An Analysis of Noise Reduction in Variable Reluctance Motors Using Pulse Position Randomization

by

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Submitted to the Department of Ocean Engineering and the Department of Electrical Engineering and Computer Science in partial fulfillment of the requirements for the degrees of

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Abstract

The design and implementation of a control system to introduce randomization into the control of a variable reluctance motor (VRM) is presented. The goal is to reduce noise generated by radial vibrations of the stator. Motor phase commutation angles are dithered by 1 or 2 mechanical degrees to investigate the effect of randomization on acoustic noise. VRM commutation points are varied using a uniform probability density function and a 4 state Markov chain among other methods. The theory of VRM and inverter operation and a derivation of the major source of acoustic noise are developed.

The experimental results show the effects of randomization. Uniform dithering and Markov chain dithering both tend to spread the noise spectrum, reducing peak noise components. No clear evidence is found to determine which is the optimum randomization scheme. The benefit of commutation angle randomization in reducing VRM loudness as perceived by humans is found to be questionable.

Thesis Supervisor: Dr. John G. Kassakian

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INTRODUCTION

The variable reluctance motor (VRM) is a versatile motor that has relatively few applications today. Its major disadvantage is that it is acoustically noisy, to the point where humans often require hearing protection in the vicinity of an operating VRM. This discomfort and potential for damage to an unprotected person's hearing have severely limited the use of VRM's. This thesis explores the use of different randomization schemes on VRM switching to reduce acoustic noise from VRM's.

1.1 Background

The VRM has many advantages over other types of motors. The most obvious advantage is its simpler construction, and thus lower cost. Dc motors and ac synchronous motors require windings on the rotor, along with a commutator or slip rings. The induction motor has either windings or conducting bars on the rotor. The VRM rotor simply consists of iron laminations, without windings or bars. Thus, the VRM rotor is the most robust rotor available. In addition to the rotor, the stator of a doubly salient VRM is relatively easy to construct, since the phase windings can be mounted separately in any sequence. Doubly salient means both the rotor and stator...
have salient poles. This arrangement produces the highest torque per frame size in VRM's.[1, 2]

The VRM has other advantages over induction motors (IM), the most widely used motors today. Moghbelli conducted an analysis of VRM and IM attributes, using 10 hp motors, and found that the VRM compared favorably[1]. The most notable VRM attribute was efficiency; VRM efficiency was found to be relatively constant for 75-100% of rated load, and generally higher than IM efficiency which varied with load. Thus, the VRM produced torque efficiently and economically at various speeds and loads. In addition, the VRM can give constant power over a range of speeds, which makes it very good for traction applications[3].

The major disadvantage of the VRM is acoustic noise. It is well documented that VRM's are noisy, but this writer could not find literature specifically directed at reducing the noise. Cameron determined that the vibrations that produce the most noise are radial vibrations of the stator induced by radial magnetic forces in the motor[4,5]. Another disadvantage of the motor is that it produces a pulsating torque compared to the smoother torque of other motors[1].

In addition to the actual motor, a power controller is required for proper operation of the VRM. The control circuitry must be complex enough to synchronize the power applied to the various phases with rotor position, to ensure a unidirectional torque. The controller must determine rotor position and provide power to the proper phase. The energy conversion takes place in the inverter circuitry. Other motors do not require such complex control systems for their power electronics.
Because the VRM requires a controller, the circuitry is already present to introduce randomization into the switching pattern. The nominal switching waveform is rotor position dependent, and randomization involves varying the rotor positions where power is applied to the stator phases. Cameron demonstrated that random perturbations of these positions reduced acoustic noise[4,5]. These random perturbations prevent coherent excitation of resonant frequencies of the stator at noisy motor speeds.

There has been some literature on reducing acoustic noise using power electronic inverters for motors other than VRMs. Handley demonstrated that a dithered pulse width modulation (PWM) strategy with a PWM chopper-controlled DC motor replaced tonal noise emission with wideband noise[6]. He found that the PWM generated noise was the dominant acoustic noise source in a variable speed drive, overshadowing the contributions of bearing, fan and motor noise. The spectra of the PWM drive noise depended on the probability density function (pdf) of the dither signal, and he chose a uniform pdf to eliminate tonals. Habetler also attempted noise reduction in sinusoidal PWM by using a randomly modulated carrier[7]. His randomization involved varying the slope of the triangle carrier used to generate the sinusoidal PWM. Again, the spectral content of the applied voltage was spread, producing acoustic noise that was more pleasing to the ear.

Characterization of the randomization of a standard switching pattern was investigated by Stanković[8]. He used different pdfs in his randomization schemes while maintaining the same average duty cycle to maintain the same average power.
His work provides a unified spectral analysis of switching patterns that have a random component introduced. He also investigated the use of Markov chains to better shape the power spectra. Applying randomization techniques to an inverter and associated VRM has an effect on acoustic noise, as shown in [4], [6], and [7]. Stanković's techniques represent a new approach to motor and power electronic converter quieting, and this thesis applies some of these techniques in an attempt to demonstrate an acoustic noise reduction in VRM's.

1.2 Thesis Outline

This thesis presents the operation, hardware design, software control system and randomization techniques necessary to understand and implement Stanković's theories. Chapter 2 describes the theory of operation and characteristics of VRMs in general, along with the specific characteristics of the experimental VRM used for this research. The equation for the major source of acoustic noise, radial vibrations is the stator, is derived using Maxwell stress tensor analysis.

Chapter 3 presents the control system. Hardware operation is described in basic terms, and the reader can refer to Appendix A for specific wiring. The major facets of the controller software are described, highlighting the features of the Motorola 68332 Microcontroller Unit (MCU). Some aspects of controller design are taken from [9]. The chapter ends with a discussion of fault tolerance in VRM's and their associated control systems.

Chapter 4 introduces the terminology and theory necessary for understanding the randomization schemes applied to the VRM. Stationary and non-stationary
randomization are described, with an extended description of the ergodic Markov chain used in the experiments. A discussion of the considerations involved in choosing control signal timing is presented.

Chapter 5 presents the experimental results. First, the laboratory setup and measurement techniques are described. Then, the data is presented, showing the effect of randomization. Randomization is especially effective at a mechanical resonance of the VRM. Limitations of the research are also presented.

Chapter 6 draws conclusions about the benefits of randomization as applied to VRMs. The applicability of this research extends beyond VRMs, with applications to all power electronic motor drives.
VRM AND INVERTER OPERATION

The basic elements necessary for VRM operation are the VRM itself, an inverter, and a controller. This chapter begins by describing the construction of the VRM used in the laboratory experiments, followed by a discussion of VRM operation using lumped-parameter electromechanical energy principles. The inverter used to drive the VRM is then explained by describing a single inverter phase as a simple switching circuit with two modes of operation. Sources of acoustic noise in the VRM are described in the third section, with discussions of the mechanics of VRM construction and the effect of the inverter drive on VRM noise generation. The controller is described in Chapter 3.

2.1 VRM Construction

A VRM is constructed with a ferrous rotor that has salient poles with no permanent magnets or electrical excitation. The sole source of excitation is windings on the stator. The stator can have either concentrated windings with salient poles or
Figure 2.1 End view of the geometry of the 8/6 VRM. An example winding is shown.

distributed windings with no saliency, classifying a VRM as either doubly salient or singly salient.

The experimental 0.5-hp VRM was donated (but not manufactured) by General Electric Corporation to MIT for experimental work done by Derrick Cameron in 1989[4,5]. The stator consists of iron laminations with eight salient poles. Each pole subtends a 21° arc. The 24° of arc between poles contains the windings, with a space factor of approximately 0.8. Each pole has a concentrated copper winding, connected in series with the diametrically opposite pole's winding to form a phase. The connections are such that the fluxes are additive. The six rotor poles also consist of iron laminations. Each rotor pole subtends a 23° arc, with 37° between poles. Figure 2.1 shows an end view of the VRM.
The depth of the lamination stacks on the stator and rotor is 2 inches. The stator laminations are supported by two aluminum endbells. Holes bored in the endbells house precision thrust bearings at each end of the rotor, whose laminations are mounted on a steel shaft. For all analysis, the construction is assumed to be symmetric, with identical electrical and mechanical characteristics for each stator phase and for each rotor pole.

2.2 VRM Principles of Operation

Torque production in the VRM is the result of the tendency of rotor poles to align with stator poles to maximize the flux linkage ($\lambda$) when a magnetomotive force (mmf) is applied to the stator. Torque is produced by the tangential components of the resulting forces. The radial components of the forces cause radial deflections of the stator, which is the major source of acoustic noise in the experimental VRM[4,5]. The rest of this section describes the particulars of VRM torque production and acoustic noise.

2.2.1 VRM Dynamics

The general operation of a VRM is described by three equations:

\[ \frac{d\lambda_n}{dt} = v_n - R_n i_n, \quad n = 1, ..., N_p \]  \hspace{1cm} (2.1)

\[ \frac{d\theta}{dt} = \omega_r \]  \hspace{1cm} (2.2)
\[ J \frac{d\omega_r}{dt} = \tau_m - B_r \omega_r - \tau_f \frac{\omega_r}{|\omega_r|} - \tau_l \]  

(2.3)

where \( \lambda_n, i_n, \) and \( v_n \) are the flux linkage, current, and applied voltage of the nth phase winding, \( R_n \) is stator phase winding resistance, \( \theta \) is rotor position, \( \omega_r \) is rotor speed, \( J \) is total rotor and load inertia, \( N_p \) is the number of phases, \( \tau_m \) is magnetic torque, \( B_r \) and \( \tau_f \) are coefficients of viscous and coulomb friction, and \( \tau_l \) is load torque[4]. Flux linkage of the nth phase, \( \lambda_n \), is related to the nth phase inductance \( L_n \) by

\[ \lambda_n = L_n(\theta)i_n \]  

(2.4)

There is no mutual inductance term in (2.4) because the low reluctance of the stator makes flux linkage with other windings negligible[2].

To determine \( \tau_m \) produced by a phase, an energy/coenergy analysis is used.

Conservation of power for a magnetic system is

\[ \frac{dW}{dt} = i \frac{d\lambda}{dt} - \tau_m \frac{d\theta}{dt} \]  

(2.5)

The energy conservation law gives

\[ dW = i \, d\lambda - \tau_m \, d\theta \]  

(2.6)

where \( W \) is energy. Coenergy \( (W') \) is defined by the equation

\[ \lambda i = W' + W \]  

(2.7)

which leads to the coenergy conservation law
\[ dW' = \lambda di + \tau_m d\theta \]  \hspace{1cm} (2.8)

By holding \( i \) constant for the integration, the equation for torque becomes

\[ \tau_m(\theta) = \left. \frac{dW'}{d\theta} \right|_i = \left. \frac{d}{d\theta} \left[ \int_0^i \lambda(i',\theta)di' \right] \right|_i \]  \hspace{1cm} (2.9)

Substituting (2.4) into (2.9) and integrating yields the equation for torque from a single VRM phase

\[ \tau_m(\theta) = \frac{1}{2} i^2 \frac{dL(\theta)}{d\theta} \]  \hspace{1cm} (2.10)

Net torque of the VRM is just the sum of individual phase torques.

VRM torque depends on the magnitude of the current and the rate of change of inductance with position, and the VRM always tries to align the rotor to the position of maximum inductance. The sign of the rate of change of inductance determines the sign of the torque. To produce a unidirectional torque, the control system must ensure each stator phase is energized during the period of rising inductance, and de-energized during the period of falling inductance. This unidirectional torque can be produced in either direction, depending on the order of phase excitation, as long as each phase is energized during the period of rising inductance.

VRM torque depends on inductance, which is a function of angular position. From basic magnetics, the equation for inductance of a phase is

\[ L = \frac{\mu_0 N^2 A_c}{2g} \]  \hspace{1cm} (2.11)
where \( \mu_0 \) is the permeability of free space, \( N \) is the number of turns, \( A_c \) is the cross sectional area of overlap between the stator pole and rotor pole, and \( g \) is the air gap length. When a stator pole and rotor pole are completely unaligned, \( g \) increases to an effective gap between the stator pole and the side of the nearest rotor pole, giving a small inductance. As the rotor turns, each phase's inductance can be in one of four conditions: (1) minimum when the poles are unaligned \( (L_{\text{min}}) \), as shown in Fig. 2.2(a); (2) increasing linearly when the poles' alignment is increasing, as shown in Fig. 2.2(b); (3) maximum when the poles are aligned \( (L_{\text{max}}) \) as in Fig. 2.2(c), and (4) decreasing linearly when the poles' alignment is decreasing, illustrated in Fig. 2.2(d).

2.2.2 VRM Practical Considerations

A VRM will not operate properly if connected directly to an ac or dc power
source. Proper operation of a VRM requires a continuously active controller which energizes and de-energizes the stator phases at the proper rotor positions. Thus, a VRM requires a closed loop control system with position feedback to apply the stator mmf to each phase at the appropriate rotor position.

The direction of rotation of the VRM rotor is opposite to the direction of rotation of the stator phase excitation. If the stator phases are excited in a clockwise sequence, the rotor turns counterclockwise. Since the stator poles repeat every 45° and the rotor poles repeat every 60°, shifting from phase A to phase B forces the rotor to move only 15°. Figure 2.3 shows the phase inductance for all four phases with phase A
A aligned and then phase B aligned. For every complete revolution of the stator flux, the rotor turns only 1/3 revolution in the opposite direction.

2.3 VRM Inverter Operation

The VRM requires an inverter and control system to operate properly. VRM torque does not depend on current direction because of the $i^2$ term in (2.10). This allows the use of unidirectional current switches in the inverter. The basic inverter circuit for each phase consists of the phase winding, two field effect transistors (FET) with gate signals supplied by the controller, and two freewheeling diodes. Figure 2.4 shows a simplified circuit for one phase. Appendix A contains the wiring diagram for the inverter and all other circuitry. The inverter can be operated in two modes: normal and regenerative. This section describes the two modes of operation.
2.3.1 Normal Operation

The normal operating mode minimizes the amount of switching in the inverter. Switching accomplishes two functions: commutation between phases based on rotor position, and current chopping to maintain the desired phase current. The controller provides the current setpoint and on/off signals. The current setpoint defines a hysteresis band to maintain an average current at a user specified value. Refer to Fig. 2.4 for the following discussion of normal mode operation.

There are four possible states for the inverter:

State 1: Q1, Q2, D1, D2 off
State 2: Q1, Q2 on; D1, D2 off
State 3: Q2, D2 on; Q1, D1 off
State 4: D1, D2 on; Q1, Q2 off

Assume the initial condition is State 1 where all devices are off. At the proper position, the controller sends the ON signal, which forces State 2 by turning on Q1 and Q2. In State 2, \( v_L = v_{\text{supply}} \) is applied across the phase winding, and \( i_L \) ramps up with the relationship

\[
\frac{di_L}{dt} = \frac{v_L}{L}
\]  

(2.12)

At some point, \( i_L \) reaches the high current level defined by the hysteresis band. To prevent \( i_L \) from increasing indefinitely, the controller turns Q1 off, forcing D2 on, and the inverter enters State 3. The phase winding then begins discharging its magnetic energy by maintaining current flow through Q2 and D2. The discharge rate is again
determined by (2.12), where the induced negative $v_L$ is just the short circuit voltage drop across the two conducting devices, $Q_2$ and $D_2$. This small voltage drop allows current to ramp down slowly. When $i_L$ reaches the low current level defined by the hysteresis band, the controller sends the inverter back to state 2 by turning on $Q_1$. This current chop cycle repeats until the rotor reaches the off position, where the controller turns off $Q_1$ and $Q_2$ and the inverter enters State 4. The phase winding discharges its magnetic energy by maintaining current flow, forcing $D_1$ and $D_2$ to turn on. The induced voltage across the phase winding is $v_L = -v_{\text{supply}}$, which allows $i_L$ to rapidly ramp down to zero, at which point $D_1$ and $D_2$ turn off and the inverter returns to State 1.

