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(54) Title: METHOD FOR CONTROLLING ROTATION RATE OF ELECTRIC MOTOR

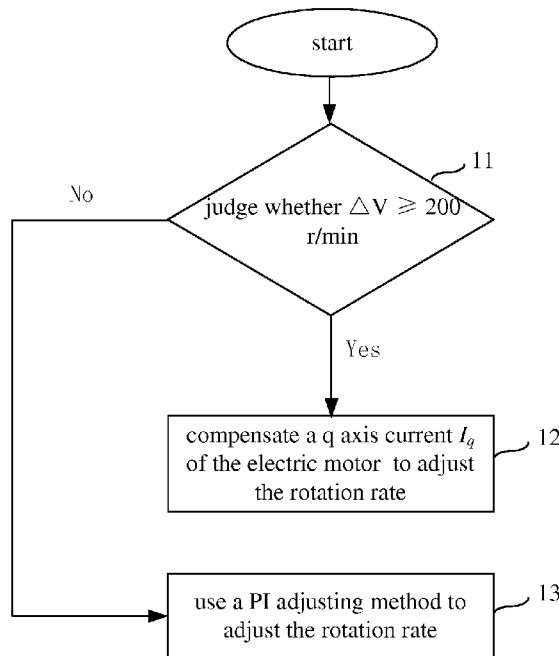


Fig. 1

(57) Abstract: A method for controlling a rotation rate of an electric motor is provided. The method comprises following steps: judging whether an absolute value of a difference between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to a predetermined value; and if yes, compensating a q axis current of the electric motor to adjust the rotation rate.

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METHOD FOR CONTROLLING ROTATION RATE OF ELECTRIC MOTOR

CROSS-REFERENCE TO RELATED APPLICATION

This application claims priority to and benefits of Chinese Patent Application Serial No. 201210083802.4, filed with the State Intellectual Property Office of P. R. China on March. 27, 2012, the entire contents of which are incorporated herein by reference.

FIELD

The present disclosure relates to an electric motor control field, and more particularly to a method for controlling a rotation rate of an electric motor.

BACKGROUND

Conventionally, a rotation rate of an electric motor (such as a synchronous electric motor without position sensor) is controlled by adjusting a proportional integral (PI) of the rotation rate. By using this method, the rotation rate may vary according to a normal variation of a load, thus ensuring a correct output of a torque. However, when the variation of the load or a variation of the rotation rate is relatively large, it will lead to a low response or a large fluctuation of the rotation rate by only using the PI adjustment.

SUMMARY

The present disclosure is aimed to solve at least one of the defects. Accordingly, a method for controlling a rotation rate of an electric motor is provided.

The method for controlling the rotation rate of the electric motor comprises following steps: judging whether an absolute value of a difference between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to a predetermined value; and if yes, compensating a q axis current of the electric motor to adjust the rotation rate.

In one embodiment, the predetermined value ranges from 100r/min to 300r/min.

In one embodiment, compensating a q axis current of the electric motor to adjust the rotation rate comprises: compensating a q axis current of the electric motor according to $I_q' = I_q - K * \Delta n$, where K is a coefficient, I_q' is an actual value of the q axis current, I_q is a given value of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N

cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$; and compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate.

In one embodiment, if yes, compensating a q axis current of the electric motor to adjust the rotation rate comprises: if the difference between the objective rotation rate and the actual rotation rate is greater than or equal to the predetermined value, judging whether $\Delta n < 0$; if yes, $I_q' = I_q - K * \Delta n$ and otherwise $I_q' = I_q$; and compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate, where K is a coefficient, I_q' is an actual output of the q axis current, I_q is a given output of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$.

In one embodiment, if yes, compensating a q axis current of the electric motor to adjust the rotation rate comprises: if the difference between the actual rotation rate and the objective rotation rate is greater than or equal to the predetermined value, judging whether $\Delta n > 0$; if yes, $I_q' = I_q - K * \Delta n$ and otherwise $I_q' = I_q$; and compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate, where K is a coefficient, I_q' is an actual output of the q axis current, I_q is a given output of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$.

In one embodiment, N ranges from 32 to 128.

In one embodiment, K ranges from 0.05 to 0.2.

