) and integral (I).

The conventional PID control process is written in the form of transfer function as:

# SCRIPT MATLAB

First of all, we started to write the code in Matlab describing different things:

## Definition of the parameters of the vehicle

1. %% DEFINITION VEHICLE VARIABLE
2. mass = 1725; %curb weight [kg]
3. cd = 0.5; %draf
4. frontarea = 2.4; %front area [m^2]
5. airdens = 1.225; %air density [kg/m^2]
6. gr = 7.73; %gear ratio
7. wheelrad = 0.317; %wheel radius [m]

## Characterization of a PMAC Brushless electric motor

Description of the torque (N\*m) and power (W) characteristic curves according to the speed of the motor (RPM). Initially, we decided to implement and study the ideal behaviour of a Brushless motor and subsequently, compare it with a not ideal one.

1. %% DEFINITION OF THE CHARACTERISTIC CURVE OF THE MOTOR
3. pb = 13500; %base power [W]
4. nb = 5000; %base speed [rpm]
5. tb = pb/(nb\*pi/30); %base torque [Nm]
6. **tm** = 120; %maximum torque[Nm]
7. nm = 3500; %maximum speed at maximum torque[rpm]
8. nc = nb\*1.01; %maximum speed at base power [rpm]
9. Pmax = 13500;
10. Tmax = 120;
12. motorspeed = linspace(0, 8000, 10000);
14. %create the torque vector
15. motortrq = zeros(1,length(motorspeed));
16. **for** i = 1:length(motorspeed)
17. **if** motorspeed(i) <= nm
18. motortrq(i) = **tm**;
19. **else**
20. **if** motorspeed(i) <= nb
21. motortrq(i) = tb+(**tm**-tb)\*((nb-motorspeed(i))/(nb-nm))^1.3;
22. **else**
23. **if** motorspeed(i) <= nc
24. motortrq(i) = tb\*nb/motorspeed(i);
25. trq = motortrq(i);
26. **else**
27. motortrq(i) = trq\*(nc/motorspeed(i))^2;
28. end
29. end
30. end
31. end
33. motorpwr = (motortrq.\*motorspeed.\*pi)/30;

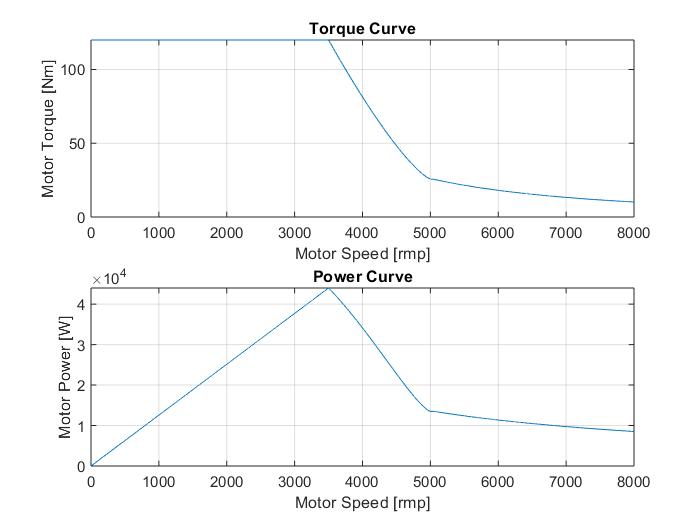


Figure 7 motor torque and power curves

## Characterization of the aerodynamic force of a car

Starting from the main equations, we evaluated the aerodynamic force and power according to the speed of the vehicle such as we were able to exploit it in the Simulink’s project in order to model the aerodynamic force as inertia of the motor.