The current chopping strategy used in the normal mode is called soft chopping, since only one of two transistors is switched to maintain current level. $Q_1$ and $D_2$ are called the "chop transistor" and "chop diode." $Q_2$ and $D_1$ are called the "commutation transistor" and "commutation diode" because they change state during commutation and not during current chopping. This distinction is arbitrary, because $Q_2$ and $D_1$ could do the chopping.

### 2.3.2 Regenerative Operation

The regenerative operating mode produces a higher switching frequency than the normal operating mode. Both FETs are switched together for chopping and commutation. Refer to Fig. 2.4 for the following discussion of the regenerative mode.

There are three expected states for the inverter:

State 1: $Q_1$, $Q_2$, $D_1$, $D_2$ off
State 2: Q1, Q2 on; D1, D2 off

State 3: D1, D2 on; Q1, Q2 off

Assume the initial condition is State 1 where all devices are off. As in the normal mode, Q1 and Q2 are turned on by the controller at the proper position to produce torque, and the inverter enters State 2. At the high current level, current chopping is accomplished by turning both Q1 and Q2 off, forcing the inverter to State 3. The negative voltage $-v_{\text{supply}}$ is across the phase winding, causing $i_L$ to rapidly ramp down by the relationship in (2.12). At the lower current level, the controller turns on both FETs and sends the inverter back to State 2. The two states where one FET is on and the other is off are possible due to unequal circuit delays; these cases would cause a temporary condition like State 3 of the normal mode where the phase winding discharges through one FET and one diode until the other FET responds to its gate control signal. At the turn off point, the inverter is sent to State 3 where it remains until the phase winding has discharged completely. When there is zero current through the diodes, the inverter returns to State 1 to wait for the next ON signal from the controller.

The current chopping strategy used in the regenerative mode is called hard chopping. Chop frequency is higher than in the normal mode since $i_L$ ramps down faster during chopping. The mode is called regenerative because the phase winding returns energy to the dc supply's capacitor during chopping.
2.4 VRM Acoustic Noise

A VRM is a noisy motor[1,4,5,11]. Two basic factors contribute to this noise: the doubly salient construction of the rotor and stator, and the frequency components of the phase current.

2.4.1 VRM Noise Sources

A doubly salient VRM is noisy for a very simple reason: the strong pulsating radial magnetic forces cause frame distortions which are transmitted to the surroundings as acoustic noise. A singly salient VRM is less noisy, but also produces less torque.

Cameron's experimental work showed that radial vibrations of the stator are the dominant noise source in the VRM[4,5]. Maxwell stress tensor analysis can be used
to determine the equation for the radial forces on the stator. Figure 2.5 shows the
surface used for the integration. The closed surface surrounds a stator pole, and is
conveniently chosen so that its surfaces are perpendicular to the longitudinal, radial
and tangential directions. Some reasonable assumptions simplify the derivation. The
flux in the air gap is radially directed, and uniform where the air gap is uniform. The
flux is negligible where the poles are not aligned. Fringing effects are ignored, and
the permeability, $\mu$, of the stator and rotor is infinite compared to $\mu_0$. This leaves a
component of the magnetic field intensity $H$ in the radial direction only, $H_r$.

The net force $f$ on the surface in any direction $m$ can be described by the
equation

$$f_m = \iint_{\text{closed surf}} \mu_0 (H_m H_n - \frac{\delta_{mn}}{2} H_k H_k) \hat{n} \ d\hat{S} = \iint_{\text{v}} F_m \hat{i}_m \ dV$$

(2.13)

where $H$ is the magnetic field intensity, $\delta$ is the Kronecker delta, $\hat{i}_m$ is the unit vector
in the $m$ direction, $\hat{n}$ is the outward pointing normal, and $F_m$ is the force density.

Given the above assumptions, the only nonzero force is in the radial direction, and
(2.13) simplifies to

$$f_r = \iint_{\text{closed surf}} \frac{\mu_0 H_r^2}{2} \hat{i}_r \ \hat{n} \ d\hat{S}$$

(2.14)

The normal vector $\hat{n}$ points toward the center and the unit vector $\hat{i}_r$ points away from
the center, so the dot product produces -1. The surface integral reduces to the surface
between the rotor and stator pole, with the area $dS$ equal to $A_c(\theta)$ which is the cross
sectional area of overlap between the stator and rotor poles.

26
The radial force can be related to circuit parameters by making the substitution

\[ H_r = \frac{Ni}{2g} \]  

(2.15)

where \( N \) is the total number of turns on the phase (including both poles), \( i \) is the current through the phase winding, and \( g \) is the air gap length between a stator and rotor pole. Substituting (2.15) into (2.14) yields the equation for the radial force on the stator pole

\[ f_r = -\frac{\mu_0 A_c(\theta) N^2 i^2}{8g^2} \]  

(2.16)

The result of (2.16) is that the stator poles are pulled toward the rotor when that phase is energized. Cameron's experimental results show that the net deflection is on the order of a micron for the experimental VRM used in this thesis. The modes of vibration also affect the acoustic noise. Three modes of mechanical resonance in the acoustic range exist for the experimental VRM: single ovalization at 2604 Hz, double ovalization at 9200 Hz, and a uniform expansion/contraction or breathing mode at 14200 Hz. Figure 2.6 shows the three modes.

2.4.2 Inverter Drive Contributions to VRM Acoustic Noise

The inverter control strategy used to drive the VRM also affects acoustic noise emissions. In broad terms, the frequency of the applied signal excites mechanical frequencies of the stator to produce noise. From (2.16), \( i^2 \) is a factor in determining the magnitude of the radial vibrations of the stator. Current is supplied to the VRM by the inverter, so the inverter must have an effect on stator vibrations and hence
Figure 2.6 Stator vibration modes. Dashed lines show the deformations (not to scale). (a) Single ovalization of the stator. (b) Double ovalization of the stator. (c) Breathing mode of the stator.

acoustic noise. If the inverter coherently excites the stator's resonant frequency, the acoustic noise will be higher. The other variable is the sensitivity of the human ear; frequencies out of range of human hearing are not troublesome, while frequencies near the average ear's maximum sensitivity in the vicinity of 3kHz are of considerable concern.

The major contribution of the inverter drive to VRM acoustic noise comes from the current commutation frequency. For the 8/6 VRM, the fundamental frequency of each phase is 6 times the rotor speed. Each phase commutates on and off for each rotor pole passage, thus with 6 rotor poles a stator phase winding undergoes 6 current fundamental periods per revolution. The fundamental mechanical excitation of the VRM as a whole occurs at 24 times the rotor's rotational speed (6 poles x 4 phases). The use of unidirectional current switches gives double the excitation frequency of
Figure 2.7  (a) Plot of current vs. time (position) during the time a phase is energized. The scale is exaggerated for clarity to show the decrease in frequency as inductance increases. (b) Plot of inductance vs. time during the same period.

Experiments on an 8/6 VRM have shown that, although the predominant noise peak always occurred in the same frequency band regardless of speed or load, lower levels of noise did occur at 24 times the speed. The predominant noise peak corresponds to a mechanical resonance of the stator. Additional noise components were observed at integer multiples of the fundamental pulse frequency[10].

Another contribution of the inverter drive to VRM acoustic noise is the current chop frequency. This frequency is significantly higher than the commutation frequency, with the regenerative mode producing a higher frequency than the normal mode. It must be noted that the current chop frequency is not a constant. From (2.12), the time derivative of $i_L$ is inversely proportional to phase inductance for a given $\nu_L$. Since $L$ is a function of position, and increases while the phase is energized
and pulling the rotor pole into alignment, the instantanteous chop frequency decreases as pole overlap increases. Figure 2.7 illustrates the changing chop frequency with increasing inductance. If the switching frequency of the inverter during current chopping is in the audio range, as in the laboratory setup, then current chopping also contributes somewhat to acoustic noise.

Some research has attempted to quantify the contribution of an inverter to motor noise. In general, non-sinusoidal voltages applied to a motor's phase winding produce higher acoustic noise than sinusoidal voltages produce[12,13]. These non-sinusoidal voltages produce harmonics which excite different modes of stator distortion. Much of the research comes to the same conclusion: when a harmonic of a non-sinusoidal phase voltage coincides with a spectrum component of the electromagnetic noise produced by the motor at a natural frequency of the stator, a high noise level results[12,13,14]. Based on this research, the inverter drive plays an important role in determining motor acoustic noise.

The work in this thesis investigates acoustic noise generated from commutation of the stator phases. This noise is in the range of human hearing. At a rotor speed of 5000 rpm the fundamental frequency of the VRM is 24 times higher at 2 kHz. Several harmonics of the commutation frequency also fall within the range of human hearing. The contribution of current chopping and the inverter to acoustic noise is also a consideration, even though it is at a lower dB level than the commutation noise. Its frequency, which is a function of supply voltage, phase inductance, and chopping method, could possibly be more annoying to the human ear than commutation noise.
There is some evidence that soft chopping produces less acoustic noise than hard chopping. There is also some evidence that using voltage pulse width modulation (PWM) instead of current chopping produces quieter operation[11]. All experiments in this thesis were conducted using hard or soft current chopping.

There are many potential benefits of a reduction in a motor acoustic noise through randomization, and there is more research to be done. If a VRM or any other motor can operate quieter through changes in its control system, there is no need for an expensive mechanical redesign. Another solution to noise problems in use today is increasing inverter switching frequency, which increases switching power losses. This thesis demonstrates the effects of randomization of the commutation points on acoustic noise.
The controller for the VRM laboratory setup incorporates hardware and software to send the appropriate signals to the VRM inverter. The main element of the control system is the Motorola 68332 Microcontroller Unit (MCU). It performs real-time calculations to implement randomization schemes based on user input. The MCU and controller hardware provide ON and OFF signals to inverter FET gate circuits, thus controlling VRM phase currents and torque.

The necessity of position feedback and current chopping for proper VRM operation is described in Chapter 2. The control system for the VRM uses two feedback loops to accomplish these functions. A digital outer loop provides the commutation ON and OFF signals, while an analog inner loop regulates the phase currents for the active phases. In the outer loop, MCU software determines the ON and OFF points for each stator phase using position feedback from the VRM via an optical shaft encoder. An IBM XT personal computer provides a user interface to the MCU. Figure 3.1 shows a block diagram of the major components of the VRM
Figure 3.1 Block diagram of the VRM laboratory setup including inverter, control system and user interface.

laboratory setup. Appendix A contains circuit wiring diagrams. The rest of this chapter describes the elements that form the control system.

3.1 Optical Shaft Encoder

A Hewlett Packard HEDS-5000 optical shaft encoder provides the position feedback necessary to determine rotor position. The stationary body of the encoder is mounted on a plate which stands off 2 inches from one end of the VRM. A code wheel is mounted on the rotor shaft, and positioned inside the body of the shaft encoder. Figure 3.2 shows the mounting of the shaft encoder. The shaft encoder uses three light emitting diodes (LEDs). Collimated light from the LEDs passes through slots in the code wheel to photodiodes, which produce three output signals called
channels A, B, and I. The LEDs and photodiodes for Channel A are offset from those for Channel B, while sharing the same slots, to produce square wave outputs in quadrature (phase difference of 90 degrees). Although it is possible to produce 800 pulses per revolution from the 200 mechanical slots in the code wheel by a logical XOR of channels A and B, only 200 pulses per revolution are used, as explained in Section 3.2.1.

The best angular resolution from the shaft encoder of 0.45 mechanical degrees per revolution was considered too low to allow a variety of randomization schemes.\(^1\) Because the range of increasing inductance for each phase covers only 21 mechanical degrees, variations of ON and OFF points up to only 2 degrees were permitted.\(^2\) The best shaft encoder resolution would allow only five possible states for a 2 degree variation. Code wheels with more slots were available, but a better solution was to use MCU features which provided a much greater resolution. Section 3.2.1 describes how the MCU further divides the position count to achieve high resolution. An MCU limitation only allows the use of one channel for position count. Channel A is not used, and Channel B gives a position count resolution of 1.8 mechanical degrees from the shaft encoder.

Channel I, the third output channel from the shaft encoder, is an index signal which produces a pulse only once per revolution. It uses slots at a different radius

\(^1\)360 deg/rev * 1 rev/800 slot

\(^2\)Uniform variation of the ON point by only 2 degrees from the nominal ON point would reduce average torque by about 5% (1 degree/21 degrees) for a given current level. Chapter 4 describes this in more detail.
than those for channels A and B. By resetting the cumulative pulse count from channel B to zero every time an index pulse is detected, correlation is achieved between rotor position and pulse count. The pulse counts corresponding to alignment of each rotor pole with each stator phase were determined using a separate circuit containing an up/down counter with a reset. The phases were energized one at a time, the rotor was moved to the six positions of maximum alignment for the phase, and the count recorded. The unaligned positions were determined from the aligned positions and motor geometry, because the unaligned positions are positions of unstable equilibrium.
3.2 Motorola 68332 Microcontroller Unit (MCU)

The MCU used in the laboratory setup is part of a promotional evaluation system developed by Motorola, the Motorola 68332EVS. It sits on a platform board that contains the MCU, one parallel and two serial RS-232 compatible input/output (I/O) ports, 32k x 16 bit random access memory (RAM), 64k x 16 bit erasable programmable read only memory (EPROM), and convenient pinout logic analyzer connections that fit standard connectors. The assembler and In Circuit Debugger (ICD) used in controller development were provided by P&E Microcomputer Systems, Inc., of Woburn, Massachusetts.

The MCU contains separate stand-alone modules which provide functions that facilitated design of the control software. These modules operate independently, simultaneously with the Central Processor Unit (CPU). Most of the MCU's modules were not used in the final design. The Serial Control Interface (SCI) allows communication between the MCU and IBM XT via an RS-232 connection using communication interface software contained in the ICD. The time-related requirement for randomization was fulfilled by using the Time Processor Unit (TPU). This module provides the phase commutation signals and is described in the next section. References [15]-[17] are reference manuals for the MCU.

3.2.1 Time Processor Unit Operation

The TPU contains 9 separate timing functions for control of external devices. These functions can be programmed on any of the 16 available TPU channels. Two functions of the TPU are used to produce the phase commutation signals. Channel 0
uses an input signal derived from the shaft encoder, and operates in the Period Measurement with Missing Transition Detection mode (PMM). This function mode allows measurement of the pulse period between normal, regularly occurring input transitions. Pulses from the shaft encoder provide the single input signal, with channel B and channel I signals logically NANDed to produce a regular pulse train with a missing transition once per revolution. This missing transition allows the TPU to determine its position every revolution and at startup. The TPU module is designed for angle-based engine control, and with appropriate software can be used to implement myriad randomization schemes.

The critical parameter for the TPU is the pulse period, which is 1/200th of a revolution. Each pulse period represents 1.8 mechanical degrees, with 199 pulse periods and one missing transition per revolution. The pulse period measurement is a 23 bit count of clock cycles between shaft encoder position pulses, stored in register TCR1. A separate register (TCR2) counts shaft encoder position pulses from 0 to 198, and resets whenever the missing transition is detected. The missing transition is detected by a delay between input pulses, with the delay trigger set in software to 1.5 pulse periods. The previous pulse period is always used for calculations, allowing the MCU to respond accurately to speed changes and speed ripples.

Eight TPU channels are used to produce the ON and OFF signals for the four stator phases. Channels 1 through 8 operate in the Position-Synchronized Pulse Generator (PSP) mode. Once initialized and synchronized to the input pulse sequence, the PSP function continually generates output pulses based on ANGLE and RATIO
parameters. For each PSP channel, ANGLE is the position count corresponding to the ON (or OFF) point. The ANGLE register has only 8 bits, which makes 256 the maximum allowed number of pulses per revolution. For this reason, only 200 of the 800 possible pulses per revolution from the shaft encoder were used for position count.

Each PSP timing function uses a fractional multiply to resolve position down to a precise angle. RATIO holds the value for calculating a fraction of a pulse period for ON and OFF point angle resolution. When the count in TCR2 matches the position indicated by ANGLE, RATIO is used to determine when the channel should output a control signal pulse. The 8 bits in RATIO divide two pulse periods into 256 positions, using the previous pulse period measurement from TCR1. This fractional multiply increases resolution to 1/128 of 1.8 mechanical degrees, which is sufficient to implement randomization schemes. The PSP output pulses are sent to a flip-flop whose output controls phase commutation. The duration of the control signal output pulse from a PSP channel is one pulse period, and the signal is used to PRESET or CLEAR a D flip-flop. The flip-flop stores the phase's commutation state.

