Abstract—In this paper, Speed Sensorless Indirect Field Oriented
Control (IFOC) of a Permanent Magnet Synchronous machine
(PMSM) is studied. The closed loop scheme of the drive system
utilizes fuzzy speed and current controllers. Due to the well known
drawbacks of the speed sensor, an algorithm is proposed in this paper
to eliminate it. In fact, based on the model of the PMSM, the stator
currents and rotor speed are estimated simultaneously using adaptive
Luenberger observer for currents and MRAS (Model Reference
Adaptive System) observer for rotor speed. To overcome the
sensitivity of this algorithm against parameter variation, adaptive for
on line stator resistance tuning is proposed. The validity of the
proposed method is verified by an extensive simulation work.

Keywords—PMSM, Indirect Field Oriented Control, fuzzy speed
and currents controllers, Adaptive Luenberger observer, MRAS.

I. INTRODUCTION

INDUSTRIAL applications need more and more efficient
and accurate performances from motor drives. Induction
machines are used widely but in recent years; permanent
magnet synchronous motors (PMSM) are increasingly applied
in several areas such as tractions, automobiles, robotics and
aerospace technology because of advantages such as: high
power/ weight ratio, large torque, inertia ratio, smooth torque
operation, controlled torque at zero speed, high speed
operation, high torque production capability, high efficiency,
compact structures [1].

However, the need of position or velocity sensors in order
to apply effective vector-control algorithms is one of their
main constraints [2]. Indeed, there are several disadvantages
of those sensors such as higher number of connection between
motor and its driver, additional cost, susceptibility to noise
and vibrations, extra space, volume and weight on the overall
actuator [3].

Therefore, vector-control methods in the absence of any
position or speed sensor have been investigated by many
researchers [2, 4]. Some techniques were proposed in
literature. These techniques are generally based on the state
observer or Luenberger observer [5], MRAS method [6], and
extended Kalman filters.

In this paper, to overcome problems related to the
mechanical speed sensor, the adaptive Luenberger observer
for speed and stator resistance estimation has been proposed.
This algorithm associated with fuzzy speed and current
controllers in a field orientation strategy leads to a performed
solution for PMSM high dynamic drives.

II. MATHEMATICAL MODEL OF PMSM AND VECTOR
CONTROL

The dq equations in the reference frame of the PMSM are:

\[
\begin{bmatrix}
u_d \\
v_q \\
\end{bmatrix} =
\begin{bmatrix}
R & 0 \\
0 & R \\
\end{bmatrix}
\begin{bmatrix}
i_d \\
i_q \\
\end{bmatrix} + \frac{d}{dt}\begin{bmatrix}
\lambda_d \\
\lambda_q \\
\end{bmatrix} + \frac{p}{2} \begin{bmatrix}
0 \\
\lambda_q \\
\end{bmatrix}.
\]

The dq axis stator flux linkages are:

\[
\begin{bmatrix}
\lambda_d \\
\lambda_q \\
\end{bmatrix} =
\begin{bmatrix}
L_d & 0 \\
0 & L_q \\
\end{bmatrix}
\begin{bmatrix}
i_d \\
i_q \\
\end{bmatrix} + \begin{bmatrix}
0 \\
\Phi_e \\
\end{bmatrix}.
\]

The model is nonlinear because it contains product terms
such as speed with \( i_d \) or \( i_q \).

The dynamic behaviour and electromagnetic torque
equations are expressed by:

\[
T_m - T_L = J \frac{d\omega}{dt} + f\omega,
\]

\[
T_m = \frac{3\mu}{2} (\Phi_e i_q + (L_d - L_q) i_d i_q).
\]

The dq model of PMSM has been used to examine the
transient behavior of a high performances vector controlled
PMSM servo drive. The direct or ‘d ’ axis is aligned with
permanent magnet flux linkage phasor \( \Phi_e \), so that the
quadrature or ‘q ’ axis is orthogonally aligned with the resulting
back e.m.f phasor.