1. %% EVALUATION OF THE VEHICLE AERODYNAMIC FORCE
2. speed = linspace(0, 60, 1000); %speed range [0:0.1:60]
4. faero = 0.5\*cd\*frontarea\*airdens.\*speed.^2; %aerodynamic force [N]
5. paero = (faero.\*speed)/1000; %aerodynamic power [kW]
7. speedkmh = 3.6.\*speed;

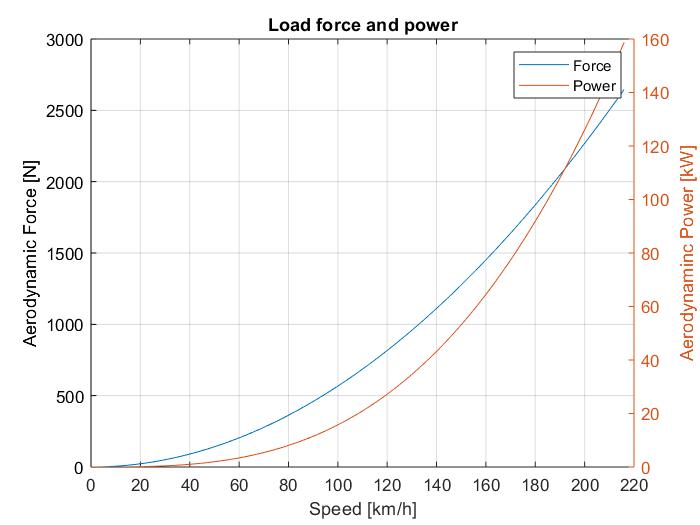


Figure 8 aerodynamic force and power curves

## Creation of the speed profile

We decided to implement the reference speed as a step function of 15 m/s because it creates one of the worst situations to control. Therefore, we are able to see how it behaves our control in this hard requirement. Moreover, we selected a low speed (54 Km/h) because we selected a driverless hybrid vehicle, therefore we considered that the electric motor works only at low speed.

1. %% CREATION OF THE REFERENCE SPEED (STEP FUNCTION)
2. time = linspace(1, 50, 10000);
3. vehiclespeed = zeros(1,length(time));
4. **for** i = 1:length(time)
5. **if** time(i) < 1.1
6. vehiclespeed(i) = 0;
7. **else**
8. vehiclespeed(i) = 15;
9. end
10. end

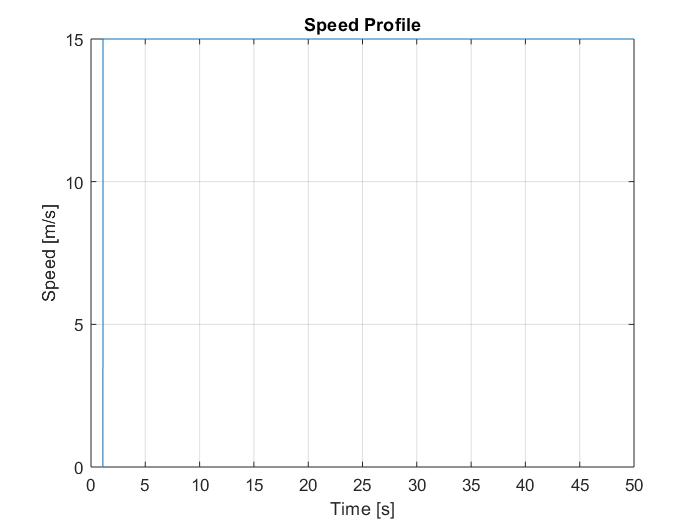


Figure 9 speed reference

# SIMULINK MODEL

In the Simulink project, we started from an already done motor controller, the Three-Phase PMSM drive. This example is based on a Permanent Magnet Synchronous Machine, a inverter with IGBT transistor that is directly connected to the battery. Moreover, the controller implements a Field-Oriented Control (FOC) structure, which is possible to select in the parameters a velocity or torque control. We decided to choose the implementation of the velocity control because we considered a driverless car instead of a normal one.

## Velocity reference of the PMSM controller

As input, we created our reference following the speed coming from the Matlab script. After that, we converted the speed of the vehicle in m/s to rad/s of the motor using the radius of the wheel, the gear ratio and the gain.