Each phase of the VRM is turned on and off six times per rotor revolution, as discussed in chapter 2. Thus, ANGLE and RATIO parameters for each phase's ON and OFF points are updated six times per revolution. Nominal ON and OFF points are stored in a table in the controller software. Randomization schemes are implemented on a real-time basis by adding to or subtracting from the nominal ON and OFF points for each phase, and placing the values in the ANGLE and RATIO registers while the phase is off.
3.2.2 Software Development

The software used in the control system was developed using the ICD, which allows parallel communication between the MCU and IBM XT for downloading programs and debugging. A separate serial communications cable allows user interface with the MCU by using the IBM XT as a dumb terminal. Appendix B contains a program listing of all MCU software.

The hardware features of the MCU TPU described in section 3.2.1 minimize the operations that the software has to perform. The MCU clock rate of 16.78 MHz is high enough that the 24 sets of calculations required for randomization of the ON and OFF points for all phases each revolution can be accomplished in real-time. Calculations for a phase's subsequent ON and OFF positions are conducted during the opposite phase's ON period. The calculations are initiated by TPU generated interrupts. Phases A and C are opposite, as are phases B and D. Randomization schemes and the timing sequence of the phases are described in chapter 4.

Software is used to allow user input to the MCU. In the initialization routine, the MCU prompts the user to select which pre-programmed randomization scheme to use. Choices are described in Chapter 4. The control software is designed such that the laboratory setup is a general test bed for applying randomizations schemes. Additional randomization schemes can be inserted with minimal effort.
3.3 Controller Hardware

Controller hardware consists of two separate circuit boards, which combine to send signals to the FET gate drivers on the inverter board. The MCU interface board’s sole purpose is to provide electrical isolation between the MCU and other hardware. The inverter controller board is a modification of the current-mode controller hardware developed by Cameron[4]. Phases A and C share much of the same controller hardware, as do phases B and D, which reduces the amount of hardware required. This arrangement is possible since opposite phases are never on at the same time.

3.3.1 MCU Interface Board

The MCU interface board provides electrical isolation between the MCU and logic/analog circuitry on the Inverter Controller board. It uses Darlington optocouplers, which have a relatively fast response time of 40 nsec.

Signals that could be defined in software were eliminated in the late stages of design to minimize the number of optocouplers. In the initial design, an eight bit digital to analog converter allowed setting the current chop level through the user interface to the MCU. Electrical isolation would have required eleven optocouplers, and was not cost effective. The eight TPU channel signals are coupled from the MCU to the Inverter Controller, and the index signal and PMM signal are coupled from the Inverter Controller to the MCU.

3.3.2 Inverter Controller Board

The inverter controller board contains the shaft encoder connection to the VRM, current chopping and commutation hardware. It produces the gate control
signals for the FET gate drivers. It uses a sampled hysteresis control scheme to control motor phase current. The feedback loop for current chopping is composed of analog hardware. Linear Hall effect sensors are used to detect motor phase currents. Opposite phases share Hall effect sensors and current chopping circuitry. Each hall effect output is a voltage level, which represents current level feedback from the VRM. Inverter mode is set to normal or regenerative with a toggle switch. The current chop setpoint is determined by a potentiometer.

Eight outputs from the MCU TPU channels configured for the PSP function are sent to the MCU interface board. These signals either preset or clear the flip-flop for the proper phase. The four outputs from these flip-flops are the phase commutation signals, where a logical 1 means ON and a logical 0 means OFF. These commutation signals are combined with the current chopping signals to control the FET gate drivers.

Current chopping is achieved by comparing the present current level to the setpoint. The output of the Hall effect sensor with zero current through it is nominally 6V. The current setpoint reference level is set to match the Hall effect sensor zero current output voltage using a potentiometer. Current chop level is set with a second potentiometer, with a voltage scale of 0.24 volts/amp to match the sensitivity of the Hall effect sensors. The current chop level is added to the current setpoint reference level to produce the voltage necessary to cause current chopping. Actual current level and inverted current setpoint signals are summed and sent via buffer stages to a flip-flop. At the current limit, the flip-flop input is pulled low, and the next inverter controller clock pulse places a logic 0 at the output to turn off the appropriate FETs.
As current falls, and Hall effect sensor voltage falls below the setpoint voltage, the Schmitt trigger output changes to set the flip-flop. The Schmitt trigger hysteresis band represents 0.2amps. Flip-flop clock frequency is set to 30 kHz. Flip-flop output is logically combined with the mode and commutation signals to send the appropriate ON and OFF signals for each FET to the inverter board.

The Inverter Controller gives a FET an ON (OFF) signal when three conditions are met: (1) the commutation signal from the microprocessor indicates the phase should be on (off), (2) the current chop circuitry indicates the current is below (above) the setpoint, and (3) the mode control switch indicates the FET should be turned on (off).

### 3.3.3 Inverter Board

The inverter board contains the 4 phase inverter circuits described in section 2.3, gate drivers for the FETs, optocouplers for electrical isolation, and the Hall effect sensors. One IR2110 gate driver per phase provides gate signals to the low and high side FETs. Each gate driver has a floating power supply for the high side FET. The optocouplers between the Inverter Controller board and Inverter board give the VRM circuitry a third separate ground. Thus, power ground is separated from logic ground which is separated from MCU ground.

The IR2110 is very sensitive to inductance in its output circuit. In the initial layout of the inverter board, leads between the IR2110s and the FETs were too long and placed too much inductance in the gate signal path. When an IR2110 received an ON signal from the inverter controller board, it tried to produce a 15V gate signal.
This step change in voltage caused ringing, and the oscillation triggered an undervoltage lockout in the IR2110 which reset the gate signal to zero and turned off the FET. This problem was solved by four changes to the initial inverter design: 1) The inverter board was rewired and the IR2110s physically placed very close to the FETs to minimize lead inductance. 2) Gate resistors were added to damp LC oscillations during turn-on, with parallel diodes for quick turn-off. 3) Tantalum and ceramic disk capacitors in parallel were placed across the low and high side IR2110 power supplies for better high frequency response. These capacitors were physically placed very close to each IR2110. 4) Each high side voltage source was changed from a bootstrap capacitor to a transformer with rectifier.

3.4 Fault Tolerance

The fault tolerance of the VRM and its associated controller is considered high compared to that of other motor drives for a couple of reasons[11,18]. First, the power electronics for each phase are completely independent from the power electronics for all other phases. The VRM can still produce torque with a fault in one or more phases if the rotor's inertia allows the rotor to rotate through the position where the faulted phase or phases would be the only source of torque. Operation would be degraded because of an increase in torque ripple.

Inverter design plays a role in VRM fault tolerance. In ac inverters used in other motor drives, the high and low switches (FETs or some other device) are connected in series between the dc supply's low and high rails. A fault which shorts a
switch also shorts the dc power supply when the other switch turns on. In the VRM’s inverter, a shoot-through path does not exist with a switch failure because a stator phase lies between the switches. A short circuit fault in the high or low switch places dc supply voltage across the phase winding without affecting power to the other phases. Separate fuses for each phase ensure that the other phases can continue operation in the event of a short circuit fault in one phase, of one FET in the normal mode or both FETs in the regenerative mode.

Another reason for the VRM’s high fault tolerance is the lack of rotor excitation. The rotor does not follow a rotating mmf that produces torque as in an ac motor. If there is a fault in one phase, the other phases continue to operate unaffected. Because the rotor has no field winding or permanent magnet, there is no generated voltage induced in a stator phase when it is open-circuited[11,18].
The use of various randomized switching functions and their effects on power electronic converters and motor drives has been the topic of much recent research[6,7,8,19]. This thesis quantifies the effect of several different randomization schemes on the acoustic noise produced by an experimental VRM. A common framework for applying randomization schemes is presented in this chapter. Terminology and definitions provided in this chapter are used in Chapter 5 to describe the experimental results.

4.1 Commutation Points

The position feedback of the controller described in Chapter 3 provides the commutation signals at the ON and OFF points. When a phase is on, it produces unidirectional torque and its current is limited by the current chopping hardware. When a phase is off, it does not contribute to torque.

4.1.1 Nominal Timing Between Phases

In the 8/6 VRM used in the experiments, at least one phase is always energized
Figure 4.1 Nominal timing relationship between the control signals for the four phases.

while the VRM is operating. Two phases are energized at the same time during an overlap period. Only one phase is energized 60% of a revolution, and two phases are energized for the other 40% of a revolution. Figure 4.1 shows the nominal timing relationships between the four phases.

Note that phases A and C are opposite; only one of them is energized at a given time. Phases B and D are also opposite. Angular separation between the OFF point of one phase and the ON point of its opposite phase is nominally 9 mechanical degrees. This separation allows randomization of both ON and OFF points without energizing opposite phases at the same time. If dc supply voltage is relatively low and the current setpoint is relatively high, the discharge rate of a phase at the OFF point
could be slow enough that opposite phases have non-zero current flow at the same time. This is undesirable for two reasons: 1) the phase turning off is producing negative torque, and 2) the shared Hall effect sensor could cause the on phase's current to chop at less than the current chop setpoint because of the addition of the current from the phase turning off.

4.1.2 Nominal ON and OFF Points

A simplified description of VRM operation is presented in Section 2.2. In Fig. 2.7, the nominal ON point is shown at the transition between the unaligned position and the region of increasing overlap of the stator and rotor poles. However, there are other considerations which give more desirable relative positions for the nominal ON and OFF points.

The nominal ON point has a significant effect on torque, but can have a small effect on acoustic noise. To understand this, suppose that phase A is off and all rotor poles are in the unaligned position with respect to phase A. Inductance for phase A is minimum per the discussion in Section 2.2. The major source of acoustic noise, as discussed in Section 2.4, is radial vibrations of the stator. The radial force which causes these vibrations, from (2.16), is inversely proportional to the square of the air gap length ($g^2$). Thus, when the phase A is not aligned with any rotor pole, energizing it would not produce any significant radial force. Phase A could be energized at any point while it is unaligned without contributing any significant acoustic noise.

Continuing with the phase A example, if phase A is turned on while it is in the unaligned position, its low inductance forces a high rate of current rise based on
When a rotor pole begins overlapping phase A, current could already be chopping, which would allow maximum torque production per (2.10).

The case for the nominal OFF point is basically the opposite of the case for the ON point. Current through the phase when inductance is maximum (at the position of maximum alignment) does not contribute to torque. If current is still present when pole alignment starts decreasing from maximum, a negative torque is produced. Additionally, the larger inductance at maximum alignment gives a longer time constant (L/R), which could also contribute to phase current being present when alignment starts decreasing. This was observed during initial experiments with low voltage (30V), high current (4A) and no mechanical load on the VRM at approximately 1500 rpm. When the current chop level was decreased, with no change to voltage or controller operation, VRM speed increased.

Current through the phase at maximum alignment affects acoustic noise, because the radial force on the stator is at its maximum value. When the phase is turned off, the radial force decreases as current falls, which contributes to stator vibration. There is experimental evidence to support the conclusion that the OFF point transient produces more acoustic noise than the ON point transient or current chopping[20].

The optimum case for the ON point which gives maximum torque production and minimum acoustic noise is to have the ON point during the unaligned position, allowing current to begin chopping by the time inductance starts to rise as the poles begin aligning. Randomizing the ON point in the unaligned position has little effect
on acoustic noise because of the small radial forces. Randomizing the ON point over a range of increasing alignment decreases the power delivered by the phases.

The optimum case for the OFF point is to turn the phase off while the stator pole is completely overlapped by the rotor pole, and early enough that phase current has enough time to decrease to zero before pole alignment starts to decrease. Randomizing the OFF point varies the spectral content of the stator vibrations, and the effects on acoustic noise are described in Chapter 5. For the reasons discussed above, most of the randomization schemes involve dithering the OFF point. References [11] and [21] further discuss these issues.

4.2 Randomization Terminology

A standard terminology is introduced here to allow comparisons between the different randomization schemes. The terminology used is taken from [8], [22] and [23]. All randomization schemes begin with the same information, the nominal ON and OFF points for each phase. How these ON and OFF points are changed during randomization defines the type of randomization.

4.2.1 Waveform Description

All the randomization schemes used in the experiments are periodic, with the period for each phase equal to 1/6 of the time per revolution. If one makes the simplifying assumption that torque ripple is negligible, the period is equal to the time between successive nominal ON (or OFF) points. The start of each period is referenced to an arbitrary point in the cycle such that the phase control signal's 0-1
transition at the ON point and 1-0 transition at the OFF point are completed somewhere in the middle of the period.

Three parameters are necessary to describe the basic switching cycle. Figure 4.2 shows their temporal relationship during an arbitrary $i$-th cycle. Let $T_i$ be the duration of the $i$-th cycle. The position of the ON point in the $i$-th cycle is given by $e_i$, and the on-time is given by $a_i$ (the time between the ON and OFF points). This gives a duty ratio $d_i = a_i/T_i$. These definitions are rigorous for the phase control signals, but are only an approximation of the current waveform. Each control signal transition defines a phase commutation ON or OFF point, but does not show the current chopping that occurs between the ON and OFF points. Chopping is influenced by the hysteresis set in the controller hardware. Only the timing of the ON point and OFF point are well-defined, because the rise and fall times of current during
commutation and chopping are variable. Randomization schemes tested in this thesis only alter the commutation points; the current chop hysteresis band is not changed.

In general, $e_i$, $a_i$, or $T_i$ can be dithered, either individually or simultaneously. Randomization schemes in the experiments do not explicitly attempt to dither $T_i$, although dithering of $T_i$ is unavoidable to some extent because of torque ripple in the operation of the VRM. Combinations of $e_i$, $a_i$, and $T_i$ used in the experiments are described in the next paragraph.

The randomization schemes are described by the effect of dithering on $e_i$ and $a_i$, ignoring the inevitable changes in $T_i$ with torque/speed ripple. The titles with defined acronyms use standard terms in literature.

- Random pulse width modulation (PWM): $e_i$ fixed, $a_i$ changes.
- Random pulse position modulation (PPM): $e_i$ changes, $a_i$ fixed. The ON and OFF points are varied by the same amount.
- Random ON modulation: $e_i$ varies, $a_i$ varies such that $e_i + a_i$ is a constant and the OFF point occurs at the same point in each $T_i$. The opposite case for varying the OFF point is PWM.

PWM, PPM and random ON modulation are lumped under the heading pulse randomization, because a standard term to describe all possible combinations does not yet exist in the literature. Randomization is also classified by different categories, which are described in Section 4.2.2.

4.2.2 Categories of Randomization

The randomization schemes used in the experiments fall into two categories:
stationary and non-stationary. Stationary means two things in terms of probability: 1) the nominal ON-OFF pattern being dithered does not change from cycle to cycle, and 2) each new cycle is independent of the previous cycle. Thus, both the deterministic and probabilistic structures are constant in time. Using a fair coin (or any coin with fixed probabilities) to choose between two values for dithering is an example of a stationary randomization scheme.

All stationary schemes used in the experiments can be further classified as wide sense stationary (WSS), which gives two additional constraints: 1) the expected value of a variable $x$ as a function of time $t$, $E\{x(t)\}$, is constant and 2) the autocorrelation depends only on $\tau = t_1 - t_2$. The autocorrelation $R(\tau)$ of a periodic switching waveform $x(t)$ is defined as

$$R(\tau) = \frac{1}{T} \int_{\frac{T}{2}}^{\frac{T}{2}} x(t) x(t+\tau) \, dt \quad (4.1)$$

where $T$ is the (nominal) switching period. Autocorrelation and power spectral density are a Fourier transform pair, and are measures of the coherence of the variable $x(t)$.