In one embodiment, the method further comprises: if the absolute value of the difference between the objective rotation rate and the actual rotation rate is less than the predetermined value, using a proportional integral method to adjust the rotation rate.

In one embodiment, the proportional integral method comprises: calculating a difference $err(k)$ between the objective rotation rate and the actual rotation rate at a current time; and adjusting the rotation rate according to $Out(k) = Out(k-1) + (Kp + Ki) * err(k)$, where Kp is a proportional coefficient, Ki is an integral coefficient, $Out(k)$ is an actual rotation rate at the current time, and $Out(k-1)$ is an actual rotation rate at a previous time.

With the method for controlling the rotation rate of the electric motor, a defect that when a variation of a load or a variation of the rotation rate is relative large, it will lead to a low response

or a large fluctuation of the rotation rate by only using the PI method is avoided. Therefore, even the variation of the load or the variation of the rotation rate is relatively large, the rotation rate can also vary rapidly with the variation of the load, which is particularly applicable for a system with high requirement on stability.

Additional aspects and advantages of the embodiments of the present disclosure will be given in part in the following descriptions, become apparent in part from the following descriptions, or be learned from the practice of the embodiments of the present disclosure.

BRIEF DESCRIPTION OF THE DRAWINGS

These and other aspects and advantages of the disclosure will become apparent and more readily appreciated from the following descriptions taken in conjunction with the drawings in which:

Fig. 1 is a flow chart of a method for controlling a rotation rate of an electric motor according to a first embodiment of the present disclosure; and

Fig. 2 is a flow chart of a method for controlling a rotation rate of an electric motor according to a second embodiment of the present disclosure.

DETAILED DESCRIPTION

Embodiments of the present disclosure will be described in detail in the following descriptions, examples of which are shown in the accompanying drawings, in which the same or similar elements and elements having same or similar functions are denoted by like reference numerals throughout the descriptions. The embodiments described herein with reference to the accompanying drawings are explanatory and illustrative, which are used to generally understand the present disclosure. The embodiments shall not be construed to limit the present disclosure.

A method for controlling a rotation rate of an electric motor is provided by an embodiment of the present disclosure. The method comprises following steps.

In step S1, it is judged that whether an absolute value of a difference between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to a predetermined value.

In step S2, if yes, a q axis current I_q of the electric motor is compensated to adjust the rotation rate.

It is found that there is a relationship between a torque of the electric motor and the q axis current I_q of the electric motor, which may be represented by a formula. However, the relationship may be different for different types of electric motors, that is, there are different formulas. Therefore, controlling I_q is equivalent to controlling the torque, and the rotation rate is controlled accordingly. Thus, a compensation of the rotation rate may be realized by a compensation of I_q .

Now an AC (alternate current) electric motor is taken as an example to illustrate the relationship between the torque T and the q axis current I_q . The torque T of the AC electric motor may be represented by a formula: $T = 1.5p[\Psi_f * I_q + (L_d - L_q) * I_d * I_q]$, where p is a number of a pole pair of the electric motor, Ψ_f is a magnetic linkage of the electric motor, L_d is an inductance of a d axis of the electric motor, L_q is an inductance of the q axis of the electric motor, and I_d is a d axis current of the electric motor. It can be known from the formula that T is in linear proportion to I_q . Particularly, if $I_d = 0$, T is in direct proportion to I_q .

With the method for controlling the rotation rate of the electric motor, a defect that when a variation of a load or a variation of the rotation rate is relatively large, it will lead to a low response or a large fluctuation of the rotation rate by only using the PI adjusting method is avoided. Therefore, even the variation of the load or the variation of the rotation rate is relatively large, the rotation rate can also vary rapidly according to the variation of the load, which is particularly useful to a system with high requirement on stability.

Specifically, in step S2, the q axis current I_q may be compensated according to

$$I_q' = I_q - K * \Delta n,$$

where K is a coefficient, I_q' is an actual value of the q axis current, I_q is a given value of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$.