If \( i_q \) is forced to be zero, then

\[
\lambda_q = \Phi_e ; \lambda_d = L_q i_d.
\]

For constant flux operation, the electromagnetic torque is :

\[
T_m = \frac{3\mu}{2} \Phi_e i_d.
\]

The torque equation for PMSM resembles to that of the
regular DC motor. Therefore, it may facilitate very efficiently
the control of the machine. The motor currents are
decomposed into \( i_d \) and \( i_q \) components in the rotor based dq
coordinates system. The maximum torque is obtained with
\( i_d = 0 \) which corresponds to the case when the rotor and
stator fluxes are perpendicular. The operation of the drive is
then similar to that of armature current controlled DC motor.
The drive behavior can be adequately described by a
simplified model expressed by equation (6) [7].
III. CONTROL STRUCTURE

Fig.1 illustrates the block diagram of IFOC scheme based PMSM drive considered in this investigation. The drive consists of adaptive Luenberger observer for speed estimation, fuzzy hysteresis current control, and AC machine. The rotor speed \( w_r \) is compared with the reference speed \( w_{ref} \). The resulting error is processed in the fuzzy speed controller for each sampling interval. The output of this is considered to be the reference torque \( T_{em}' \).

IV. FUZZY LOGIC SPEED CONTROLLER

The fuzzy logic control has two inputs and one output \( U' \). The input variables used are the speed error \( e(k) \) and change in speed error \( \Delta e(k) \):

\[
e(k+1) = w_{ref} - w_r(k+1) \tag{7}
\]

\[
\Delta e(k+1) = e(k+1) - e(k) . \tag{8}
\]

To obtain normalized inputs and output for fuzzy logic controller, the constant gain blocks are used as scaling factors \( G_1, G_2, G_3 \):

\[
e'(k+1) = e(k+1) \cdot G_1 \tag{9}
\]

\[
\Delta e'(k+1) = \Delta e(k+1) \cdot G_2 \tag{10}
\]

\[
U'(k) = U(k-1) + G_3 \cdot \Delta e'(k) . \tag{11}
\]

The fuzzy logic control consists of three stages: the fuzzification, rule execution, and defuzzification. In the first stage, the crisp variables \( e(k) \) and \( \Delta e(k) \) are converted into fuzzy variables \( e'(k) \) and \( \Delta e'(k) \) using the triangular membership functions shown in Fig.2 and Fig.3. Moreover, the triangular membership function of variation in the command \( \Delta U \) and speed control surface are shown in Fig.4 and Fig.5.

The universe of discourse is divided into the fuzzy sets symbolized as follows: NL (negative large), NM (negative middle), NS (negative small), ZE (zero), PS (positive small), PM (positive middle) and PL (positive large). Each fuzzy variable is a member of the subsets with a degree of membership varying between 0 and 1.

In the second stage of the fuzzy logic control, the fuzzy variables \( e'(k) \) and \( \Delta e'(k) \) are processed by an inference engine that executes a set of control rules contained in rule bases which is described in table I.

Different inference algorithms can be used to produce the fuzzy set values for the fuzzy variable \( \Delta U \). In this paper, the sum-prod inference algorithm is used. The inference engine output variable is converted into a crisp value \( T_{em}' \) in the defuzzification stage.

Various defuzzification algorithms have been proposed in the literature [8]. In this paper, the centroid defuzzification algorithm is applied, in which the crisp value is calculated as the centre of gravity of the membership function.
To reduce the current harmonics, three fuzzy current controllers are introduced.

In fact, each fuzzy logic controller has two inputs and one output $\Delta U_j (j=a, b$ or $c)$. The input variables used are the current error $e_j(k)$ and change in current error $\Delta e_j(k)$:

$$e_j(k) = i_{\text{ref}} - i_j(k)$$
$$\Delta e_j(k) = e_j(k) - e_j(k - 1)$$

With: $j=a$, $b$ or $c$.

The universe of discourse is divided into the fuzzy sets symbolized as follows: NL (negative large), NS (negative small), ZE (zero), PS (positive small), PL (positive large), N (negative) and P (positive). Each fuzzy variable is a member of the subsets with a degree of membership varying between 0 and 1.

Moreover the triangular membership function of the error $e_j$, error variation $\Delta e_j$, variation in the command $\Delta U_j$ and the current control surface are shown respectively in Fig.6, Fig.7, Fig.8 and Fig.9.

The control strategy depends firstly on the inferences (rules). To simplify their descriptions table II is dressed. The method of inference selected here is known as sum-prod.

In this paper, the centroid defuzzification is adopted.

The inverter switching conditions are:

$$S_j = 1 \text{ if } \Delta U_j \text{ is positive.}$$
$$S_j = 0 \text{ if } \Delta U_j \text{ is null.}$$
$$S_j = -1 \text{ if } \Delta U_j \text{ is negative.}$$

With: $j=a$, $b$ or $c$.