In schemes that are not WSS, a "time-averaged" autocorrelation and the corresponding average power spectrum are used[22]. In this thesis, some schemes are non-stationary, which means the outcome of the randomization event is influenced by the previous outcome or outcomes. Trials are dependent, and their outcome is biased by the history of previous outcomes. In all non-stationary randomization schemes tested, ergodic Markov chains are used.

A Markov chain changes the probability density function (pdf) of the
randomization scheme for the next trial. An ergodic Markov chain is one where every possible state can be reached from every other state, and the chain is periodic. Markov chains can be understood by using a simple example. Consider the 4-state Markov chain used in the experiments for 1 degree of dither. There are only two possible outcomes from randomizing the nominal OFF point in the simple 4-state Markov chain randomization scheme. Either the OFF point is left as the nominal OFF point, representing a short commutation cycle, S, with no delay, or the OFF point can be delayed 1 degree from the nominal point, representing a long commutation cycle, L. The chain responds with the following switching policy taken from [8] and shown in Fig. 5.3:

- Either an L or S delay can be next, regardless of state history.
- The controller observes the last two delays, and if they are SL or LS, then either L or S is allowed for the next delay with probability 0.5.
- If the previous pair is LL, than a subsequent S delay receives a probability of 0.75 and another L delay has a probability of 0.25.
- If the previous pair is SS, then a subsequent L delay receives a probability of 0.75, and another S delay has a probability of 0.25.

The goal of using the Markov chain is to reduce the probability of coherently exciting a particular frequency with several sequential OFF pulses at the same delay.

4.3 Experimental Randomization Schemes

All randomization schemes for the experiments start with a uniformly
Figure 4.3 Four state Markov chain used in the experiments. Numbers represent the assigned probabilities for all possible state transitions.

distributed random 8 bit variable from the same random number generator. The 8 random bits are used to determine the magnitude of the change in mechanical position of the appropriate phase's ON and/or OFF points. In most cases the ON and/or OFF points are randomized for all phases, and in one case the points are randomized for only one phase.

4.3.1 Random Number Generation

The validity of the randomization schemes is a function of the quality of the random number generation. Computer generation of an infinite sequence of statistically independent random numbers is a contradiction in terms because an algorithm must be used. Given the algorithm, the next "random" number in a sequence is completely determined. However, it is quite possible to produce long sequences of pseudo-random numbers with a uniform distribution that passes basic statistical tests.
The random number generator used in the control system was first proposed by D. H. Lehmer in 1951, and is implemented in the controller subroutine GETRAND using the programming algorithm contained in [24]. This parametric multiplicative linear congruential algorithm produces essentially random unsigned 32 bit numbers. It is a full period random number generator, which means that it cycles through all $2^{32}$ possible combinations of bits before repeating.

The 32 random bits generated each iteration are divided into four different eight bit random numbers. In the uniform randomization schemes, these 8 bits are scaled according to the number of mechanical degrees of dithering and added to the RATIO parameter of the appropriate PSP channel (which is discussed in Section 3.2.1). In the simple Markov chain scheme, only 1 bit is necessary to determine if the next control pulse should be long or short. If the prior (2 state) Markov history is LL and the random bit indicates L should be the next commutation cycle, another trial is conducted which reduces the probability of another L signal from 0.5 to 0.25. With this simple algorithm, implementing the Markov chain is no more complicated than implementing a stationary randomization scheme.

4.3.2 Selection and Application of Randomization Schemes

The number of possible randomization schemes that can be applied is infinite. This thesis uses different randomization schemes, without a priori prediction of the results. Several factors were considered in choosing the randomization schemes. The major factor was the research carried out by A.M. Stanković in [8] and [19], which suggests the benefit of Markov-based random modulation. Also, the experience with
uniform random modulation in Cameron’s work suggests that this method should also be tested[4].

Stanković’s work concentrates on power converters, and the use of a VRM introduces some interesting challenges in implementing randomization schemes. The position feedback is a function of speed, instantaneous speed is a function of torque ripple, and torque ripple is unavoidable in the experimental VRM. In this sense, there is always a small amount of randomization in the ON and OFF points even when using the nominal ON and OFF points.

All stationary schemes in the experiments used the uniform pdf of the random number generator. Gaussian and other distributions with allowed values over a wide (or infinite) range were not used because values outside a narrow limit (such as a standard deviation) would not have produced useful torque. The control signal would have been too short to produce much torque, or too long and negative torque would have been developed. Many other pdf’s could possibly be used, but are not considered in this thesis.

The number of degrees of dithering is a tradeoff between the loss of torque with a shorter on period and the benefits of randomization in reducing acoustic noise. The maximum dither is 2 mechanical degrees, with \( E\{x(t)\} \) equal to 1 degree. Using the 21 degrees of the stator pole as a measure of the most torque that can be produced for a given current chopping level, and assuming worst case where randomization occurs during the region of increasing inductance, one can expect a reduction in power applied to the VRM of about 5%. This comes from the average loss of 1 out of 21
degrees of useful torque production per pole. To deliver the same average power to the load, chop current when using a randomization scheme would have to be increased with a corresponding increase in the magnitude of radial forces on the stator. The net result on acoustic noise depends on the spectral content of the vibrations and mechanical resonances of the stator.

The choice of starting point for dithering depends on several factors. For the ON point, the dithering takes place where the stator and rotor poles do not overlap. This minimizes the loss of torque when current is not at the chop level by the time inductance starts rising. The effectiveness of dithering the ON point in reducing noise is questionable.

The choice of starting point for dithering the OFF point is a major concern, because of the possibility of entering the negative torque region. The experimental VRM is inductance limited, with a relatively slow time constant at turn off. For this reason, the highest speed for the experimental VRM is achieved when the nominal OFF point and start point for OFF dithering are placed in the region of rising inductance.

In addition to using the different schemes defined in Section 4.2.1, the other randomization variable is the number of phases to which dithering is applied. Dithering was applied to either one or four phases. Using one phase is an attempt to quantify the acoustic effect of randomization while minimizing the variation in power delivered to the load.
EXPERIMENTAL RESULTS

This chapter describes the results of the various randomization schemes on acoustic noise generated by the experimental VRM. Six randomization schemes, in addition to the nominal control system, were tested. For clarity, they are described in this chapter by the names of their subroutines in the control system, which are always of the form DITH#. The experimental setup is described first, along with various aspects of acoustic measurements and implementation of the randomization schemes, then the results are presented in Section 5.4.

5.1 Experimental Setup

A diagram of the experimental setup is shown in Fig. 5.1. Electrical connections to the controller and inverter are described in Chapter 3. Several pieces of equipment were used to collect data. A computer, two oscilloscopes, a current probe, and sound meter collected the data and verified proper controller operation.
Figure 5.1 Block diagram of the laboratory setup, showing the VRM and load, control system components, and measuring equipment.

This equipment was in addition to the computer, microprocessor, and hardware of the controller.

Mechanical load for the VRM is provided by a DC compound machine connected to the VRM shaft with a rubber coupling and hose clamps to minimize noise transmission. DC generator armature load is held constant at 80Ω. VRM mechanical load is changed by varying excitation to a separately excited field winding in the DC machine with a variac and bridge rectifier.

5.1.1 Acoustic Noise Measurement

Noise measurements are made using a Realistic 33-2050 sound meter mounted on a tripod. A very important aspect of sound measurements is consistency, and
within each series of experiments the relative positions the VRM and sound meter are held constant. The VRM and connected dc load machine are clamped to a table, separate from all other equipment, to minimize the possibility of secondary noise. The sound meter's tripod stands on the floor.

The sound meter provides two forms of output. The first is an analog meter movement, which provides an indication of average sound level, but cannot respond to instantaneous sound levels in the audio range. Sound pressure is measured in dB relative to the internationally accepted reference pressure,

\[
p_{\text{ref}} = 2 \times 10^{-5} \frac{N}{m^2} = 20 \mu Pa
\]  

The analog meter's scale is logarithmic, from -10 dB to +6 dB relative to the center point. Seven different center points are available on the sound meter, in increments of 10 dB from 60 to 120 dB. The sound meter is always placed at a distance from the VRM such that when the VRM runs without randomization, average relative dB level is zero. This allows measurements to be taken where the meter is most sensitive to sound variations without clipping peaks and minimums.

The second form of output is voltage proportional to instantaneous sound level. This output voltage is calibrated to noise level for each series of experiments by recording voltage at a known sound level (from the analog meter) and taking the average. A computer-generated tone with programmable frequency is used for this calibration. Sound meter output is sent to a digital storage oscilloscope, which samples 4000 points at time intervals of 20 µsec (50 kHz). This sampling rate is
chosen from the available sampling rates on the oscilloscope because the frequencies
of interest are in the audio range, which extends up to 20 kHz. The sampling rate of
50 kHz is the closest available choice to twice the Nyquist frequency. Sampled data is
downloaded to a computer to allow data analysis.

Sound meter output voltage is calibrated by measuring several known sound
levels with the sound meter, then correlating dB levels read on the analog meter with
average sampled voltage from the oscilloscope. Fast response is selected (versus slow
response) on the sound meter to allow detection of all audio frequency components of
VRM noise, instead of relying on an average value.

Acoustic weighting is set to A-weighting, which has been standardized by the
International Electrotechnical Commission[25]. The human ear does not hear all
frequencies equally, and A-weighting adjusts sound meter frequency response to match
an experimentally determined equal-loudness contour for the human ear.

5.1.2 Speed Measurements

Speed measurements are made by two methods. The output of the shaft
encoder is periodic, and is used to derive the control signals for the VRM as discussed
in Chapter 3. The INDEX pulse, once per revolution, provides a direct indication of
speed. By capturing two consecutive INDEX pulses on an oscilloscope, speed can
easily be determined. Phase control signals without randomization can also be used to
determine frequency, because they occur at six times the rotation rate of the VRM.

The second method is not an exact measurement of speed, but is the method
used to ensure that the VRM sees the same load. Output voltage from the dc machine
is recorded for the case with no randomization, and used as a reference level. When randomization changes VRM speed, inverter dc supply voltage is changed until dc machine output voltage returns to the same level. Dc machine excitation is held constant throughout this process to ensure load torque is not affected. In general, when randomization provides a smaller average current (i.e. the same chop current for fewer mechanical degrees) to the VRM, inverter dc supply voltage must be increased to provide the same average power to the load.

5.1.3 Other Measurements

An oscilloscope and current probe are used to provide indication of proper controller operation. Current measurements show current chopping, and provide an indication of phase inductance because of the L/R time constant involved in changing VRM phase current. Circuit voltages are used for speed measurements, and to show timing relationships.

A measurement which is not taken is temperature. It is evident from touching the VRM that stator temperature increases during motor operation. Core loss is the major cause of the temperature rise, and is produced by two mechanisms: hysteresis and eddy currents. These losses are approximated by the relation

\[ P_{\text{core}} \propto f B^{1.6-2.0} \]  

(5.2)

where \( f \) is frequency in Hz and \( B \) is magnetic flux density in Wb[26]. From (5.2), current chopping frequency has a major effect on core loss. This core loss explains why VRM speed does not necessarily increase as inverter dc supply voltage is increased, because higher voltage gives a higher copy frequency. Conservation of
energy shows that less power is delivered to the load as core loss increases

\[ P_{\text{out}} = P_{\text{in}} + P_{\text{losses}} \]  

(5.3)

where \( P_{\text{losses}} \) are governed by (5.2) in a VRM.

5.2 Comparing Randomization Schemes

Six separate randomization schemes are used in the experiments, plus DITH0 which has no randomization. DITH0 provides a baseline for comparing the different schemes. The biggest challenge in comparing the schemes is to hold some variable constant such that the comparisons are valid. The controller software produces a random displacement, within a user-specified bound of 1 or 2 degrees, which is added to a reference. Two different methods are used to determine the reference angle. Some experiments use the nominal ON and OFF points as references, and add the random angle to the nominal angle. Other experiments use a reference angle such that the expected value of the randomized angle equals the nominal angle. For example, given a uniform pdf and 1 degree of dither, the reference angle in the second method is 1/2 mechanical degree prior to the nominal angle, because the expected value \( E\{x(t)\} \) is 1/2. This method is an attempt to maintain the same average torque without changing any other parameters. This method did not achieve its goal; experimental results using both methods show speed changes with different randomization schemes. The number of degrees of dithering is also variable. The choices are limited to one and two degrees as suggested by Cameron's research[4].
The method chosen for comparing randomization schemes is to compare dc machine output power. The separately excited field is held constant on the dc load machine, along with the armature's load resistor in each separate series of experiments. A multimeter on the output of the dc load machine measures average voltage, which is converted to power. If the voltage remains constant, average power and speed are also constant (all other factors being equal). Voltmeter readings are recorded for this comparison, along with frequency measurements from an oscilloscope.

5.3 The Experimental Randomization Schemes

The six different randomization schemes include four stationary and two non-stationary processes. DITH0, as discussed above, contains no randomization and uses the nominal ON and OFF points.

5.3.1 Stationary Randomization Schemes (DITH1, DITH2, DITH3, and DITH6)

The four stationary schemes use a uniform pdf to dither the ON and/or OFF points. DITH1 varies the ON point only, and DITH2 varies the OFF point only. DITH3 is a combination of DITH1 and DITH2; it independently varies the ON and OFF points. DITH1, DITH2, and DITH3 vary the respective ON and/or OFF points for all four phases. Each occurrence of a control pulse uses a randomized angle.

DITH6 operates only on phase A; the other three phases use the nominal ON and OFF points. DITH6 is an attempt to determine if the torque ripple and non-coherent vibrations generated from one phase are significant enough to reduce acoustic noise from all four phases.
5.3.2 Non-Stationary Randomization Schemes (DITH4, DITH5)

The two non-stationary schemes are versions of the 4-state Markov chain described in Section 4.2.2. Both dither only the OFF point. DITH4 uses the simple 4-state Markov chain with only two possible values for the OFF point. The short commutation cycle (S) uses the nominal OFF point, and the long commutation cycle (L) adds 1 or 2 degrees to the nominal OFF point based on user input.

DITH5 is a combination of uniform dithering and the simple Markov chain. The same decision process is used for S or L commutation, but an S OFF displacement from the nominal OFF commutation point can be any of 128 possible fractions from 0/128 to 127/128 of a half degree (for 1 degree of dither selected by the user) or full degree (for 2 degrees of dither). Similarly, an L OFF commutation point's displacement can be any point from 128/128 to 255/128 of a half or full degree past the nominal OFF point.

5.4 Results

The experimental results show that randomization does have an effect on acoustic noise. The data is in the form of output voltage from the sound meter. Data is collected and transferred to a computer as a series of 4000 voltage levels. These levels vary over wide range (over 1 volt) compared to the average voltage levels that correspond to dB levels on the analog meter (about 0.3 volts). Figure 5.2 shows the result of calibrating the meter, with the best-fit straight line used for voltage-dB correlation. Measured acoustic noise reduction for the various schemes is on the order
Instantaneous sound meter output voltages are analyzed using the Matlab computer program. A Fast Fourier Transform (FFT) of the data is used to provide spectral content of the meter's voltage. This instantaneous voltage does not correlate to dB levels on the meter because of the wide swings in voltage. Figure 5.3 shows an example of instantaneous output voltage and the result of the FFT analysis. The spectrum analysis shows a large peak near 1300Hz, which corresponds roughly to the fundamental mechanical excitation of the VRM as a whole, and is due to the contributions of the 4 phases and 6 poles per phase. The theory is discussed in Section 2.4.2. Measured frequency on an oscilloscope of consecutive ON signals for the same phase is about 46 Hz, which corresponds to an excitation frequency of 1100
Hz. The disparity between actual and calculated VRM fundamental frequency is assumed to be due to speed ripple and inaccuracy in measuring frequency using cursors on the oscilloscope. Speed ripple, as discussed in Section 5.1.2, could not be measured accurately. The ripple is discernable as variations in dc machine output voltage and fluctuations in sound perceived by the ear.

5.4.1 Trials

The most rigorous trials in the experiments are the equal angle trials. In these trials, the nominal ON point is changed such that the $E\{x(t)\}$ for all randomization
schemes is the same, where x(t) represents each commutation ON and OFF point. The
software always adds dithering to the nominal point, thus the nominal point is changed
for different amounts of dithering. Consider DITH0 with no dithering and DITH2
with OFF point uniform dithering. in the 1 degree of dither case, the nominal OFF
point occurs 1/2 degree sooner in DITH2 than in DITH0.

