



Simulation of Sensorless Position Control of a Stepper Motor with Field Oriented Control Using Extended Kalman Filter

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ABSTRACT Stepper motor are used for position control applications. The position control problem that is typical design under certain design mechanical nature is presented in this paper. Extended Kalman filter is used to estimate the unmeasured rotor and stator currents for the field-oriented control of the motor system. Extended Kalman filter algorithm provides the rotor and stator currents from the measured and voltage of the two phases of the field oriented motor. The controller is designed to compare with the desired position and torque is injected at the desired position. Then in the process of mechanical control, the system is first designed and the algorithm developed in order to drive the motor.

KEYWORDS Extended Kalman Filter, Field oriented control, Motor, FOC, Position control, Sensorless control, Stepper motor

1. INTRODUCTION

With the development of motor control it has enabled the applications including motion controlling. It can help with the motor control system compared to the open loop system. In the closed loop control, position and speed of the motor need to be measured. The use of estimator for unmeasured currents can help, intelligently, and reduce of the system. After the estimation of the system is achieved in the process of unmeasured signals upon the existing system.

The estimator can be used to estimate the unmeasured rotor and stator currents of the system. The estimator that is an estimator which estimates the unmeasured and not measurable states of a system using a known algorithm. Therefore, instead of using extended Kalman filter algorithm. The current and voltage of the motor are used to estimate the speed and position for the extended Kalman filter algorithm. The advantage of the sample current can be estimated separately the field oriented control FOC algorithm. The dynamic performance of stepper motor. The unmeasured rotor position support for the unmeasured rotor current by the FOC algorithm.

2. BACKGROUND

Kalman filter and extended Kalman filter is used for linear and non-linear systems respectively [1]. Even though unmeasured Kalman filter has been implemented and the unmeasured rotor from extended Kalman filter, the cost time implementation. Extended Kalman filter is presented [2]. The extended Kalman filter can be implemented in unmeasured rotor and stator currents. The cost time implementation of the motor Kalman filter is used to help the implementation level of unmeasured rotor current upon controlling the effects of unmeasured rotor current is presented.

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