
How to use STM32 motor control SDK v6.0 workbench

Introduction

The STM32 motor control software development kit (MC SDK) is part of the STMicroelectronics motor-control ecosystem. It is referenced as **X-CUBE-MCSDK** or **X-CUBE-MCSDK-FUL** according to the software license agreement applied. It includes:

- ST MC FOC firmware library for permanent magnet synchronous motor (PMSM) field-oriented control (FOC)
- ST MC 6-step firmware library
- ST motor profiler
- ST motor pilot
- ST MC workbench software tool, a graphical user interface (GUI) for the configuration of MC SDK firmware library parameters

This user manual explains how to use the ST MC workbench software tool included within the MC SDK firmware version 6.0.



1 General information

The ST MC workbench software tool is part of the MC SDK that is used for the development of motor control applications running on STM32 32-bit microcontrollers, based on the Arm[®] Cortex[®]-M processor.

The ST MC workbench provides the user with an easy and friendly way to configure his MC application software matching his hardware setup.

When completed, the user can directly generate his project which is compatible with the STM32CubeMX usage for a further MC application extension.

The ST MC workbench runs on a PC system using Windows[®] and requires a USB Type-A connector.

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2 Related documents

Documents available from Arm® infocenter website

- Cortex®-M0 Technical Reference Manual
- Cortex®-M3 Technical Reference Manual
- Cortex®-M4 Technical Reference Manual

Documents available from www.st.com or your STMicroelectronics sales office

- STM32F0xx datasheets
- STM32F3xx datasheets
- STM32F4xx datasheets
- STM32G4xx datasheets
- STM32G0xx datasheets
- STM32F7xx datasheets
- STM32H7xx datasheets
- STM32L4xx datasheets

Motor control reference documents

Table 1 presents the documentation that helps to get a deeper understanding of the STMicroelectronics motor control solution.

Table 1. Reference documentation

Reference	Document
[AN5143]	Application note <i>How to migrate motor control application software from SDK v4.3 to SDK v5.x</i>
[AN5166]	Application note <i>Guidelines for control and customization of power boards with STM32 MC SDK v5.0</i>
[AN5464]	Application note <i>Position control of a three-phase permanent magnet motor using X-CUBE-MCSDK or X-CUBE-MCSDK-FUL</i>
[DB3548]	Data brief <i>STM32 MC SDK software expansion for STM32Cube</i>
[UM2374] ⁽¹⁾	User manual <i>Getting started with STM32 motor control SDK v5.x</i>
[UM2380] ⁽¹⁾	User manual <i>Getting started with STM32 motor control SDK v5.x</i>
[UM2392]	User manual <i>STM32 motor control SDK v5.0.0 firmware</i>
[UM2916]	User manual <i>MCSDK - 6-step firmware examples: insights of the firmware and how to customize it</i>
[UM3016]	User manual <i>STM32 MC SDK motor profiler</i>
[UM3026] ⁽¹⁾	User manual <i>Getting started with STM32 motor control SDK v6.0</i>
[UM3027] ⁽¹⁾	User manual <i>Workbench tools for STM32 motor control SDK 6.0</i>
[wiki]	Refer to the motor control pages at the wiki.st.com/stm32mcsdk STMicroelectronics wiki site

1. UM3026 and UM3027 are respectively the evolutions of UM2374 and UM2380 for MC SDK 6.0.

3 ST motor-control workbench

Launch the ST motor-control workbench software tool by clicking either its icon (Figure 1) or running directly from the installation folder.

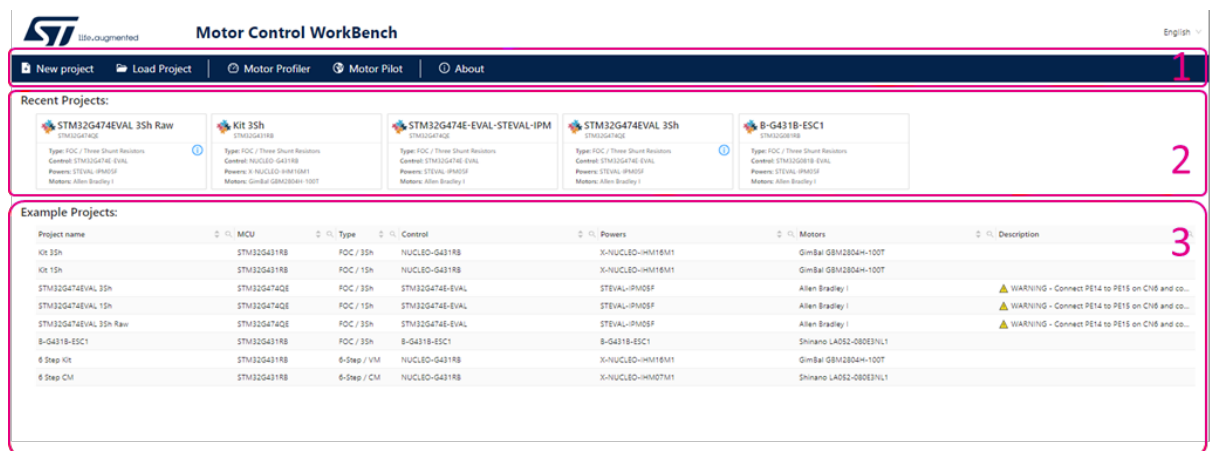
Figure 1. ST MC workbench – Icon



The ST MC workbench GUI presents the following home area (start-up page) where there are the following sections:

1. The user buttons area (Area 1 in Figure 2) to start either a new project or load a previous one, as well as launch the ST Motor Profiler or Motor Pilot software tools.
2. The recent projects area (Area 2 in Figure 2) to load a user's recent project.
3. The example projects area (Area 3 in Figure 2) to load a project example.