Representative trials are presented in this thesis. Equal angle trials for all OFF
point randomizations are compared. Fewer trials with ON dithering were conducted,
as discussed in Chapter 4. Results for ON dithering (DITH1 and DITH3) come from
initial trials, where the equal angle principle is not applied.

5.4.2 Spectral Plots

This section presents plots from equal angle OFF trials and initial ON trials.
Comparison of the plots (which are all presented on the same scale) supports some
generalizations. Dithering does have an effect on spectral content. Equal angle trials
consistently show that the peak frequency component (other than the dc component)
has a consistent drop from the no dither case. This tends to spread the frequency
spectrum, and raise spectral density at other frequencies. In general, the equal angle
trials show that the VRM operates at the same average speed, though with a larger
ripple. Variation of dc load machine voltage output in equal angle trials with no
separately excited field on the dc load machine is approximately 2 percent on the
multimeter. Results from initial ON dither trials do not show a consistent trend. It is
unclear whether this is due to the dithering or the significant differences in speed.
Figure 5.4 Comparison between equal angle trials at dc supply = 30V, chop current = 1.96A, 2700 rpm, scheme DITH0 no dither and scheme DITH2 with 1 degree of OFF dither.

Another significant variable in determining the randomization effectiveness is the choice of nominal ON and OFF points. In initial trials, the nominal points come from shaft encoder alignment and stationary calibration described in Section 3.1. Because of the effect of the large L/R time constant at the OFF point, these points were optimized experimentally. This optimization occurred after initial trials, which
Figure 5.5 Comparison between equal angle trials at dc supply = 30V, chop current = 1.96A, 2700 rpm, scheme DITH2 with 1 degree and 2 degrees of OFF dither.

makes the ON dither results (during initial trials) questionable.

During optimization, the dc load machine field excitation is set to a constant value, and the nominal points are adjusted while variations in load power are observed. These changes are made dynamically with a subroutine in the controller software. By moving the position of the nominal ON and OFF points back almost 6 degrees,
Figure 5.6 Comparison between equal angle trials at dc supply = 30V, chop current = 1.96A, 2700 rpm, scheme DITH4 with 1 degree and 2 degrees of OFF dither.

Load voltage increased from 11.3V to 19.2 V (an increase in output power of 189%).

Supply voltage and current chop level were not changed during this optimization.
Figure 5.7 Comparison between equal angle trials at dc supply = 30V, chop current = 1.96A, 2700 rpm, scheme DITH5 with 1 degree and 2 degrees of OFF dither.
Figure 5.8 Comparison between equal angle trials at dc supply = 30V, chop current = 1.96A, 2700 rpm, scheme DITH6 with 1 degree and 2 degrees of OFF dither.
Figure 5.9 Comparison between initial trials without equal angles and before optimizing at dc supply = 30V, chop current = 2.35A, DITH0 no dither and DITH1 with 1 degree of ON dither. DITH0 speed = 1600 rpm, DITH1 speed = 1670 rpm.
Figure 5.10 Comparison between initial trials without equal angles and before optimizing at dc supply = 30V, chop current = 2.35A, DITH0 no dither and DITH3 with 1 degree of ON/OFF dither. DITH0 speed = 1600 rpm, DITH3 speed = 1870 rpm.
5.4.3 Experimental Limitations

The operating points of most concern are mechanical resonances of the stator. The first mechanical resonance occurs at 3720 rpm based on research in [4]. This was confirmed using scheme DITH0. Unfortunately, at 3720 rpm, the overhead associated with real-time randomization calculations interferes with controller operation. There are two solutions to this problem. First, many subroutines can incorporated into one routine, eliminating the costly (in terms of time) subroutine calls and returns. While this solution would gain some speed, the problem could still remain at higher rpm within the VRM's operating envelope.

Another solution is to use the same software to produce a look-up table of randomization values. Even though this method would use a lot of memory, it would eliminate the timing limitation without forcing a restructuring of the subroutines. A final solution is to use hardware generated random values, using either counters or random bit generation chips (such as the National Semiconductor MM5437)[27].
CONCLUSIONS

This thesis is successful in showing that randomization has an effect on acoustic noise. The reduction in acoustic noise is easily seen in a spectral analysis of noise generated the VRM. In terms of human hearing, the reduction achieved in non-resonant trials is less than 1 dB. Thus, although randomization affects the noise spectrum, these experiments do not show a significant human advantage.

There are advantages to spreading the noise spectrum. In applications where signature reduction is important, such as machinery noise on naval vessels, spreading the noise spectrum can help prevent identification of the vessel by signature. These advantages are not limited to VRMs; any machine which receives energy through power electronic devices can reap the benefits of a spread spectrum.

A significant area that is not covered in this research is the behavior of the VRM at a mechanical resonance. The software that determines the amount of dithering has too many instructions and subroutine calls. When the VRM is run at the
first mechanical resonance, the program cannot complete calculations for one phase before it is time for the next phase's calculations.

6.1 Lessons Learned

Several problems during the design and initial test phase of this research have important lessons associated with them. The inductance-limited operation of the experimental VRM tended to minimize the time spent chopping current, and maximize the time for current changes at the commutation points. Randomization of the OFF points could not occur during the maximum aligned positions, because of the negative torque produced after the OFF signal. Depending on the optimum nominal OFF position, effectiveness of randomization could involve a tradeoff between the noise reduction and torque.

Noise generated by the inverter circuit is another concern. In the regenerative mode, the VRM returns energy to the power supply. Thus, during current chopping, there is a large rate of change of current (from positive to negative current chop level and vice versa) in the connections to the power supply. The induced magnetic and electric fields that result can cause noise problems. In this research, the optically isolated microcontroller's memory was affected by the aluminum plate the circuit was mounted on.

6.2 Suggestions for Future Research

The major area that still needs investigation is noise reduction at motor
resonance points. This can be accomplished with the control system software and hardware designed and successfully used during this research. Modifications to the control system to decrease computational overhead are needed to achieve the desired high speed operation. Tightening the structure of the code is probably sufficient for achieving this. Other improvements would be to use other, less computationally demanding, methods for random number generation, such as lookup tables or hardware random bit generators. It is expected that the reduction in noise from randomization at resonance would exceed the slight noise reduction achieved at non-resonant speeds with OFF point dithering. An area related to VRM resonance is load resonance. The effect of randomization on the drive motor of a load at resonance could also be investigated. Investigations of these areas may yield much more significant results with the randomization techniques implemented in this thesis.

Signature reduction through the use of randomization is another area of potential research. Waterborne noise is still the primary method used by submarines for detecting other submarines. The noise spectrum emitted by a vessel can be used for positive identification. Randomization can be used to muddle machinery noise signatures, preventing a positive identification.

The effect of randomization on machine efficiency could be part of any one of these topics. Efficiency is not addressed in this thesis. A dynamic method for analyzing efficiency would be necessary, because of the rapidly changing motor torque.
REFERENCES


APPENDIX A

Schematic Diagrams
MCU Interface Board
Inverter Controller Board
APPENDIX B

Controller Source Code
; Setup communications - define registers
CREG EQU $FFFFFF9 ; Test Submodule Control Reg
CMCR EQU $FFFC00 ; QSM Configuration Register
QILR EQU $FFFC04 ; QSM Interrupt Level Register
QIVR EQU $FFFC05 ; QSM interrupt vector register
SCCR0 EQU $FFFC08 ; SCI control register 0
SCCR1 EQU $FFFC0A ; SCI control register 1
SCSR EQU $FFFC0C ; SCI status register
SCSRLOW EQU $FFFC0D ; lower byte of SCSR
SCDR EQU $FFFC0F ; SCI data reg (lower 8 bits)

; data and ASCII characters for serial interface
CR EQU 13T ; ASCII for carriage return
LF EQU 10T ; ASCII for line feed
BS EQU 08T ; ASCII for back space (to delete)
PROMPT EQU 62T ; ASCII for >
CHSIZ EQU 06T ; Character buffer size

; pin assignment register
PEPAR EQU $FFFA17 ; Port E Pin Assignment Register
DDRE EQU $FFFA15 ; Port E Data Direction Register
PORTE EQU $FFFA11 ; Port E Data Register
PPPAR EQU $FFFA1F ; Port F Pin Assignment Register
DDRF EQU $FFFA1D ; Port F Data Direction Register
PORTF EQU $FFFA19 ; Port F Data Register

; TPU setup parameters
TMCR EQU $FFFE00 ; TPU Module Configuration Register
TICR EQU $FFFE08 ; TPU Interrupt Configuration Register
CIFR EQU $FFFE0A ; Channel Interrupt Enable Register
CFSR0 EQU $FFFE0C ; Channel Function Select Reg 0
CFSR1 EQU $FFFE0E ; Channel Function Select Reg 1
CFSR2 EQU $FFFE10 ; Channel Function Select Reg 2
CFSR3 EQU $FFFE12 ; Channel Function Select Reg 3
CISR EQU $FFFE20 ; Channel Interrupt Status Reg
HSQR0 EQU $FFFE14 ; Host Sequence Register 0
HSQR1 EQU $FFFE16 ; Host Sequence Register 1
HSRR0 EQU $FFFE18 ; Host Service Request Register 0
HSRR1 EQU $FFFE1A ; Host Service Request Register 1
CPRO EQU $FFFE1C ; Channel Priority Register 0
CPRI EQU $FFFE1E ; Channel Priority Register 1
PMCHCO EQU $FFFP00 ; PM Channel 0 CHANNEL CONTROL
PMMAX EQU $FFFP02 ; PM Channel 0 MAX_MISSING NUM_TEETH
PMMAT EQU $FFFP06 ; PMM Chan 0 RAT TCR_2_MAX
PSPPER1 EQU $FFFP10 ; PSP Chan 1 PERIOD_ADDRESS
AONREG EQU $FFFP18 ; PSP Chan 1 Ratio 1, Angle 1
ONREG EQU $FFFP28 ; PSP Chan 2 Ratio 1, Angle 1
CONREG EQU $FFFP38 ; PSP Chan 3 Ratio 1, Angle 1
DONREG EQU $FFFP48 ; PSP Chan 4 Ratio 1, Angle 1
OFFREG EQU $FFFP58 ; PSP Chan 5 Ratio 1, Angle 1
OFFREG EQU $FFFP68 ; PSP Chan 6 Ratio 1, Angle 1
OFFREG EQU $FFFP78 ; PSP Chan 7 Ratio 1, Angle 1
OFFREG EQU $FFFP88 ; PSP Chan 8 Ratio 1, Angle 1
PERIOD EQU $FFFP08 ; PSP Chan 0 PERIOD_HIGH_WORD

; Definitions for Random Number Calculations
a equ 16807T ; multiplier
m equ 2147483647T ; prime modulus
q equ 127773T ; m div a
r equ 2836T ; m mod a
SEED EQU 530559108T ; initial seed for random
BIT8 EQU $0000FF00 ; mask to isolate 8 rand bits

ORG $0400
JSR CLRTPU ; all motor phases off
BCLR.B #0,CREG.L ; prevent test submodule reset
MOV.L #00H.D0
MOVEC D0,VBR ; initialize VBR
MOVEA.L #STACK0,A7 ; initialize the stack pointer
The following INIT routines initialize the VRM program setup, entering default values and asking for changes.

INITEBI initializes the EBI, disabling external interrupts and external data and address acknowledge lines (pins are floating, and spurious signals mess up the program)

```
INITEBI MOVE.B #00, PEPAR.L ; assign PORT E pins 0, 2, 3 as I/O
MOVE.B #OFFH, DDRE.L ; assign PORT E output pins
MOVE.B #00H, PPFA.R.L ; assign PORT F pins as I/O
MOVE.B #OFFH, DDRF.L ; assign all PORT F pins as output
```

INITCOM initializes the serial communications setup.

```
INITCOM MOVE.W #0087H, QMCR.L ; supervisory access, int arbitration 7
MOVE.W #02H, QILR.L ; use SCI, int pri 2, QSPI disabled
MOVE.W #55H, SCCR0.L ; clock rate 9600 baud, @16.777 Mhz
MOVE.W #100CH, SCCR1.L ; 9600, N parity, 8 data, 1 stop, no int
```

; load interrupt vector addresses

```
MOVEC VBR, A2 ; load vector base register address
MOVE.L #AINT, ($104, A2) ; load channel 1 interrupt (A on)
MOVE.L #BINT, ($108, A2) ; load channel 2 interrupt (B on)
MOVE.L #CINT, ($112, A2) ; load channel 3 interrupt (C on)
MOVE.L #DINT, ($116, A2) ; load channel 4 interrupt (D on)
MOVE.L #STRT, ($120, A2) ; load channel 9 interrupt (STRT)
```

; initialize PMM channel 0

```
MOVE.W #0004H, PMMCHCO.L ; PMM, rise edge, use TCR1
MOVE.W #01C6H, PMMMA.X.L ; 1 miss xsit to reset TCR2
MOVE.W #0020H, (A5) ; Missed tooth if 1.5 periods
MOVE.W #0020H, (10H, A5)
MOVE.W #0020H, (20H, A5)
MOVE.W #0020H, (30H, A5)
MOVE.W #0020H, (40H, A5)
MOVE.W #0020H, (50H, A5)
MOVE.W #0020H, (60H, A5)
MOVE.W #0020H, (70H, A5)
MOVE.W #0020H, (80H, A5)
MOVE.W #01H, (90H, A5) ; chan 9 transition mode, input
MOVE.L #AONREG.A5 ; use as base reg for loading
ADDA.L #1T, A5
MOVE.W #0004H, PMMCHCO.L ; PMM, rise edge, use TCR1
MOVE.W #01C6H, PMMMA.X.L ; 1 miss xsit to reset TCR2
MOVE.W #0020H, (A5) ; all 8 PSP channels with
MOVE.W #0020H, (10H, A5) ; HIGH_TIME
MOVE.W #0020H, (20H, A5)
MOVE.W #0020H, (30H, A5)
MOVE.W #0020H, (40H, A5)
MOVE.W #0020H, (50H, A5)
MOVE.W #0020H, (60H, A5)
MOVE.W #0020H, (70H, A5)
MOVE.W #0020H, (80H, A5)
MOVE.W #0, ACNT ; initialize to first entry in
MOVE.W #0, BCNT ; the ON and OFF tables for
MOVE.W #0, CCNT ; each phase
MOVE.W #0, DCNT
MOVE.W #0, AMEM ; initialize first Markov pair
MOVE.W #0, BMEM ; to SS
MOVE.W #0, CMEM
MOVE.W #0, DMEM
```

TPUSETUP initializes the random number generator, TPU setup registers

```
TPUSETUP MOVE.L #SEED, D7 ; seed the random no gen
JSR RANDOM ; set up first random nos.
MOVE.L #4T, D4 ; init counter for random nos. left
MOVE.W #208EH, TMCR.L ; divide by 64, hi pri interrupt
MOVE.W #074CH, TICR.L ; non-maskable interrupts at vbr+64 (+4)
MOVE.W #0005H, CFSR0.L ; chan 1-8 PSP, chan 0 PMM, chan 9 DIO
MOVE.W #008CH, CFSR1.L
MOVE.W #0CCCH, CFSR2.L
MOVE.W #0CCCH, CFSR3.L
```

; show default inputs, ask for changes

```
INITPROG MOVE.L #WELCOME, A2
JSR SENDSTR ; send welcome message
MOVE.L #DITHO, A3 ; default is no randomization
```
; TPUSOCIAL only after all setup is done, and TPU is ready to go!
; Enables channels 9 and 0, so the VRM can be manually started.
; Gets PSP channels ready for enabling in STRT
TPUSOCIAL MOV.W #0001H, HSQR0.L ; PSP angle-time mode
MOV.W #5557H, HSQR1.L ; PMM count mode
MOV.W #000EH, HSRR0.L ; Init host serv 11 for DIO,
MOV.W #0AAA9H, HSRR1.L ; 10 for PSP, 01 for PMM
MOV.W #0200H, CIER.L ; chan 9 interrupt enabled for STRT
MOV.W #0, CISR.L ; int status flag
MOV.B #1, FLAG9.L ; flag to count # STRT interrupts
MOV.W #000CH, CPR0.L ; High priority for DIO for STRT
MOV.W #0003H, CPR1.L ; High priority for PMM always