But, the three level current controlled inverter devices ON/OFF conditions are:

$$S_j = 1 \text{ if upper transistor of inverter is on}$$
$$= -1 \text{ if lower transistor of inverter is on.}$$
$$= 0 \text{ if diode of inverter is on.}$$

with $j:a$, $b$ and $c$. 

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### Table I

<table>
<thead>
<tr>
<th>$e_j$</th>
<th>NL</th>
<th>NM</th>
<th>ZE</th>
<th>PM</th>
<th>PL</th>
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<tr>
<td>$\Delta e_j$</td>
<td>NL</td>
<td>NM</td>
<td>ZE</td>
<td>NS</td>
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<td>PL</td>
<td>ZE</td>
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<td>PM</td>
<td>PL</td>
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### Table II

<table>
<thead>
<tr>
<th>$\Delta e_j$</th>
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<tbody>
<tr>
<td>N</td>
<td>N</td>
<td>N</td>
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<td>P</td>
<td>ZE</td>
<td>ZE</td>
<td>ZE</td>
<td>ZE</td>
<td>ZE</td>
</tr>
</tbody>
</table>

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Fig. 6 The membership function of $e_j$

Fig. 7 The membership function of $\Delta e_j$

Fig. 8 The membership function of $\Delta U_j$

Fig. 9 Current control surface
VI. LUENBERGER ADAPTIVE OBSERVER

The simplified state space of PMSM is given by:

\[
\frac{dX}{dt} = AX + BU \\
Y = CX
\]

(15)

with:

\[
X = [i_d \ i_q]^T ; U = [u_d \ u_q \ \Phi_r]^T ; Y = [i_d \ i_q]^T
\]

\[
A = \begin{bmatrix}
-\frac{R}{L_s} & p\omega_r \\
-p\omega_r & -\frac{R}{L_s}
\end{bmatrix} ; B = \begin{bmatrix}
\frac{1}{L_s} & 0 & 0 \\
0 & \frac{1}{L_s} & -\frac{p\omega_r}{L_s}
\end{bmatrix} ; C = \begin{bmatrix}
1 & 0 \\
0 & 1
\end{bmatrix}
\]

The second order Luenberger observer (shown in fig.1) is given by:

\[
\frac{d\hat{X}}{dt} = A_1(\hat{\omega}_r, \hat{R})\hat{X} + B_1U + K(Y - \hat{Y})
\]

\[
\hat{Y} = C\hat{X}
\]

(16)

With:

\[
\hat{X} = [\hat{i}_d \ \hat{i}_q]^T ; Y = [i_d \ i_q]^T
\]

\[
A_1(\hat{\omega}_r, \hat{R}) = \begin{bmatrix}
\frac{\hat{\omega}_r}{L_s} & p\omega_r \\
-p\omega_r & -\frac{\hat{\omega}_r}{L_s}
\end{bmatrix} ; B_1 = \begin{bmatrix}
\frac{1}{L_s} & 0 & 0 \\
0 & \frac{1}{L_s} & -\frac{p\omega_r}{L_s}
\end{bmatrix}
\]

The matrix gain \( K \) is chosen so that the poles of \((A_1 - KC)\) to be stable.

VII. ADAPTIVE STATOR RESISTANCE AND ROTOR SPEED OBSERVATION

The rotor speed and the stator resistance are reconstructed using the model reference adaptive system (MRAS). The MRAS principle is based on the comparison of the outputs of two estimators. The first is independent of the observed variable named as model reference. The second is the adjustable one. The error between the two models feed an adaptive mechanism to turn out the observed variable.

In this work, the actual system is considered as the model reference and the observer is used as the adjustable one. The stator resistance and the rotor speed are built around the following adaptive mechanisms:

\[
\hat{R} = -\mu \int_0^t (e_d \hat{i}_d + e_q \hat{i}_q)dt
\]

(17)

with \( \mu = \frac{\lambda}{L_s} \); \( e_d = i_d - \hat{i}_d \); \( e_q = i_q - \hat{i}_q \).

\[
\hat{\omega}_r = K_s(i_d \hat{i}_q - i_q \hat{i}_d - \frac{\Phi_r}{L_s} e_q) + K_f \int_0^t (i_d \hat{i}_q - i_q \hat{i}_d - \frac{\Phi_r}{L_s} e_q)dt
\]

(18)

Where \( K_s, K_f \) and \( \mu \) are the proportional and integral constants respectively. The tracking performance of the speed estimation and the sensitivity to noise are depending on proportional and integral coefficient gains. The integral gain \( K_i \) is chosen to be high for fast tracking of speed. While, a low proportional \( K_p \) gain is needed to attenuate high frequency signals denoted as noises [9].