It should be noted that, the current N cycles refer to N cycles starting with a current cycle (denoted as M_{2N}) and backtracking to an M_{N+1}^{th} cycle, and the N cycles before the current N cycles refer to N cycles starting with an M_N^{th} cycle and backtracking to an M_1^{th} cycle. Taking $N=64$ as an example, the current N cycles refer to $[M_{128}, M_{65}]$, and the N cycles before the current N cycles refer to $[M_{64}, M_1]$, where M_{128} is the current cycle.

A value of N should be selected properly, because a too large N may lead to a hysteresis and offer no compensation effect, while a too small N may lead to a poor precision. In one embodiment, N may range from 32 to 128. Preferably, $N=64$. In one embodiment, K may range

from 0.05 to 0.2. Similarly, the predetermined value should be selected properly, because a too large predetermined value may not meet a requirement of rapid response, while a too small predetermined value may lead to a fluctuation. Preferably, the predetermined value may range from 100 r/min to 300 r/min.

A specific embodiment is described below to make the present disclosure be better understood by those skilled in the art. In this embodiment, as an example, the predetermined value takes 200 r/min.

Fig. 1 is a flow chart of a method for controlling the rotation rate of the electric motor according to a first embodiment of the present disclosure. As shown in Fig. 1, the method comprises following steps.

In step 11, it is judged whether an absolute value of a difference (ΔV) between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to 200 r/min.

In step 12, if yes, a q axis current I_q of the electric motor is compensated to adjust the rotation rate (for example, to realize a rapid response of the rotation rate), and the process is terminated.

In step 13, if no, a PI adjusting method is used to adjust the rotation rate.

It should be noted that, the PI adjustment may refer to any method in prior art for performing a PI adjustment on the rotation rate. In order to better understand the present disclosure, a specific PI adjusting method is shown as follows. This PI adjusting method may comprise following steps.

In step A1: a difference $err(k)$ between the objective rotation rate and the actual rotation rate at a current time is calculated.

In step A2: the rotation rate is adjusted according to $Out(k) = Out(k-1) + (Kp + Ki) * err(k)$, where Kp is a proportional coefficient, Ki is an integral coefficient, $Out(k)$ is an actual rotation rate at the current time, and $Out(k-1)$ is an actual rotation rate at a previous time. A specific value of Kp and Ki may be set according to practical requirement.

In this embodiment, Kp is mainly used for generating a direct proportion to the difference so as to rapidly reduce the difference. However, a steady state error will exist with only the direct proportion, so an integral (i.e., Ki) is required to eliminate the steady state error.

In this embodiment, Kp and Ki may be selected by giving preference to proportion. Firstly, Ki is given a value of zero; secondly, the objective rotation rate is modified (for example, make the objective rotation rate change greatly); thirdly, different Kps are tried to choose one Kp with which

the actual rotation rate may rapidly fluctuate around the objective rotation rate; fourthly, K_i is used. It should be noted that, K_i does not need to be too large, and because the integral acts on a time axis, an integration period needs to be selected. When the actual rotation rate may rapidly fluctuate around the objective rotation rate and a fluctuation value is relatively small, the current K_p and K_i may be considered qualified.

Fig. 2 is a flow chart of a method for controlling the rotation rate of the electric motor according to a second embodiment of the present disclosure. As shown in Fig. 2, the method comprises following steps.

In step 21, it is judged that whether an absolute value of a difference (ΔV) between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to 200 r/min. If yes, step 22 or step 23 is performed; and otherwise, step 28 is performed.

In step 22, if the difference between the objective rotation rate and the actual rotation rate is greater than or equal to 200 r/min, step 24 is performed.

In step 23, if the difference between the actual rotation rate and the objective rotation rate is greater than or equal to 200 r/min, step 25 is performed.

In step 24, it is judged whether $\Delta n < 0$; if yes, step 26 is performed, and otherwise step 27 is performed.

In step 25, it is judged whether $\Delta n > 0$; if yes, step 26 is performed, and otherwise step 27 is performed.

In step 26, $I_q' = I_q - K * \Delta n$, and the process is terminated.

In step 27, $I_q' = I_q$, and the process is terminated.

In step 28, a PI adjusting method is used to adjust the rotation rate.

In this embodiment, K is a coefficient, I_q' is an actual output of the q axis current, I_q is a given output of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$. It should be noted that, as to explanations about these parameters (such as K , N , Δn), please refer to relevant descriptions hereinbefore.