;***************************
; ALLDAY is where the program sits, waiting for user input. Timing signals
; for motor control are interrupt driven. No interrupt is required for
; communications.
ALLDAY MOV.L #CMD_SUM1.A2 ; give command summary
JSR SENDSTR
CLR.L D1
JSR ONECHAR ; wait (forever) for user input,
JSR CRLF
CMP.B #88T, D1 ; then match for proper subroutine
B EQ EXIT
CMP.B #120T, D1 ; x?
B EQ EXIT
CMP.B #78T, D1 ; N?
B EQ NOMINAL
CMP.B #110T, D1 ; n?
B EQ NOMINAL
CMP.B #72T, D1 ; H?
B EQ HELP
CMP.B #104T, D1 ; h?
B EQ HELP
CMP.B #83T, D1 ; S?
B EQ SPEED
CMP.B #115T, D1 ; S?
B EQ SPEED
CMP.B #82T, D1 ; R?
B EQ RNDMIZE
CMP.B #114T, D1 ; r?
B EQ RNDMIZE
BADCHAR MOV.L #ERROR2.A2 ; not a valid character
JSR SENDSTR
JMP ALLDAY
NOMINAL JSR CHGNOM
JMP ALLDAY
EXIT JSR CLRTPU
MOV.L #EXIT_MSG.A2
JSR SENDSTR
SITHERE NOP
JMP SITHERE
HELP MOV.L HELP_MSG.A2
JSR SENDSTR
SPEED JSR SPD
JMP ALLDAY
RNDMIZE JSR SCHEME
JMP ALLDAY

; WAIT_IN is used during the initialization routine to wait for a
; 2 digit input number.
; Returns the char in D1 after echoing back to monitor. To allow
; use of backspace to delete, waitin waits for a carriage return
; before returning to the initialization routine. Upon return, the 2
; ascii number digits are in D0.
WAIT_IN MOV.L #CHBUF.A5 ; CHBUF is char buff (stack)
CLR.L D2 ; clr D2, ready to count digits
CLR.L D0 ; clr D0, ready to receive answer
WAIT1 BTST #6, SCSRLOW.L ;is RDR full? check RDRF bit
BEQ WAIT1 ;RDRF = 0, Z = 1, no input yet
MOVE.W SCSR.L, D1 ;arm SCSR clearing mechanism
MOVEQ.L #0, D1 ;clear D1
MOVE.B SCSR.L, D1 ;ascii char in D1
CMPI #BS,D1 ;is char a backspace?
BNE WAIT2 ;if no, jump
CMPI.B #0,D2 ;beginning of buffer?
BEQ WAIT1 ;if yes, wait for next char
JSR SENDCHAR ;echo backspace
MOVE.B -(A5), D1 ;pop char stack (delete char)
SUBQ.B #1T, D2
JMP WAIT1 ;wait for next char

WAIT2 CMPI #CR.D1 ;is char a carriage ret?
BNE WAIT3 ;if no, jump
JSR CRLF ;send CR, LF
CMPI.B #2.D2 ;have 2 digits been received?
BNE WAITONE ;if no - retain default value?
MOVE.W CHBUF.L, D0 ;if yes - done receiving input
JMP WAITDONE

WAITONE CMPI #0.D2
BNE WAITERR ;if equal, retain default value

WAITERR MOVE.L #ERROR3, A2 ;send error msg for wrong digits
JSR SENDSTR
JMP WAIT_IN ;try again

WAIT3 CMPI.B #2.D2 ;more than 2 digits?
BNE WAIT4 ;not full, jump
MOVE.L #FULL1,A2 ;full, get too long error msg
JSR SENDSTR
JMP WAIT_IN ;start over

WAIT4 CMPI.B #&T,D1 ;test if valid number
BGE WAIT6 ;ascii 48-57
MOVE.L #ERROR2,A2 ;if invalid, send error msg
JSR SENDSTR
JMP WAIT1

WAIT6 CMPI.B #7T,D1
BGT WAIT5
MOVE.B D1,(A5)+ ;push char onto stack
ADDI.B #1,D2 ;update digit count
JMP WAIT1 ;wait for next char

;*******************************************************************
; ONECHAR waits for and receives one ascii serial comm
; character, placing it in D1
ONECHAR BTST #6, SCSRLOW.L ;is RDR full? check RDRF bit
BEQ ONECHAR ;RDRF = 0, Z = 1, no input yet
MOVE.B SCSR.L, D1 ;ascii char in D1
JSR SENDCHAR ;echo char to screen

;*******************************************************************
; SENDSTR sends a string whose starting address is in A2. Strings end in 00.
SENDSTR MOVE.B (A2)+, D3 ;Get next char to send
BNE SENDSTR1 ;if not 00, good char, xmit
RTS

SENDSTR1 BTST.B #7T, SCSRLOW.L ;prev xmit done? check SCSR TC bit
BEQ SENDSTR1 ;TC = 0, Z = 1, xmit busy
MOVE.B D3, SCSR.L ;send char to SCSR
JMP SENDSTR ;send next char

;*******************************************************************
; SENDCHAR sends a single ascii char via serial comm. The ascii char
; to send is in D1.
SENDCHAR BTST.B #7T, SCSRLOW.L ;prev xmit done? check SCSR TC bit
BEQ SENDCHAR ;TC = 0, Z = 1, xmit busy
MOVE.B D1, SCSR.L ;send char to SCSR
RTS

;*******************************************************************
; CRLF is a subroutine that sends a carriage return, line feed
CRLF MOVE.B #CR, D3
JSR SENDCHAR ;send carriage return
MOVE.B #LF, D3
JSR SENDCHAR ;send line feed
RTS

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;***********************************************************************
;SPD determines rotor speed in rpm, by scaling the pulse period from
;TPU channel 0. RPM = [16.777/4 Mcnts/sec * 60 sec/min] / [TCR1 cnts/period * 200 period/rev]
;***********************************************************************

;***********************************************************************
;ASC_DEC converts a 2 digit ascii number in D0 to BCD which it returns
;in D1 and hexadecimal which it returns in D1. Validity of numbers
;was already checked in WAIT_IN
;***********************************************************************

;***********************************************************************
;ONEDIG retrieves a 1 digit num from the user interface, and returns it
;in hex in D1.
;***********************************************************************

;***********************************************************************
;DEC_SEND takes a 2 digit BCD number in D1 and sends it to the screen
;in tenths, in the form #.#
;***********************************************************************

;***********************************************************************
;SCHEME allows the user to change randomization schemes. This subroutine
;must be changed if a new randomization scheme choice is added.
;***********************************************************************
SCHEME2 CMPA.L #DITH2,A3 ;is current scheme DITH2?
BNE SCHEME3
MOVE.L #RMSG2,A2
JSR SENDSTR
JMP CHGSCH

SCHEME3 CMPA.L #DITH3,A3 ;is current scheme DITH3?
BNE SCHEME4
MOVE.L #RMSG3,A2
JSR SENDSTR
JMP CHGSCH

SCHEME4 CMPA.L #DITH4,A3 ;is current scheme DITH4?
BNE SCHEME5
MOVE.L #RMSG4,A2
JSR SENDSTR
JMP CHGSCH

SCHEME5 CMPA.L #DITH5,A3 ;is current scheme DITH5?
BNE SCHEME6
MOVE.L #RMSG5,A2
JSR SENDSTR
JMP CHGSCH

SCHEME6 CMPA.L #DITH6,A3 ;is current scheme DITH6?
BNE CHGSCH ;becomes SCHEME7 if added
MOVE.L #RMSG6,A2
JSR SENDSTR
JMP CHGSCH

CHGSCH MOV.E L #RANDMSG1,A2 ;change scheme?
JSR SENDSTR
CLR.L D1
JSR ONECHAR ;wait for user input in D1
CMPI.B #CR,D1 ;is it CR?
BNE CHGSCH0 ;branch if yes, change scheme
MOVE.L #RANDMSG3,A2 ;no change, say so, then leave
JSR SENDSTR
JMP ENDSCHM

CHGSCH0 MOV.E L #RANDMSG2,A2 ;send new scheme message
JSR SENDSTR
CMPI.B #48T,D1 ;is it scheme 0?
BNE CHGSCH1 ;no, try 1
MOVE.L #RMSG0,A2
JSR SENDSTR
MOV.E L #DITH0,A3 ;globally load scheme 0 address
JMP ENDSCHM

CHGSCH1 CMPI.B #49T,D1 ;is it scheme 1?
BNE CHGSCH2 ;no, try 2
MOVE.L #RMSG1,A2
JSR SENDSTR
JSR ONDITH
MOV.E L #DITH1,A3 ;globally load scheme 1 address
JMP ENDSCHM

CHGSCH2 CMPI.B #50T,D1 ;is it scheme 2?
BNE CHGSCH3 ;no, try 3
MOVE.L #RMSG2,A2
JSR SENDSTR
JSR OFFDITH
MOV.E L #DITH2,A3 ;globally load scheme 2 address
JMP ENDSCHM

CHGSCH3 CMPI.B #51T,D1 ;is it scheme 3?
BNE CHGSCH4 ;no, try 4
MOVE.L #RMSG3,A2
JSR SENDSTR
JSR ONDITH
JSR OFFDITH ;get degrees of ON dither
MOV.E L #DITH3,A3 ;globally load scheme 3 address
JMP ENDSCHM

CHGSCH4 CMPI.B #52T,D1 ;is it scheme 4?
BNE CHGSCH5 ;no, try 5
MOVE.L #RMSG4,A2
JSR SENDSTR
JSR OFFDITH ;get degrees of OFF dither
MOV.E L #DITH4.A3 ;globally load scheme 4 address
JMP ENDSCHM

CHGSCH5 CMPI.B #53T,D1 ;is it scheme 5?
BNE CHGSCH6 ;no, try 6
MOVE.L #RMSG5,A2
JSR SENDSTR
JSR OFFDITH ;get degrees of OFF dither
MOV.E L #DITH5,A3 ;globally load scheme 5 address

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JMP

CHGSCH6 CMP.I #54T,D1 ;is it scheme 6?
BNE ERRSCHEM ;no, must be error
MOVE.L #RMSG6,A2
JSR SENDSTR
JSR OFFDITH ;get degrees of OFF dither
MOVE.L #DITH6,A3 ;globally load scheme 6 address
JMP ENDSHEM
ERRSCHEM MOVE.L #ERROR5,A2 ;invalid scheme chosen
JSR SENDSTR
JMP CHGSCH
ENDSCHEM

;----------------------------------------------

;GETDITH asks for 1 digit for dithering, and the only acceptable values
;are 1 and 2. Returns answer to the screen, and returns hex dither value
;in D1.

GETDITH JSR ONE.DIG ;get # degrees of dither
CMP.I #0,D1 ;0 is unacceptable
BNE GETDITH2
DITHERR MOVE.L JSR SENDSTR
JSR GETDITH ;try again for valid digit
JMP DITHERR
GETDITH3 MOVE.L #3,D1 ;>2 is unacceptable
BLT GETDITH3 ;OK digit (1 or 2)
JMP DITHERR
GETDITH4 RTS

;----------------------------------------------

;ONDITH asks for degrees of ON dither, and places value in DITH1DEG

ONDITH MOVE.L #DITH1MSG,A2 ;ask for # degrees of ON dither
JSR SENDSTR
JSR GETDITH
MOVE.L D1,DITH1DEG.L ;store # degrees of dither
RTS

;----------------------------------------------

;OFFDITH asks for degrees of OFF dither, and places value in DITH2DEG

OFFDITH MOVE.L #DITH2MSG,A2 ;ask for # degrees of OFF dither
JSR SENDSTR
JSR GETDITH
MOVE.L D1,DITH2DEG.L ;store # degrees of dither
RTS

;----------------------------------------------

;STRT is executed twice, when the interrupt is enabled and when
;the motor is manually started. FLAG9 is used to discount the first
;interrupt, since enabling a DIO channel causes an interrupt. 2nd int
;is when the first index pulse is received. This is the only time
;channel 9 is used. It uses channel I from the shaft encoder
;as an input, and reacts to the first transit to produce the int
;which accesses this routine. The interrupt processing activates PSP
;channels 1-8, and deactivates channel 9. Forces C phase to be
;energized first (function of shaft encoder code wheel alignment).

STRT MOVE.W CISR.L,D0 ;two steps to negate
MOVE.W #0,CISR.L ;int status flag
CLR.L DO
MOVE.B FLAG9.L,D0 ;check interrupt count
BNE NOTYET ;if turn-on int, ignore
MOVE.W #001EH,CIER.L ;chan 1,2,3,4 interrupts enabled
MOVE.W #000DH,CPR0.L ;Hi pri CON, PPM
MOVE.W #00C1H,CPR1.L ;No priority for others
JMP STRTEND ;done with STRT interrupt
NOTYET SUBI.B #1,D0 ;update STRT int counter
MOVE.B D0,FLAG9.L
STRTEND

;----------------------------------------------

;CLRTPU is called during initialization and during the stop/exit
;routine. It places all 8 phase TPU channels in DIO mode, and clears
; all outputs to zero. It also cycles the OFF signals to clear all
; the hardware latches that hold the control signals. VRM HV DC supply
; to the inverter should not be energized until after this routine is called.
; to ensure that all phases are off.
CLRTPU MOV.E. #00H, CPR0.L ; turn off all TPU channels
MOV.E. #00H, CPR1.L
MOV.E. #00H, CISR.L ; disable all TPU interrupts
MOV.E. #0008H, CFSR1.L ; TPU channels 1-9 DIO
MOV.E. #8888H, CFSR2.L
MOV.E. #8880H, CFSR3.L
MOV.E. #0001H, CFSR4.L
MOV.E. #0008H, CPR1.L
MOV.E. #OFD54H, CPR0.L
CLRTPU CLR.L
CLRTPU CLR.L ; disable all TPU interrupts
CLRTPU CLR.L ; TPU channels 1-9 DIO
CLRTPU CLR.L ; set hi output on OFF channels, low
CLRTPU CLR.L ; output on ON channels.
MOV.E. #0003H, CPR0.L ; go, service 8 ON/OFF TPU channels
MOV.E. #0F54H, CPR1.L
CLRTPU CLR.L
CLRTPU CLR.L ; set lo output on OFF channels
CLRTPU CLR.L ; turn off all TPU channels
CLRTPU CLR.L
CLRTPL CLR.L DO
MOV.W HSR0.L, D0 ; give TPU time to service all
ADD.W HSR1.L, D0 ; channels
BNE CLRTPU1 ; done yet?
RTS