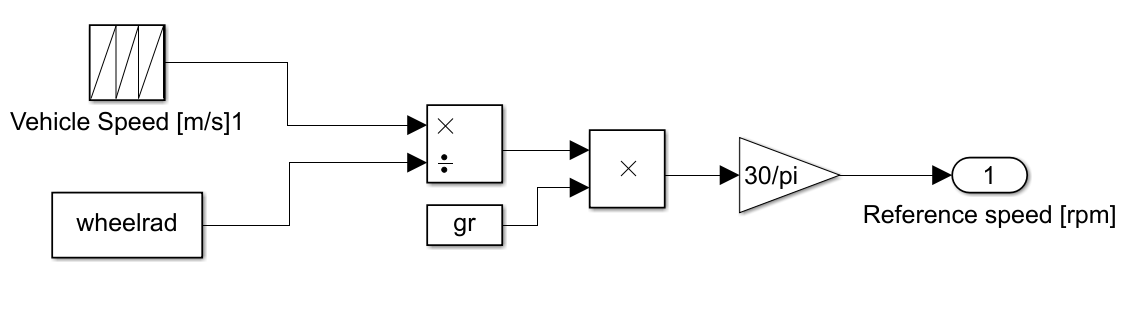


Figure 10 simulink reference speed calculation

## Application of the aerodynamic force as inertia to the motor

We inserted as aerodynamic inertia that contrast the motor torque. We evaluated it, by using the actual speed of the motor inside the equation:

At the end, we convert the force in a torque and then in inertia using an ideal torque source block.

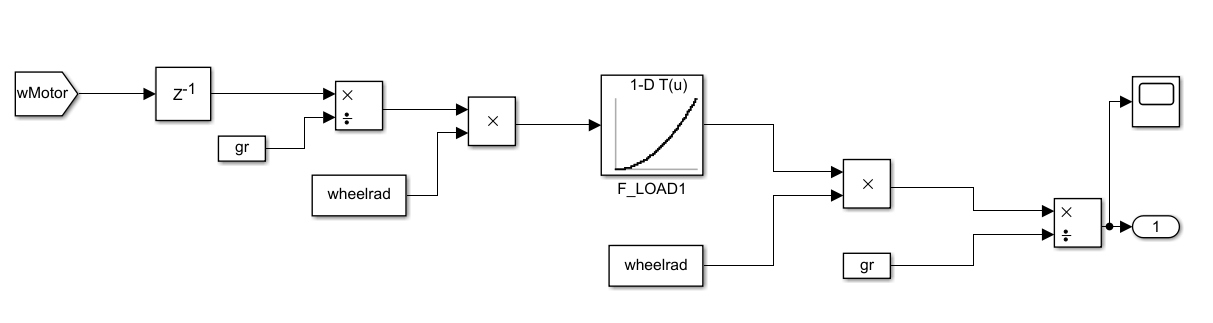


Figure 11 simulink load torque calculation

## Implementation of a not ideal behaviour following and applying its characteristic torque curve

Starting from the Matlab script, we created the real feature of the torque according to the motor speed. After that, exploiting this curve from Matlab, we modified inside of the PMSM controller block (which is present already in the main project of Simulink) the Torque limiter block, by replacing Tmax (maximum torque) with the real torque coming from the real characteristic curve that depends on the actual motor speed. This path to find this block is:

PMSM controller 🡺 PMSM Field-Oriented Control 🡺 Outer loop control 🡺 PMSM Current Reference Generator 🡺 Torque limiter

Here the control makes a comparison and give to his output the lower value between the torque demand (Pmax/wMechanical) and the maximum torque (real Tmax). Therefore, if the asked torque is higher than the maximum one, the control cut and limits it. So, after replacing the Tmax as described before, the control will drive the motor following his real torque behaviour as portray in the characteristic curve.