This embodiment shows an improved technical solution based on the first embodiment. In this second embodiment, a step of judging $\Delta n < 0$ or $\Delta n > 0$ is included, which is for preventing an incorrect instruction resulted from a program fault. The undue instruction may reduce the rapid

response of the rotation rate. For example, if the difference between the objective rotation rate and the actual rotation rate is greater than the predetermined value, Δn is supposed to be less than 0. However, Δn may be actually greater than or equal to 0 because of the program fault. Therefore, in order to prevent the incorrect instruction resulted from the program fault, the q axis current may not be adjusted, that is $I_q' = I_q$.

Reference throughout this specification to “an embodiment”, “some embodiments”, “one embodiment”, “an example”, “a specific examples”, or “some examples” means that a particular feature, structure, material, or characteristic described in connection with the embodiment or example is included in at least one embodiment or example of the disclosure. Thus, the appearances of the phrases such as “in some embodiments”, “in one embodiment”, “in an embodiment”, “an example”, “a specific examples”, or “some examples” in various places throughout this specification are not necessarily referring to the same embodiment or example of the disclosure. Furthermore, the particular features, structures, materials, or characteristics may be combined in any suitable manner in one or more embodiments or examples.

Although explanatory embodiments have been shown and described, it would be appreciated by those skilled in the art that changes, alternatives, and modifications may be made in the embodiments without departing from spirit and principles of the disclosure. Such changes, alternatives, and modifications all fall into the scope of the claims and their equivalents.

WHAT IS CLAIMED IS:

1. A method for controlling a rotation rate of an electric motor, comprising:

judging whether an absolute value of a difference between an objective rotation rate of the electric motor and an actual rotation rate of the electric motor is greater than or equal to a predetermined value; and

if yes, compensating a q axis current of the electric motor to adjust the rotation rate.

2. The method according to claim 1, wherein the predetermined value ranges from 100r/min to 300r/min.

3. The method according to claim 1 or 2, wherein compensating a q axis current of the electric motor to adjust the rotation rate comprises:

compensating a q axis current of the electric motor according to $I_q' = I_q - K * \Delta n$,

where K is a coefficient, I_q' is an actual value of the q axis current, I_q is a given value of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$; and

compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate.

4. The method according to claim 1 or 2, wherein if yes, compensating a q axis current of the electric motor to adjust the rotation rate comprises:

if the difference between the objective rotation rate and the actual rotation rate is greater than or equal to the predetermined value, judging whether $\Delta n < 0$;

if yes, $I_q' = I_q - K * \Delta n$ and otherwise $I_q' = I_q$; and compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate,

where K is a coefficient, I_q' is an actual output of the q axis current, I_q is a given output of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$.

5. The method according to claim 1 or 2, wherein if yes, compensating a q axis current of the electric motor to adjust the rotation rate comprises:

if the difference between the actual rotation rate and the objective rotation rate is greater than

or equal to the predetermined value, judging whether $\Delta n > 0$;

if yes, $I_q' = I_q - K * \Delta n$ and otherwise $I_q' = I_q$; and compensating a torque by compensating the q axis current of the electric motor to adjust the rotation rate,

where K is a coefficient, I_q' is an actual output of the q axis current, I_q is a given output of the q axis current, and Δn is a difference between an average of an actual rotation rate during current N cycles and an average of an actual rotation rate during N cycles before the current N cycles, $N \geq 1$.

6. The method according to any one of claims 3-5, wherein N ranges from 32 to 128.

7. The method according to any one of claims 3-5, wherein K ranges from 0.05 to 0.2.

8. The method according to any one of claims 1-7, further comprising:

if the absolute value of the difference between the objective rotation rate and the actual rotation rate is less than the predetermined value, using a proportional integral method to adjust the rotation rate.

9. The method according to claim 7, wherein the proportional integral method comprises:

calculating a difference $err(k)$ between the objective rotation rate and the actual rotation rate at a current time; and

adjusting the rotation rate according to $Out(k) = Out(k-1) + (Kp + Ki) * err(k)$,

where Kp is a proportional coefficient, Ki is an integral coefficient, $Out(k)$ is an actual rotation rate at the current time, and $Out(k-1)$ is an actual rotation rate at a previous time.