; CHGNOM allows changing the nominal ON and OFF points from the
; values stored in PHASETAB which holds RATIO and ANGLE parameters
; for all 8 PSP channels. This adjustment may be necessary depending
; on the accuracy of the values calculated from the shaft encoder
; placement. CHGNOM can also restore the nominal points.
CHGNOM MOV.E. #NOMMSG8, A2 ; restore nominal points?
JSR SENDSTR
JSR MODECHG
BEQ CHGNOM1
MOV.E. #AGNOM, A2 ; address of 1st nominal pt
MOV.E. #AGONTAB, A1 ; 1st address of point table
MOV.E. #24T, D1 ; counter for 24 long words
NOMBACK MOV.E. (A2)+, (A1)+ ; restore nominal point
SUB.L #17, D1 ; update countdown
BNE NOMBACK
CHGNOM1 MOV.E. #NOMMSG, A2 ; change modes? ask
JSR SENDSTR
JSR MODECHG
BEQ CHGEND
BEQ CHGNOM1 ; if no, done
ONQUEST MOV.E. #NOMMSG1, A2 ; change ON pts?
JSR SENDSTR
JSR MODECHG
BEQ OFFQUEST ; if no, change OFF pts?
ONANGQ MOV.E. #NOMMSG6, A2 ; adjust ON angle?
JSR SENDSTR
JSR MODECHG
BEQ ONRAT ; if no, adjust ON ratio?
MOV.E. #NOMMSG2, A2 ; subtract or add?
JSR SENDSTR
JSR MODECHG ; ask: y = add, n = sub
JSR MODECHG
BEQ OFFQUEST ; if no, change OFF pts?
ADDON CLR.L D1 ; set up counter
MOV.E. #AGONTAB, A1 ; load address of ONTABS
JSR ADDPT ; add 1 to ANGLE
BRA ONANGQ ; change angle again?
SUBON CLR.L D1 ; set up counter
MOV.E. #AGONTAB, A1 ; load address of ONTABS
JSR SUBPT ; sub 1 from ANGLE
BRA ONANGQ ; change angle again?
ONRAT MOV.E. #NOMMSG4, A2 ; change ON RATIO?
JSR SENDSTR
JSR MODECHG
BEQ OFFQUEST ; if no, go to OFF pt questions
MOV.E. #AGONTAB, A1 ; load address of ONTABS
CLR.L D1 ; set up counter
JSR ADDRAT
BRA ONRAT ; another 1/4 degree?
OFFQUEST MOV.E. #NOMMSG3, A2 ; change OFF pts?
JSR SENDSTR ;ask
JSR MODECHG ;get answer
BEQ CHGEND ;if no, done
OFFANGQ MOV.L #NOMMSG7,A2 ;adjust OFF angle?
JSR SENDSTR ;ask
JSR MODECHG ;get answer
BEQ OFFRAT ;if no, adjust OFF ratio?
MOV.L #AOFFTAB,A1 ;load address of OFFTABS
MOV.L #NOMMSG2,A2 ;subtract or add?
JSR SENDSTR ;ask; y = add, n = sub
JSR MODECHG ;get answer in D0
BEQ SUBOFF ;n = subtract 1 from angle
ADDOFF MOV.L #AOFFTAB,A1 ;load address of OFFTABS
CLR.L D1 ;set up counter
JSR ADDPT ; add 1 to ANGLE
BRA OFFANGQ ;change OFF ANGLE again?
SUBOFF MOV.L #AOFFTAB,A1 ;load address of ONTABS
CLR.L D1 ;set up counter
JSR SUBPT ; sub 1 from ANGLE
BRA OFFANGQ ;change OFF ANGLE again?
OFFRAT MOV.L #NOMMSG5,A2 ;change OFF RATIO?
JSR SENDSTR ;ask
JSR MODECHG ;get answer in D0
BEQ OFFQUEST ;if no, go to OFF pt questions
CLR.L D1 ;set up counter
MOV.L #AOFFTAB,A1 ;load address of ONTABS
JSR ADDRAT
BRA OFFRAT ;another 1/4 degree?

CHGEND RTS

;******************************************************************************
;ADDPT adds 1.8 mechanical degrees (1 angle) to the present
;nominial point
ADDPT MOV.W (A1),D0 ;get ratio/angle
andi.l #OFFH,D0 ;isolate angle
cmpi.b #06,D0 ;is angle 198?
bne ADDPT1 ;if angle isn't 198, no problem
mov.w (A1),D0 ;get ratio/angle
cmpi.l #8000,D0 ;if angle 198 and
bge ADDZERO ;big ratio (~"199")
br a ADDPT1 ; small ratio, can increase to "199"

ADDZERO MOV.W (A1),D0 ;since angle is 198, ratio big,
andi.l #BITSH,D0 ; set ang to zero
subi.l #8000H,D0 ;decrement ratio by 1 angle
mov.w (A1),D3 ;get original point
add.l D3,D0 ;update point
mov.w D0,(A1) ;place updated point in memory
bra ADDPT2

ADDPT1 mov.w (A1),D0 ;reload ratio/angle
addi.b #1T,D0 ;increase angle
mov.w D0,(A1) ;place updated point in memory
ADDPT2 adda.l #2T,A1
addi.b #1T,D1 ;increment counter
cmpi.b #24T,D1 ;cycled thru all 4 phase tables?
bne ADDPT

ADDEND RTS

;******************************************************************************
;SUBPT subtracts 1.8 mechanical degrees (1 angle) from the present
;nominial point
SUBPT MOV.W (A1),D0 ;get ratio/angle
andi.l #OFFH,D0 ;isolate angle
bne SUBPT1 ;if angle isn't 0, no problem
addt.l #198T,D0 ;load 198 (2 angles < 0)
addl.l #8000H,D0 ;increment ratio by 1 angle
clr.l D3
mov.w (A1),D3 ;get original point (w/ 0 ang)
add.l D3,D0 ;update point
mov.w D0,(A1) ;place updated point in memory
bra SUBPT2

SUBPT1 mov.w (A1),D0 ;reload ratio/angle
subt.b #1T,D0 ;decrease angle
mov.w D0,(A1) ;place updated point in memory
SUBPT2 adda.l #2T,A1
addi.b #1T,D1 ;increment counter
cmpi.b #24T,D1 ;cycled thru all 4 phase tables?
bne SUBPT
; *******************************************
; ADDRAT adds 1/2 degree to the nominal point by adding to RATIO.
; incrementing ANGLE if necessary. 1/2 degree = ratio of 36.

ADDRAT
CLR.L D0
MOVE.W (A1),D0 ; get ratio/angle
ADDI.L #0000H,D0 ; isolate angle
CMP.L #19BT,D0 ; compare to max # teeth
BNE ANGPT1 ; if angle isn't 198, no problem

MOVE.L (A1),D0 ; reload ratio/angle
CMP.L #000000H,D0 ; if angle 198, ratio >= 220T?
BLT ANGPT1 ; if small ratio, go increase ratio

ANGZERO
SUBI.L #8000H,D0 ; get ratio/angle again
ANDI.L #800000H,D0 ; make angle 0
MOVE.W D0,(A1) ; place updated point in memory

BRA ANGPT2

ANGPT1
MOVE.W (A1),D0 ; get ratio/angle again
ADDI.L #24000H,D0 ; ratio by 1/2 mechanical degree
CMP.L #1000000H,D0 ; test if ratio too big
BLT ANGPT3 ; if not too big

SUBI.L #800000H,D0 ; subtract 128 from ratio
ADDI.B #1H,D0 ; add 1 to angle
MOVE.W D0,(A1) ; place updated point in memory

ANGPT2
ADDI.L #2T,A1 ; increment counter
ADDI.B #1H,D1 ; get ratio/angle again
CMP.L #24T,D1 ; cycled thru all 4 phase tables?

BNE ANGEND

; *******************************************
; PHASEINT is processing for the interrupt generated by the
; PHASEON signal. PHASEINT calculates next ON and OFF points for C's
; opposite phase, phase A. A3 always holds the address of the
; randomization scheme chosen by the user. Since PSP generates
; two interruptions per evolution, after 1st, disable interrupt.
; Re-enable interrupt during opposite phase's interrupt.

PHASEINT
JSR TEMPIN ; store regs
MOVE.W CISR.L,D0 ; two steps to negate
MOVE.W #00000000H,CISR.L ; int status flag
MOVE.W #0004H,CISR.L ; prevent 2nd A int, enable B int
MOVE.W #0003H,CIER.L ; HI pri DOFF, BON, ACN, PMM
MOVE.W #003FH,CIER.L ; No priority for others

JSR ASUB ; allows init using ASUB
JSR TEMPOUT ; restore regs
MOVE.W #8080H,HSRR1.L ; immediate update of C points

PHASEINT
JSR GETONOFF ; get ratios, angles (uses A4,D0)
ADDI.L D0,CCNT.L ; store updated CCNT
ADDI.L D1,CCNT.L
ADDI.L D2,CCNT.L
ADDI.L D3,CCNT.L

GETONOFF
DO,CCNT.L
DO,CNT.L
DO,AOFF
DO,CON
DO,PM
DO,CONREG
DO,AOFFREG

BINT1
JSR TEMPIN ; store regs
MOVE.W CISR.L,D0 ; two steps to negate
MOVE.W #00000000H,CISR.L ; int status flag
MOVE.W #0006H,CISR.L ; prevent 2nd B int, enable C int
MOVE.W #0003H,CIER.L ; HI pri AOFF, BON, CON, PMM
MOVE.W #0CF3H,CIER.L ; No priority for others

JSR BSUB ; allow init using BSUB
JSR TEMPOUT ; restore regs
MOVE.W #0002H,HSRR0.L ; immediate update of D points
MOVE.W #0002H,HSRR1.L ; immediate update of D points

PHASEINT
JSR GETONOFF ; get ratios, angles (uses A4,D0)
ADDI.L D0,DCNT.L ; store updated DCNT
CLR L D1
CLR L D2
CLR L D3
MOVE.W DMEM.L,D3 ; in case Markov dither used
JSR (A3) ; call proper randomization scheme
MOVE.W D3,DMEM.L ; in case Markov dither used
MOVE.L ON.W,DONREG.L ; load D ON RATIO1/ANGLE1
MOVE.L OFF.W,DOFFREG.L ; load D OFF RATIO1/ANGLE1 address

BSUB1 RTS

CINT JSR TEMPIN ; store regs
MOVE.W CISR.L,D0 ; two steps to negate
MOVE.W #0,CISR.L ; int status flag
MOVE.W #0010H,CIER.L ; prevent 2nd C int, enable D int
MOVE.W #33C3H,CPR1.L ; Hi priority BOFF, CON, DON, PMM
MOVE.B #1,CFLAG ; set flag for CINT for DITH6
JSR CSUB ; allow init using CSUB
MOVE.B #0,CFLAG ; clear CINT flag for DITH6
JSR TEMPOUT ; restore regs
MOVE.W #0808H,HSRR1.L ; immediate update of A points

CINT1 RTS

CSUB MOVE.L #AONTAB,A4 ; address of AONTAB
JSR GETONOFF ; get ratios, angles (uses A4,D0)
MOVE.W D0,ACNT.L ; store updated ACNT
CLR.L D1
CLR.L D2
CLR.L D3
MOVE.W AMEM.L,D3 ; in case Markov dither used
JSR (A3) ; call proper randomization scheme
MOVE.W D3,AMEM.L ; in case Markov dither used
MOVE.L ON.W,AONREG.L ; load A ON RATIO1/ANGLE1
MOVE.L OFF.W,AOFFREG.L ; load A OFF RATIO1/ANGLE1 address

CSUB1 RTS

DINT JSR TEMPIN ; store regs
MOVE.W CISR.L,D0 ; two steps to negate
MOVE.W #0,CISR.L ; int status flag
MOVE.W #0002H,CIER.L ; prevent 2nd D int, enable A int
MOVE.W #03H0H,CPR1.L ; Hi priority AON, DON, COFF, PMM
JSR DSUB ; allow init using DSUB
JSR TEMPOUT ; restore regs
MOVE.W #2020H,HSRR1.L ; immediate update of B points

DINT1 RTE

DSUB MOVE.L #BONTAB,A4 ; address of BONTAB
MOVE.W BCNT.L,D0 ; get placeholder in BxTAB
JSR GETONOFF ; get ratios, angles (uses A4,D0)
MOVE.W D0,BCNT.L ; store updated BCNT
CLR.L D1
CLR.L D2
CLR.L D3
MOVE.W BMEM.L,D3 ; in case Markov dither used
JSR (A3) ; call proper randomization scheme
MOVE.W D3,BMEM.L ; in case Markov dither used
MOVE.L ON.W,BOFFREG.L ; load B ON RATIO1/ANGLE1
MOVE.L OFF.W,BOFFREG.L ; load B OFF RATIO1/ANGLE1 address

DSUB1 RTS

;******************************************************************************

TEMPIN MOVE.L D0,TEMP0.L ; store D0 value
MOVE.L D1,TEMP1.L ; store D1 value
MOVE.L D2,TEMP2.L ; store D2 value
MOVE.L D3,TEMP3.L ; store D3 value

RTS

TEMPOUT MOVE.L TEMP0.L,D0 ; restore D0 value
MOVE.L TEMP1.L,D1 ; restore D1 value
MOVE.L TEMP2.L,D2 ; restore D2 value
MOVE.L TEMP3.L,D3 ; restore D3 value

RTS

;******************************************************************************

; GETONOFF gets the nominal ON and OFF values of ratio and angle from ; the appropriate phase's tables, given ONTAB in A4, and ; CINT in D0. Updates CNT for next interrupt. Generic for any phase. ; Based on order in memory, OFF values 48 words later than ON values.

GETONOFF ADDA.L D0,A4 ; to access proper ONTAB entry
MOVE.W (A4),ON.L ;get ON ratio/angle
MOVE.W (48T.A4),OFF.L ;get OFF ratio/ang
ADDI.B #2T,D0 ;update CNT (by 2 bytes)
CMPF.B #12T,D0 ;is it at end of table?
BNE GETEND
MOVE.B #0,D0

GETEND RTS ;returns new CNT in D0

*********************************************************************

;DITH0 is randomization scheme 0, no randomization. Nominal ON
;and OFF points are used.
DITH0 RTS

*********************************************************************

;DITH1 is randomization scheme 1, uniform distribution, dithering the
;ON point only by 1 or 2 degrees as selected by the user. Scaling is
;used since pulse counts represent 1.8 degrees with the 200 slot
;code wheel. See chapter 3. The random number is 8 bits, 2 pulses,
or up to 3.6 mechanical degrees. Mult by # deg, divide by 3.6 for
;proper scaling of ratio. No dithering scheme exceeds 3.6 degrees
;of dithering, so masking with #BITS8 is valid.
DITH1 JSR GETRAND ;Put 8 random ratio bits in D5
MULU.L DITH1DEG.L,D5 ;multiply ratio by # deg
MULU.L #10T.D5 ;multiply by 10/36 to divide
DIVU.L #36T.D5 ;by 3.6
AND.L #BITS8.D5 ;isolate ratio bits after math
CLR.L D1
MOVE.W (ON),D1
JSR RATANG ;change ON point
MOVE.W D1,(ON)
RTS

*********************************************************************

;DITH2 is randomization scheme 2, uniform distribution, dithering the
;OFF point only by 1 or 2 degrees as selected by the user. Scaling is
;used since pulse counts represent 1.8 degrees with the 200 slot
;code wheel. See chapter 3. The random number is 8 bits, 2 pulses,
or up to 3.6 mechanical degrees. Mult by # deg, divide by 3.6 for
;proper scaling of ratio. No dithering scheme exceeds 3.6 degrees
;of dithering, so masking with #BITS8 is valid.
DITH2 JSR GETRAND ;Put 8 random ratio bits in D5
MULU.L DITH2DEG.L,D5 ;multiply ratio by # deg
MULU.L #10T.D5 ;multiply by 10/36 to divide
DIVU.L #36T.D5 ;by 3.6
AND.L #BITS8.D5 ;isolate ratio bits after math
CLR.L D1
MOVE.W (OFF),D1
JSR RATANG ;change OFF point
MOVE.W D1,(OFF)
RTS

*********************************************************************

;DITH3 is randomization scheme 3, uniform distribution, dithering the
;ON and OFF points independently by only by 1 or 2 degrees
;as selected by the user.
DITH3 JSR DITH1
JSR DITH2
RTS