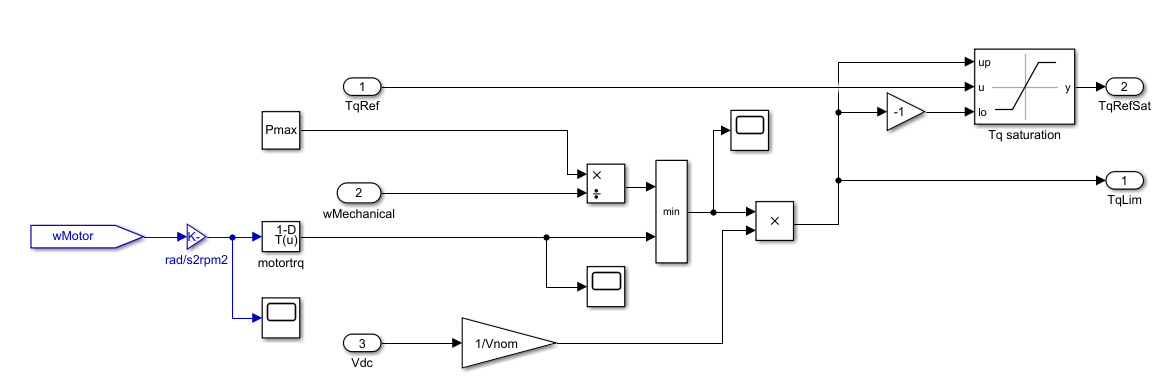


Figure 12 simulink motor characterisation in the control loop

## Modification of the control parameters

Afterwards, we modify many parameters to set properly our control and the other components following the requirements.

* Nominal DC voltage of the battery and the DC link: we put 150 V such as we were able to modify the speed with higher value.
* Higher switching frequency: we increased the fsw = 10000 in order to remove the ripple current and obtain a more precise and smooth control.
* Setting the gain values Kp and Ki of the inner loop and outer loop of the PI controller: we started by removing the rate limiter for the reference speed inside the control. Afterwards, we started to tune the Kp and Ki of our system. First of all, we put Ki = 0, such as we starting to tune just Kp to understand, in the easiest way, which was the best value of the proportional gain. At the end, we tuned and selected the Ki value to improve our control. Afterwards, we modified also the D-axis current proportional gain and Q-axis current proportional gain in order to obtain a better control.

Finally, we set: Kp = 0.8, Ki = 18, Kpd = 1, Kid = 10, Kpq = 1, Kiq = 10.

# CODE GENERATION

One of the main features of the Model-Based Design using Simulink is the automatic code generation for specific hardware development. In our case we chose to implement a system exploiting as target device a demo-board provided by STMiscroelectronics, i.e. STM32F407G-DISCO. In this case it has been necessary to download the proper hardware support package.

First, it’s really important for the project to be deployed on a microcontroller environment that all the time constant of the simulation are the same, as it’s not possible to have a variable step timing.

Another error that occur during the code generation was that MATLAB uses a variable called ‘rt’ as already defined value, so it has been necessary to change all the occurrences of a variable name in this way.

At this point we were able to run the Code Generation Advisor, that is a Simulink tool which performs some checks on the model in order to understand whether it is possible to generate a coherent code starting from such a project.

The analysis is performed to have execution efficiency, RAM efficiency and to follow MISRA C guidelines, that are the specific one for an automotive application.