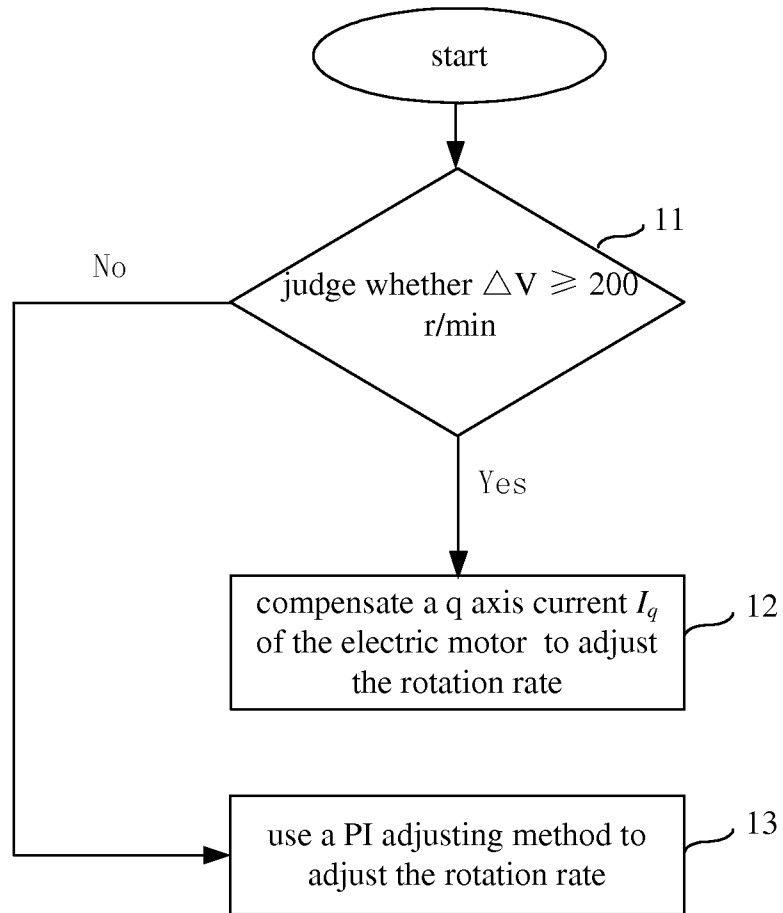


Fig. 1

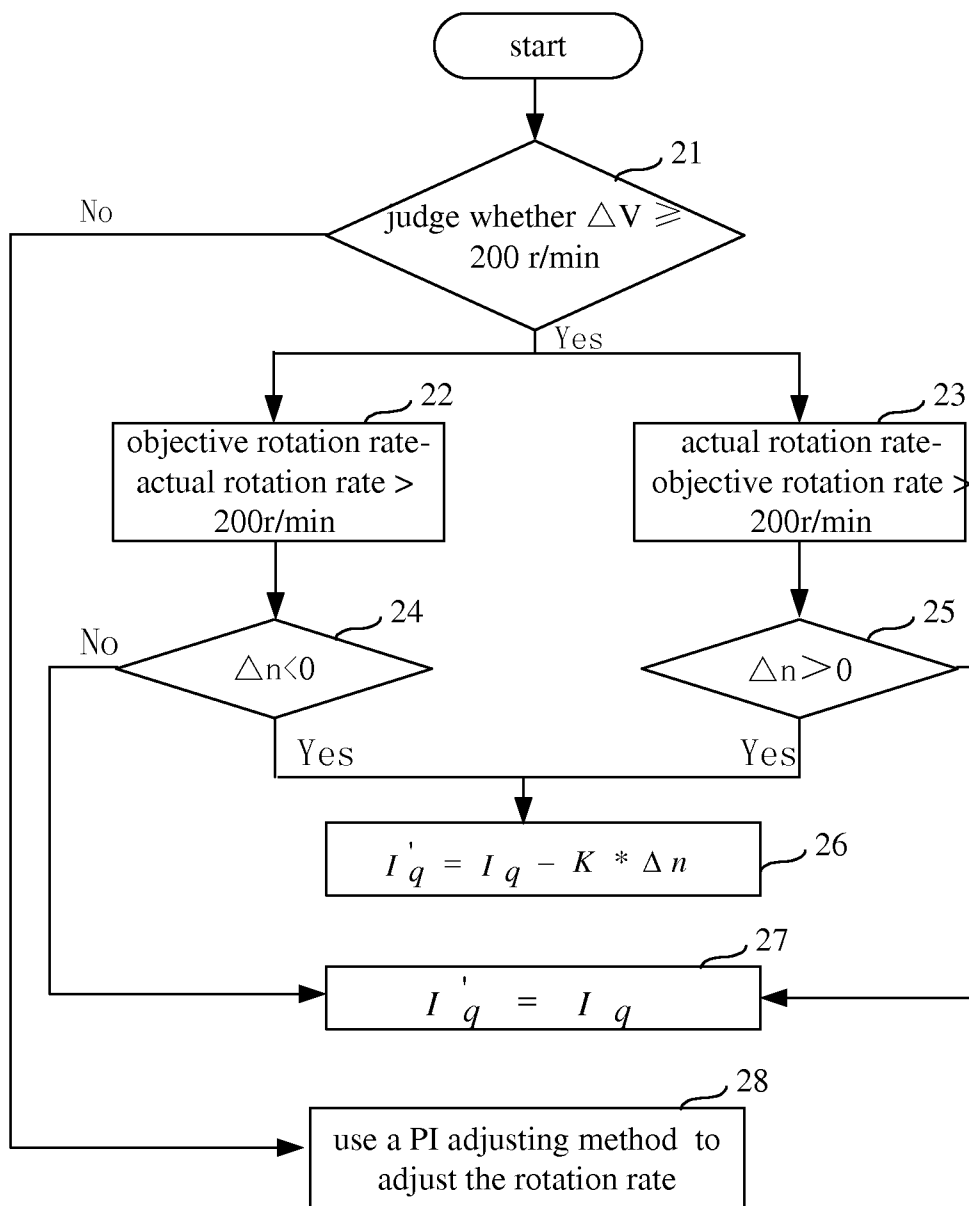


Fig. 2

INTERNATIONAL SEARCH REPORT

International application No.

PCT/CN2013/073189

A. CLASSIFICATION OF SUBJECT MATTER

See the extra sheet

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

IPC: H02P

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

CNPAT, CNKI, EPODOC, WPI, rotate, motor, speed, rate, difference, error, preset, predetermined, threshold, exceed, than

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	JP 2011-239541 A(CANON KK) 24 Nov.2011 (24.11.2011) See description, paragraphs [0006]-[0045] and figures 1-4	1-2
A	CN 101505135 A(UNIV TIANJIN) 12 Aug.2009 (12.08.2009) See the whole document	1-9
A	CN 102315814 A(BYD CO.,LTD) 11 Jan.2012 (11.01.2012) See the whole document	1-9
A	US 4361794 A(FUJITSU FANUC LTD) 30 Nov.1982 (30.11.1982) See the whole document	1-9
A	JP 2005-192267 A(MATSUSHITA DENKI SANGYO KK) 14 Jul.2005 (14.07.2005) See the whole document	1-9

 Further documents are listed in the continuation of Box C. See patent family annex.

* Special categories of cited documents:	“T” later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention
“A” document defining the general state of the art which is not considered to be of particular relevance	“X” document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone
“E” earlier application or patent but published on or after the international filing date	“Y” document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art
“L” document which may throw doubts on priority claim (S) or which is cited to establish the publication date of another citation or other special reason (as specified)	“&” document member of the same patent family
“O” document referring to an oral disclosure, use, exhibition or other means	
“P” document published prior to the international filing date but later than the priority date claimed	

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INTERNATIONAL SEARCH REPORT
Information on patent family members

International application No.
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Patent Documents referred in the Report	Publication Date	Patent Family	Publication Date
JP 2011-239541 A	24.11.2011	None	
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INTERNATIONAL SEARCH REPORT

International application No.

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A. CLASSIFICATION OF SUBJECT MATTER

H02P 6/06 (2006.01) i

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