*********************************************************************

;DITH4 is randomization scheme 4, 2 state MARKOV chain described in
;Chapter 4. A short state gives the nominal OFF pt, a long state
;gives DITH3DEG degrees of delay of the nominal OFF pt. RATIO of
;71 corresponds to 1 mechanical degree
DITH4 JSR GETRAND ;get random number
JSR S_OR_L ;get state, look at history
CMPF.B #1.D2 ;D2 is 1 if 2nd trial nec
BBQ DITH4 ;do 2nd trial if 1st LLL or SSS
CMPF.L #0.T.LSFLAG.L
BBQ DITH4END ;if S, no dither
MOVE.L (DITH3DEG).L,D5 ;get degrees of dither
MULU.L #71T.D5 ;scale dither to #degrees
ROL.L #8T.D5 ;place in ratio bits
MOVE.W (OFF),D1
JSR RATANG ;change OFF point
MOVE.W D1,(OFF)
DITH4END RTS
DITH5 is randomization scheme 5, which uses the same Markov scheme as DITH4 described in Chapter 4. Instead of 2 discrete states, a uniform distribution is used where S represents 0 to half size, and L represents half to full size of the possible dithering value. Only the OFF point is dithered. Uses the same scaling as DITH1.

```assembly
DITH5
JSR GETRAND ;get random number
JSR S_OR_L ;get state, look at history
CMPI.B #1,D2 ;D2 is 1 if 2nd trial nec
BEQ DITH5 ;do 2nd trial if 1st LLL or SSS
MULU.L (DITH2DEG).L,D5 ;multiply ratio by # deg
MULU.L #10T,D5 ;multiply by 10/36 to divide
DIVU.L #36T,D5 ; by 3.6
AND.L #BITS8,D5 ;isolate ratio bits after math
CLR.L D1
MOVE.W (OFF),D1
JSR RATANG ;change OFF point
MOVC.W D1,(OFF)
RTS
```

DITH6 is randomization scheme 6, which uniformly randomizes phase A only, using the method of DITH2. Checks CFLAG to see if this is the CINT, which processes phase A.

```assembly
DITH6 CMIPI.B #1,CFLAG
BNE DITH6END ;don't dither unless phase A
JSR DITH2
DITH6END RTS
```

S_OR_L is a subroutine that determines if the present random number is short or long, by comparing msb of the number in D5 to 1.

```assembly
S_OR_L BTST.L #15T,D5
BEQ IS_S
JSR LONGP
MOVC.B #1T,LSFLAG.L
BRA SLEND
IS_S JSR SHORTP
MOVC.B #0T,LSFLAG.L
SLEND RTS
```

LONGP is the subroutine that processes a long pulse in Markov schemes. See Chapters 4, 5.

```assembly
LONGP CMPI.B #00H,D3 ;get history state - SS?
BEQ S_L
CMPI.B #01H,D3 ;SL?
BEQ SL_L
CMPI.B #02H,D3 ;LS?
BEQ S_L
LL_L CMPI.B #1,D2 ;1st or 2nd trial?
BEQ LL_LOK ;if 2nd trial, LLL is OK
MOVC.B #1,D2 ;set flag, allow 2nd trial
BRA LONGPEND
LL_LOK CLR.L D2 ;no more trials
BRA LONGPEND ;history remains unchanged
S_L CMPI.B #1T,D3 ;history becomes SL
CLR.L D2 ;no more trials
BRA LONGPEND
SLL_L CMPI.B #1T,D3 ;history becomes LL
CLR.L D2 ;no more trials
LONGPEND RTS
```

SHORTP is the subroutine that processes a short pulse in Markov schemes.

```assembly
SHORTP CMPI.B #00H,D3 ;get history state - SS?
BEQ SS_S
CMPI.B #01H,D3 ;SL?
BEQ SL_S
CMPI.B #02H,D3 ;LS?
BEQ LS_S
MOVC.W #27,D3 ;prev SL or SS, next LS
CLR.L D2 ;no more trials
BRA SHRTPEND
LS_S MOVC.W #07,D3 ;next SS
```
**CLR.L**  
**D2**  
;no more trials

**BRA**  
**SHRTPEND**

**SS_S**  
**CMP.I.B**  
$\#1,D2$  
;list or second trial?

**BEQ**  
**SS_SOK**  
;if 2nd trial, SS_S is OK

**MOVE.B**  
$\#1,D2$  
;set flag, allow 2nd trial

**BRA**  
**SHRTPEND**

**SS_SOK**  
**CLR.L**  
**D2**  
;no more trials, history SS

**SHRTPEND**  
**RTS**

/*RATANG is a subroutine which takes D5 as RAT, the change to a  
PSP RATIO1 parameter, and D1 as the RATIO/ANGLE values for  
the given ON or OFF point. Bits 8-15 of D5 are the only bits that  
can be non-zero (i.e. a change in RATIO1). Changes are always  
in the positive direction (added). The change RAT is added  
to RATIO1, and ANGLE1 is changed if necessary. TP5 latency  
problems are ignored. The word is in the order RATIO1-ANGLE1.*/

**RATANG**  
**ADD.L**  
**D5,D1**  
;add the RATIO

**RATANG1**  
**CMP.L.L**  
#10000H,D1  
;is there overflow?

**BLT**  
**RATANG3**  
;if no, done

**MOVE.L**  
**D1,D0**

**AND.L**  
#0FF,D0  
;isolate present angle

**CMP.L.L**  
#198T,D0  
;branch if 199 not an issue

**BNE**  
**RATANG2**  
;is more overflow?

**SUBI.L**  
#10000H,D1  
;from 198 to 0 is 2 angles

**AND.I.L**  
#01FF00H,D1  
;make angle 0

**BRA**  
**RATANG1**  
;more overflow?

**RATANG2**  
**ADD.I.L**  
#1T,D1  
;add 1 to ang (won't exceed 199)

**SUBI.L**  
#8000H,D1  
;sub 128 from ratio (1.8 deg)

**BRA**  
**RATANG1**  
;check for more overflow

**RATANG3**  
**RTS**

/*GETRAND is a subroutine to get the next random number, which is left  
in D5. Incorporates RANDOM.  
;RANDOM program is a prototype for a pseudo-random number generation routine.  
;The RNG is based on the algorithm in "Random Number Generators: Good Ones  
;Are Hard to Find" by S. Park and K. Miller (Communications of the ACM,  
;Vol. 31, No. 10, pp.1192-1201, OCT 1988). Specifically, it is modeled after  
;the integer version 2 of their code, which is designed to operate properly  
;with signed integers of max val 2^31-1. The algorithm is a parametric  
multiplicative linear congruential generator with multiplier 16807 and prime  
modulus 2^31 - 1 (both base ten). proposed by D.H. Lehmer in 1952. Code  
;written by D. J. Perreault, modified by M. C. Smoot  
;8 random bits represent 2*1.8 degrees of ratio used in RATIO1 in PSP mode.*/

**GETRAND**  
**MOVE.L**  
**D6,D5**  
;D6 holds all random bits left

**AND.L**  
#BITS8,D5  
;d5 has 8 avail random bits

**SUBI.B**  
#1,D4  
;dec count of 8 bit seg avail

**BNE**  
**GETRAND1**  
;if new random no. unnecc

**BNE**  
**GETRAND2**  
;D6 holds random bits ready

**Rand:**  
**MOVE.B**  
#47,D4  
;# of sets of 8 rand bits avail counter

**DIVSI.L**  
#q,D6:d7  
;calc lo:hi (seed mod q:seed div q)

**MULS.I**  
#a,D6  
;calc a*lo --> d6

**MULS.I**  
#r,D7  
;calc r*hi --> d7

**SUB.I**  
#110T,D6  
;from 198 to 0 is 2 angles

**BLE**  
**RNDASK1**  
;test = a*lo - r*hi --> d6

**MoveI.**  
**D6,D7**  
;test >0, test --> seed

**BRA**  
**RNDASD**

**RNDASD1:**  
**Movel.**  
#m,D7  
;test <=0, test + m --> seed

**ADD.I.**  
**D6,D7**  
;d7 will have rand for next calc

**MOVE.L**  
#789T,D6  
;D6 holds rand bits (expendable)

**RDAEND:**  
**JMP**  
**GETRAND2**

**GETRAND1**  
**ROR.L**  
#8T,D6  
;if old ok, shift next 8 bits to ready

**GETRAND2**  
**RTS**

/*MODECHG waits for a 1 char input of Y (or y) for yes, ENTSR (or  
;N or n) for no. If yes, returns a 1 in D0; if no, returns a 0 in D0.*/

**MODECHG**  
**JSR**  
**ONECHAR**  
;get one character

**JSR**  
**CRLF**

**CMP.I.B**  
#CR,D1  
;check if Y or N was input

**BEQ**  
**NOCHG**

**CMP.I.B**  
#789T,D1  
;N?

**BEQ**  
**NOCHG**

**CMP.I.B**  
#110T,D1  
;N?

**BEQ**  
**NOCHG**

**CMP.I.B**  
#89T,D1  
;Y?

**BEQ**  
**YESCHG**

**101**
CMPB B #121T,D1 ;y?
BEQ YESCHG
MOVE.L #ERROR2,A2 ;invalid character
JSR SENDTR
JMP MODECHG
YESCHG MOVE.L #1,D0
RTS
NOCHG MOVE.L #0,D0
RTS

;phaseONNOM and phaseOFFNOM store the original nominal points,
determined from experiments to be the optimum ON and OFF
points. These values never change.
;phaseONTAB and phaseOFFTAB store the present
nominal values for phase ON and OFF points, dependent on code wheel
position. If code wheel is removed, these values must be reset.
;These are word values, to be loaded in RATIO1/ANGLE1 for the 8
/TPU PSP channels for each of the six rotor poles.
AONNOM DW $5CBE,$061E,$3137,$5C58,$067A,$319B
BONNOM DW $06C5,$311E,$5C3F,$0661,$3182,$5CA3
CONNOM DW $3105,$5C26,$0648,$3169,$5C8A,$06AC
DONNOM DW $5COD,$062F,$3150,$5C71,$0693,$31B4
AOFFNOM DW $1500,$4021,$6B42,$1564,$4085,$6BA6
BOFFNOM DW $4008,$6B29,$154B,$406C,$6B8D,$15AF
COFFNOM DW $6B10,$1532,$4053,$6B74,$1596,$4O7B
DOFFNOM DW $1519,$403A,$6B5B,$157D,$409E,$6BBF
AONTAB DW $5CBE,$061E,$3137,$5C58,$067A,$319B
BONTAB DW $06C5,$311E,$5C3F,$0661,$3182,$5CA3
CONTAB DW $3105,$5C26,$0648,$3169,$5C8A,$06AC
DONTAB DW $5COD,$062F,$3150,$5C71,$0693,$31B4
AOFFTAB DW $1500,$4021,$6B42,$1564,$4085,$6BA6
BOFFTAB DW $4008,$6B29,$154B,$406C,$6B8D,$15AF
COFFTAB DW $6B10,$1532,$4053,$6B74,$1596,$4O7B
DOFFTAB DW $1519,$403A,$6B5B,$157D,$409E,$6BBF

;Data space definitions
CHBUF DS 8T ;character buffer for serial comm
CURDEC DS 4T ;chop cur dec val,2 digits,1/10amp
DECSTOR DS 4T ;temp storage for DEC_SEND
MODE DS 4T ;flag for storing inverter mode
STACK1 DS 2056T ;set up superv stack space
STACK0 DS 4T ;start of stack, load in A7
TEMP0 DS 4T ;temp storage for D0
TEMP1 DS 4T ;temp storage for D1
TEMP2 DS 4T ;temp storage for D2
TEMP3 DS 4T ;temp storage for D3
ON DS 4T ;temp storage for ON word for PSP
OFF DS 4T ;temp storage for OFF word for PSP
DITH1DEG DS 4T ;Holds ON dither degrees
DITH2DEG DS 4T ;Holds OFF dither degrees
ACNT DS 4T ;placeholder for phase A tables
DCNT DS 4T ;placeholder for phase B tables
CCNT DS 4T ;placeholder for phase C tables
DCNT DS 4T ;placeholder for phase D tables
FLAG9 DS 4T ;counter to use 2nd STRT interrupt
AMED DS 4T ;memory for AOFF Markov
BMEM DS 4T ;memory for BOFF Markov
CMEM DS 4T ;memory for COFF Markov
DMEM DS 4T ;memory for DOFF Markov
LENFLAG DS 4T ;1 for L, 0 for S in Markov
CFLAG DS 4T ;set if CINT, cleared otherwise

;Strings for messages to the PC monitor
CURINST1 DB 'YOU HAVE ENTERED ',00
DECP DB '.',00
DEGNOM1 DB ' DEGREES',CR,LF,00
ERROR1 DB CR, 'ERROR1 - TOO MANY CHARACTERS; RETYPE',CR,LF,PROMPT,00
ERROR2 DB CR, 'ERROR2 - ILLEGAL CHARACTER, RE-ENTER',CR,LF,PROMPT,00
ERROR3 DB CR, 'ERROR3 - TWO DIGITS ARE REQUIRED, START OVER',CR,LF,00
ERROR5 DB CR, 'ERROR5 - INVALID RANDOMIZATION SCHEME',CR,LF,00
WELCOME DB 'WELCOME TO THE VRM MOTOR CONTROL PROGRAM',CR,LF,PROMPT,00
CMD_TITLE DB 'LIST OF USER OPTIONS',CR,LF,LF
CMD_C DB 'C - CURRENT. SET THE CURRENT CHOPPING LEVEL',CR,LF
CMD_D DB 'D - DEGREES. SET DEGREES OF PERTURBATION OF ANGLE',CR,LF
DB 'H - HELP. DISPLAYS THE COMMAND SUMMARY',CR,LF
DB 'M - MODE. CHANGES THE INVERTER MODE ',CR,LF
DB 'S - SPEED. DISPLAYS SPEED IN RPM ',CR,LF
DB 'TO CHANGE PARAMETER, INPUT SINGLE LETTER FROM ',CR,LF
DB 'THE LIST ABOVE',CR,LF

CMD_SUM1 DB 'X-STOP N-NOMINAL M-MODE R-RANDOMIZE ',CR,LF
DB 'CHOOSE FUNCTION BY ENTERING A SINGLE LETTER',CR,LF

HELP_MSG DB 'Choose user option by entering the letter ',CR,LF
DB 'which corresponds to your choice from the ',CR,LF
DB 'list provided. Then follow instructions. ',CR,LF

NOMMSG DB 'CHANGE THE NOMINAL ON OR OFF PTS? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG1 DB 'CHANGE THE NOMINAL ON PT? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG2 DB 'ADD OR SUBTRACT 1.8 DEG FROM NOM PT? ',CR,LF
DB 'Y for ADD, N or ENTER for SUBTRACT',CR,LF

NOMMSG3 DB 'CHANGE THE NOMINAL OFF PT? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG4 DB 'REFINE THE NOMINAL ON ANG BY ADDING 1/2 DEG? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG5 DB 'REFINE THE NOMINAL OFF ANG BY ADDING 1/2 DEG? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG6 DB 'MAKE GROSS ADJUSTMENT TO ON ANGLE? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG7 DB 'MAKE GROSS ADJUSTMENT TO OFF ANGLE? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

NOMMSG8 DB 'DO YOU WANT TO RESTORE ORIGINAL NOMINAL POINTS? ',CR,LF
DB 'Y for yes, N or ENTER for no',CR,LF

RANDMSG DB 'CURRENT RANDOMIZATION SCHEME IS SCHEME ',CR,LF
RANDMSG1 DB 'CHANGE SCHEME? ENTER # (0 - 6) OR RETURN FOR NO',CR,LF
RANDMSG2 DB 'YOU HAVE CHOSEN SCHEME ',CR,LF
RANDMSG3 DB 'YOU HAVE CHOSEN TO KEEP THE SAME RANDOMIZATION SCHEME',CR,LF

RMSG1 DB '1: UNIFORM DITH OF ON PT ',CR,LF
RMSG2 DB '2: UNIFORM DITH OF OFF PT ',CR,LF
RMSG3 DB '3: UNIFORM DITH OF ON AND OFF PTS ',CR,LF
RMSG4 DB '4: TWO STATE MARKOV OF OFF PT ',CR,LF
RMSG5 DB '5: MOD MARKOV, UNIFORM DIST IN A SHORT OR LONG DELAY FOR OFF POINT ',CR,LF
RMSG6 DB '6: UNIFORM DITH OF PHASE A OFF POINT (ONLY) ',CR,LF

DITH1MSG DB 'ENTER # OF DEGREES OF OFF DITHER (1 OR 2) ',CR,LF
DITH2MSG DB 'ENTER # OF DEGREES OF OFF DITHER (1 OR 2) ',CR,LF
EXIT_MSG DB 'PROGRAM STOPPED ... ALL PHASES OFF ',CR,LF
DB 'hit F1, type PC 400, then GO to restart',CR,LF