MRAS representation structure for identifying the rotor speed and the stator resistance simultaneously is given in Fig.10. The scheme consists of 2 models; reference and adjustable ones and an adaptation mechanism. The block reference model represents the actual system having unknown parameters values. The block adjustable model has the same structure of the reference one, but with adjustable parameters instead of the unknown ones. The block adaptation mechanism updates the adjustable model with the estimated parameter until satisfactory performance is achieved. The PMSM model was considered to be the reference model and we have used the Luenberger observer as adjustable model to obtain the estimated stator currents [10].

VIII. SIMULATION RESULTS AND DISCUSSION

The efficiency of the proposed control scheme has been verified based on an extensive simulation work under MATLAB/SIMULINK software package. Motor parameters used in simulations are given in table III.

The adaptive control algorithm for sensorless PMSM at variable step speed target under no load and with load applied has been tested. The effects of stator resistance variation are also considered.

In fact, after starting process without load \( T_L = 0 \), a load torque of \( T_L = 5.5N.m \) is applied at 0.2s and at t=0.8s after cancellation at 0.5s. The speed is inverses at t=0.5s. Simulation results are reported in Fig.11. The d and q axis stator currents responses indicate that the decoupling of the PMSM is established and ensured. For adaptive Luenberger observer method good dynamic response in speed without overshooting in starting and inversion, an influence at the inversion in currents is observed.

To investigate the behavior of the proposed sensorless control drives against stator resistance variation, a load torque of \( T_L = 5.5N.m \) is applied at 0.8s after starting process without load \( T_L = 0 \) under deviation of stator resistance from its nominal value by 100% at t=0.4s. The obtained results are given in Fig.12. Errors between the real and the estimated speeds and also currents occur at a time of the load and resistance variation. But, these errors are maintained and there is no compensation.
To overcome the sensitivity of the vector control algorithm against stator resistance variation, estimation and on-line adjustment of the stator resistance in vector control algorithm is necessary to maintain the decoupling of the PMSM. The MRAS principle has been used to observe the stator resistance value. The obtained results with on-line adjustment of the stator resistance are reported in Fig. 13.

The system response converges to the model reference one. An error occurs at time of the stator resistance variation. It converges to zero thanks to the adaptive control algorithm. The d and q axis stator currents responses indicate that the decoupling of the PMSM is established and ensured despite of the stator resistance variation. This is because of the on-line estimation and tuning of stator resistance in the vector control algorithm. The results show that the observed stator resistance follows exactly the real stator resistance, indicating the robustness of the proposed algorithm.

Fig. 14 shows simulation results under load with and without on-line adjustment of the stator resistance. The steady state currents during high deviation of stator resistance without on-line adjustment of the stator resistance show the loss of decoupling. Moreover, one can notice from fig. 14 (d) that when the resistance increases the speed drops and regulation performances are lost. But, the decoupling and the performances of the PMSM is maintained and ensured despite of the stator resistance variation in the case of on-line adjustment of the stator resistance.
IX. CONCLUSION

In this paper, the synthesis of a sensorless Indirect Field Oriented Control of Permanent Magnet synchronous Motor based on adaptive Luenberger observer is presented. The adaptive with control algorithm for the rotor speed associated with fuzzy speed and current controllers show good performances under no load, load applied and against stator resistance variation. The influence of the stator resistance variation on the Indirect Field Oriented Control was eliminated by the proposed algorithm for the estimation and on line adjustment of the stator resistance. The validity of this algorithm has been verified by simulation under Matlab/Simulink environment.

Practical implementation of the proposed method is a subject of future follow up research work.

APPENDIX

TABLE III

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
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<tbody>
<tr>
<td>Rated voltage</td>
<td>220/380V</td>
</tr>
<tr>
<td>$R$</td>
<td>1.4Ω</td>
</tr>
<tr>
<td>$L_d$</td>
<td>6.6mH</td>
</tr>
<tr>
<td>$L_q$</td>
<td>5.8mH</td>
</tr>
<tr>
<td>$L_s$</td>
<td>6.6mH</td>
</tr>
<tr>
<td>$\Phi_v$</td>
<td>0.1546Wb</td>
</tr>
<tr>
<td>$J$</td>
<td>0.00176N.m.s²/rad</td>
</tr>
<tr>
<td>$f$</td>
<td>0.000388N.m.s/rad</td>
</tr>
<tr>
<td>$p$</td>
<td>3</td>
</tr>
</tbody>
</table>

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