![Immagine che contiene screenshot

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzc3AACSkgACAAAAAzc3AADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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+ghYf+AL/wDx6jyNa/6CFh/4Av8A/Hquea//AD7yfmv+NHmv/wA+8n5r/jQBT8jWv+ghYf8AgC//AMeo8jWv+ghYf+AL/wDx6rnmv/z7yfmv+NHmv/z7yfmv+NAFPyNa/wCghYf+AL//AB6jyNa/6CFh/wCAL/8Ax6rnmv8A8+8n5r/jR5r/APPvJ+a/40AU/I1r/oIWH/gC/wD8eo8jWv8AoIWH/gC//wAeq55r/wDPvJ+a/wCNHmv/AM+8n5r/AI0AU/I1r/oIWH/gC/8A8eo8jWv+ghYf+AL/APx6rnmv/wA+8n5r/jR5r/8APvJ+a/40AU/I1r/oIWH/AIAv/wDHqPI1r/oIWH/gC/8A8eq55r/8+8n5r/jR5r/8+8n5r/jQBT8jWv8AoIWH/gC//wAeo8jWv+ghYf8AgC//AMeq55r/APPvJ+a/40ea/wDz7yfmv+NAFPyNa/6CFh/4Av8A/HqPI1r/AKCFh/4Av/8AHquea/8Az7yfmv8AjR5r/wDPvJ+a/wCNAFPyNa/6CFh/4Av/APHqPI1r/oIWH/gC/wD8eq55r/8APvJ+a/40ea//AD7yfmv+NAFPyNa/6CFh/wCAL/8Ax6jyNa/6CFh/4Av/APHquea//PvJ+a/40ea//PvJ+a/40AU/I1r/AKCFh/4Av/8AHqPI1r/oIWH/AIAv/wDHquea/wDz7yfmv+NHmv8A8+8n5r/jQBT8jWv+ghYf+AL/APx6jyNa/wCghYf+AL//AB6rnmv/AM+8n5r/AI0ea/8Az7yfmv8AjQBT8jWv+ghYf+AL/wDx6obzTtXvrC4tJdRshHPE0TFbF8gMMHH73rzWl5r/APPvJ+a/40ea/wDz7yfmv+NAEtFRea//AD7yfmv+NHmv/wA+8n5r/jQBLRUXmv8A8+8n5r/jR5r/APPvJ+a/40AS0VF5r/8APvJ+a/40ea//AD7yfmv+NAEtFRea/wDz7yfmv+NHmv8A8+8n5r/jQBLRUXmv/wA+8n5r/jR5r/8APvJ+a/40AS1S1GzmuzayWs8cMttN5qmSIyKcoyYIDL2f17VY81/+feT81/xo81/+feT81/xoAp+RrX/QQsP/AABf/wCPUeRrX/QQsP8AwBf/AOPVc81/+feT81/xo81/+feT81/xoAp+RrX/AEELD/wBf/49R5Gtf9BCw/8AAF//AI9VzzX/AOfeT81/xo81/wDn3k/Nf8aAKfka1/0ELD/wBf8A+PUeRrX/AEELD/wBf/49VzzX/wCfeT81/wAaPNf/AJ95PzX/ABoAp+RrX/QQsP8AwBf/AOPUeRrX/QQsP/AF/wD49VzzX/595PzX/GjzX/595PzX/GgCn5Gtf9BCw/8AAF//AI9R5Gtf9BCw/wDAF/8A49VzzX/595PzX/GjzX/595PzX/GgCn5Gtf8AQQsP/AF//j1Hka1/0ELD/wAAX/8Aj1XPNf8A595PzX/GjzX/AOfeT81/xoAp+RrX/QQsP/AF/wD49R5Gtf8AQQsP/AF//j1XPNf/AJ95PzX/ABo81/8An3k/Nf8AGgCn5Gtf9BCw/wDAF/8A49R5Gtf9BCw/8AX/APj1XPNf/n3k/Nf8aPNf/n3k/Nf8aAKfka1/0ELD/wAAX/8Aj1Hka1/0ELD/AMAX/wDj1XPNf/n3k/Nf8aPNf/n3k/Nf8aAKfka1/wBBCw/8AX/+PUeRrX/QQsP/AABf/wCPVc81/wDn3k/Nf8aPNf8A595PzX/GgCn5Gtf9BCw/8AX/APj1Hka1/wBBCw/8AX/+PVc81/8An3k/Nf8AGjzX/wCfeT81/wAaAKfka1/0ELD/AMAX/wDj1Hka1/0ELD/wBf8A+PVc81/+feT81/xo81/+feT81/xoAp+RrX/QQsP/AABf/wCPUeRrX/QQsP8AwBf/AOPVc81/+feT81/xo81/+feT81/xoAp+RrX/AEELD/wBf/49R5Gtf9BCw/8AAF//AI9VzzX/AOfeT81/xo81/wDn3k/Nf8aAKfka1/0ELD/wBf8A+PUeRrX/AEELD/wBf/49VzzX/wCfeT81/wAaPNf/AJ95PzX/ABoAp+RrX/QQsP8AwBf/AOPUW9je/wBqR3l9d28vlQvEiQ27R/eZCSSXb+4Pzq55r/8APvJ+a/40ea//AD7yfmv+NAEtFRea/wDz7yfmv+NHmv8A8+8n5r/jQBLRUXmv/wA+8n5r/jR5r/8APvJ+a/40AF1/x5zf9c2/lUtV5nkkgkRbeTLKQMlfT61YoAKKKKAM0/eT/ron/oQq7F/rZ/8AroP/AEFapH7yf9dE/wDQhV2L/Wz/APXQf+grQBLRVe40+yu5BJdWcE7gYDSRKxA9MkVF/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KALtFUv7F0r/AKBln/4Dr/hR/Yulf9Ayz/8AAdf8KAP/2Q==)

Figure 13 purposes of the analysis

In the following image it’s possible to see the entire check list done during the system analysis:

![Immagine che contiene screenshot

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzY0AACSkgACAAAAAzY0AADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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VJIY+YqgbeMdjnkVyqeBtck0fS9EuZdPWw0VJRaXEcjmW5JhkijDoUAjAEmWIZskdBXf/arf/nvH/wB9ij7Vb/8APeP/AL7FJxTTXcabWx5zdeBPEsPh/VdI0yTSpIdXs4Y55bmaRWglSBISFAQ7lIjBBJBGTwatnwFdx65cnyor7T7rUBfMZtYu4fKbcr4+zpmOTDLkEle2QcZru/tVv/z3j/77FH2q3/57x/8AfYqrty5uv9f5E2VuU5awN34L8L6Npb28d9fXF79mVIpSq4eR5GfcVzhY9zEY5xjvmr/i7RZta0+3jtrK1u5YZvNUT3s1m0Z2kbkmiVmRuSOByCRW19qt/wDnvH/32KPtVv8A894/++xU20sM83Hw81yN2nurlNZlvLRLe8WfWLuzA2l8fNED5w2uF+cAnbnPzEVNP8OtQS6a9tJITJDfPNBbJf3FqrRNbxRFTNH86sDFkcMCOvXj0L7Vb/8APeP/AL7FH2q3/wCe8f8A32Kffz/zuHby/wArHD6X4S1vw7qB1PQ7TTPPurcw3dpc6hcOqN5ryCRZmRnckyNuBUZOORW34d0nVdI1fVxdLZyWN9dNeJNHK3mq7KilDGVxtG0kNuzyOK3ftVv/AM94/wDvsUfarf8A57x/99ihafl+oPXf+un5HF6l4Q1m4GsaXayWP9k61ei7muZJHFxBnZvRUClXzs4Ysu3PQ4rf8LaPcaHpM9rdvG7yX91cgxEkbZZ3kUcgc4YZ9/WtX7Vb/wDPeP8A77FH2q3/AOe8f/fYoWisG/5/n/mcva6Jr2l3mp2liunT6ZqN1LdGeaZ0miMg+ZNgQhuc4bcMDjBxXORfDTUrS0SHbb6glzp1taXkLaxd2catHEI2IEQxKpA6MFPXnnA9L+1W/wDz3j/77FH2q3/57x/99iklZW9Pw2Drf1/E8+/4QTXH161uLh7GeK11VbxLuW7naUQjOIViK7E2ggAgndjJwSTXXeEtIn0Hwjpul3jxvPawiN2iJKk+xIB/StP7Vb/894/++xR9qt/+e8f/AH2KeysHW5W1mK8n0qWPTYrOaZsDyr4HypFz8ytgEjIzzg/Q1xFh4A1GHUFvEg0vSITf2lydL0+V2t4xEXLupKKN7bwMBVHyjJNegfarf/nvH/32KPtVv/z3j/77FC0d/wCtAeqscXJ4R1i08UXOv6a1jNcf2hJcQ21xK8aSRSW8MTBnCMUcNFkEKwxx34rD4eX73mmXU91a72vbi41WNN22SOWVZhFHxyA8UYy2Mgue+K737Vb/APPeP/vsUfarf/nvH/32KFpby/r9Aev9f13Od8FeF7nwzDqCXk8U5muNtsY8/u7VFCwxnI6gZz7muWvvhvqF3rWsTx6ZoEUt/qH2q317zHN/aLhBhVEQ5G04/eY+bp2r0v7Vb/8APeP/AL7FH2q3/wCe8f8A32KFo7/10/yB6q39f1qcNoejl/itrU8Uwk03T2EscWOI7yeNfN/JFU/WZq6Pxbo1xr2hLZWbxJILu1nzKSBtjnSRhwDzhDj3x0rW+1W//PeP/vsUfarf/nvH/wB9ihaW8v0Dq2cR438H634ivL4Wb2dxaXenG1iivLuaNbSX58yCNFKyFty8nBG3jPSiHwfrEHiKC6s/sunwh1a6nttQnP2wCPZte2K+Xk4H7zO7A6V2/wBqt/8AnvH/AN9ij7Vb/wDPeP8A77FKysN6nG+APBeo+CLe3sknt5rKa1jN6nmOzR3aoql4yR8yMB0ONu0Y64G3Y6FLb+MNZ1afyXgvorZIlGSymMOGzkYH3hjBNa/2q3/57x/99ij7Vb/894/++xVNtiOKj8Hawqw6O0lj/Y0OrHU1uhI/2hv35nERj27R85xv38j+HNULHwN4k0XTXg0yTSp5LzSE066NxLIohZDKVdMId4PmnKnb0zntXon2q3/57x/99ij7Vb/894/++xUtJrl/ra35DvZ3/re/5nm8Pw2v7USW7Jb6ha3qQfaUk1i7tljZIY42AijGyVT5YI3bTzg9q7Tw1o8+jWt/HcvG5uNRubpPLJOEkkLKDkDnB5rU+1W//PeP/vsUfarf/nvH/wB9iqbbd/66f5EpJK39df8AMqeILCXVfDWp6dbsizXdpLBG0hIUMyFQTjPGTXK/8IRqP9ga9Y+da+bqN3azwne21RFHArbvl4OYWxjPUdO3a/arf/nvH/32KPtVv/z3j/77FJaNvuPexkeLNIvNX022/sswfa7O9gvI0uHKRyGNwdpYBiuRnnBx6Viy+EdVutG1eGd7OO51HWLbUVVJWZEWM25ZdxQEn9y2OOcjpzjsftVv/wA94/8AvsUfarf/AJ7x/wDfYoj7u39bf5IHrb+u/wDmzhdG8B3el6tbpNFFeWNteyXcNxJrF2GQs7MP9F5i3DcRu3YPXHNbXivSL7WPLhj0XQdZs9vMOqsyGN8/eUiNweMcYB4610H2q3/57x/99ij7Vb/894/++xStpYOtzzWL4aapYIoW4XWPtFlFa3Sz6vd2QGzf08rd5i7X27X5wv3uTWheeCtX8nXLGw/s9bPUjb3ELyTyBoZYUiURldhyh8kfNuyM9DXdfarf/nvH/wB9ij7Vb/8APeP/AL7FPv5gcZJ4T1q/1s6pe/YLeSW+sbp4Yp3kCiAOHAYxrkncMcDv0rO1zTJvC/iCXxPNqWj2xk1SSSCPUrpoInSS2ijIMm07XBhJHBBHHfj0T7Vb/wDPeP8A77FH2q3/AOe8f/fYo2vb+tv8kHr/AFv/AJnleleGNZ1rwrBeWdtaRXs1zfSw3639xZywLLcu6umxT5iEbW2PgHjPWvTJYNQXRlgtbuH7eI1X7TPCWUtwCxQEZ7nGRVj7Vb/894/++xR9qt/+e8f/AH2KOlg3d2Y+jeFLTStVuNXmnmvdWuoxHPeS4XcoOQoRAFAHbjPqTVPUvBVlrXjldY1rT9P1C0j09beKO6hErJIJC24BlIAwRznNdJ9qt/8AnvH/AN9ij7Vb/wDPeP8A77FHVPt/X6h0a7nMah4Ok1P/AISuCWeOC21y0itomizui2xshJHA6kYAP5ViN4C1W7t3+029pDdq1sqXL6zeXhdI7mKVxtmGI8iPgDdzjnFehfarf/nvH/32KPtVv/z3j/77FC0dw6WOF1XwFd3GvapNFFFfWGrTrNNHPrF3aiIhEQjyospKPkB52nsSRipbjwLez+ExYG5jW7g1mfU4fLnliVw88jhDImHU7ZMZXofUde1+1W//AD3j/wC+xR9qt/8AnvH/AN9ijol2/T/hh/1+f+ZxmjeDb201/T9Umt7W0eKeaW5VdTuL15N0IjU+ZMoJI2gYwAAB1qHS/COv+Hb8ajpf9m3dxJ9qilguJ5IkEcl086MrhGO4B8FduD68ZPc/arf/AJ7x/wDfYo+1W/8Az3j/AO+xR1v/AFtb8hdLHAr4C1BNWnaeK3vrS7vhfSF9XvIRE+5XIFuuY5MOuQSV7ZBxmtHwn4X1XRdbkmkFvp+m+Q0Y0+0v5rmF5CwIkVJFAgwAw2JkHd7V1v2q3/57x/8AfYo+1W//AD3j/wC+xQtNv66A9ThvEnhHxDef8JLa6K+mNa+IUVpJLuWRJLdxEsZACoQykIDnIwSeDTbrwXrn2x5YJbO5tpNRuLmSxlu5oI5FkWMIzMiksybG+Qjad3UECu7+1W//AD3j/wC+xR9qt/8AnvH/AN9ihafl+X+QPU83s/hpq1vpttG11YrcWlpbCLYXMZmhu2nAIIzsIIGeo54OOV13SNQ07VU8aa3e6Lpt9DcwiO2nvHW02LFNHtacxghj57HdswMAYPWvR/tVv/z3j/77FH2q3/57x/8AfYoV0rL+tbho9/T8LHK/Dl7i40fU7+5EX+napPcRvASY5EO1QyEgEqdpwcDI571jweA9cv8ARrDQtbfT7fTrGS4lW4s53kmmaRZUUbWRQgAmJJy2cY4r0L7Vb/8APeP/AL7FH2q3/wCe8f8A32KTSaS6Wt9wJtNv1/E4lfDfimX7FLcf2PHPpVhLZ2ZSSR0naQIpkkUoNoCpnyxuyTjcKs+GPDGseDdHOjaPJYXNjHdxvBLcllk8liDMGCrguDnYehBAOMZPW/arf/nvH/32KPtVv/z3j/77FVd3v/W9xWVrEtFRfarf/nvH/wB9ij7Vb/8APeP/AL7FIZLRUX2q3/57x/8AfYo+1W//AD3j/wC+xQBLRUX2q3/57x/99ij7Vb/894/++xQBLRUX2q3/AOe8f/fYo+1W/wDz3j/77FAEtFRfarf/AJ7x/wDfYo+1W/8Az3j/AO+xQBLRUX2q3/57x/8AfYo+1W//AD3j/wC+xQBLRUX2q3/57x/99ij7Vb/894/++xQBLRUX2q3/AOe8f/fYo+1W/wDz3j/77FAEtFRfarf/AJ7x/wDfYo+1W/8Az3j/AO+xQBLRUX2q3/57x/8AfYo+1W//AD3j/wC+xQBLRUX2q3/57x/99ij7Vb/894/++xQBLRUX2q3/AOe8f/fYo+1W/wDz3j/77FAEtFRfarf/AJ7x/wDfYooAp+Hv+RY0v/rzh/8AQBWjRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFYOlf8AHtP/ANflz/6PeiigC7RRRQBasv8Aj1H+83/oRqeiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKACiiigAooooAKKKKAP/Z)

Figure 14 code generation analysis

Using the code generation tool, we were than able to generate the C code, as it’s possible to verify from the report generated after that:

![Immagine che contiene screenshot

Descrizione generata automaticamente](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEdpb3JnaWEAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzc1AACSkgACAAAAAzc1AADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Figure 15 code generation report

# CONCLUSION

# REFERENCES

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* Wikipedia: Vector control (motor)

[Figure 1 predefined model 3](#_Toc4438090)

[Figure 2 equivalent circuit of a PMSM in the abc reference frame 4](#_Toc4438091)

[Figure 3 PMSM physical description 4](#_Toc4438092)

[Figure 4 equivalent circuit in the dq reference frame 5](#_Toc4438093)

[Figure 5 FOC scheme 6](#_Toc4438094)

[Figure 6 PI control loop 7](#_Toc4438095)

[Figure 7 motor torque and power curves 8](#_Toc4438096)

[Figure 8 aerodynamic force and power curves 9](#_Toc4438097)

[Figure 9 speed reference 10](#_Toc4438098)

[Figure 10 simulink reference speed calculation 11](#_Toc4438099)

[Figure 11 simulink load torque calculation 11](#_Toc4438100)

[Figure 12 simulink motor characterisation in the control loop 12](#_Toc4438101)

[Figure 13 purposes of the analysis 13](#_Toc4438102)

[Figure 14 code generation analysis 14](#_Toc4438103)

[Figure 15 code generation report 14](#_Toc4438104)