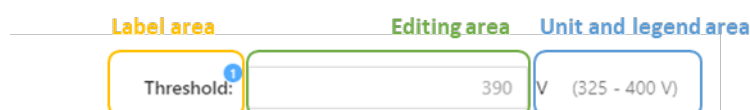
Figure 2. ST MC workbench – GUI (Home view)



3.1 Editing field behavior

One of the common developing paths in the ST MC workbench is the editing and combo field behavior. Each edit or combo field has the following format and behavior:

Figure 3. ST MC workbench – Editing field



Label area

In this area, the field name is shown with optionally a number notification bullet that shows specific notes on the field. The bullet must be info (Blue), warning (Orange), or error (Red), and the specific messages pop up on the bullet mouse over.

Editing area

In this area, the user can set its value. The field (Edit or combo) assumes different styles depending on its editing state:

- Field with default value: No value specified by the user (Value in light grey). The default value can be changed silently by the application itself.

Edit fields	Combo fields

- Field with default value in editing mode (Value in light grey): The user can edit its value. The user can transform the default value into an explicit user value by clicking the upper-right small icon (🔑).

Edit fields

- Field with explicit user value (Value in black): The explicit user value cannot be recalculated by the application. The user can reset the field to its default value by pressing the upper-right small icon (🔑).

Edit fields	Combo fields

- Field with error on value (Value in red): The user must review the field or reset the field to its default pressing the upper-right small icon.

Edit fields	Combo fields

Unit and legend area

This area is optional: It indicates the unit or the legend of the field, meaning the valid range.

3.2 New project wizard

When clicking the *New Project* button (Figure 2. ST MC workbench – GUI (Home view)), a window pops up that helps the user to define step-by-step the project configuration ().

3.2.1 General Info

In the *General Info* step the user can set the following info:

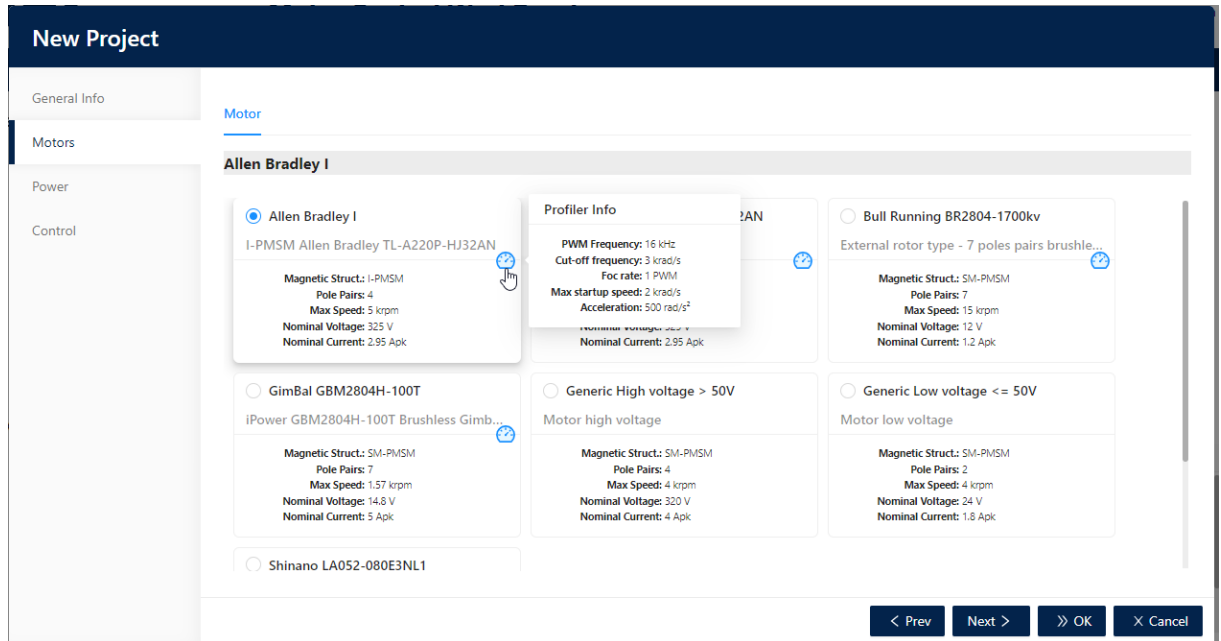
- **Project Name & Description**
 - Insert a *Project name* (Optional field), if specified it is used as the default file name in *save as...*
 - Insert a *Description* (Optional field).
- **Select Motor Control Algorithm & Hardware**
 - Selects *Num. Motors* usage.
 - Selects *Algorithm* type, such as FOC or 6-step.
 - Selects the ST *Hardware* type boards:
 - *Custom* if the system is composed of a control evaluation board together with a power evaluation board.
 - *Kit* if the ST board is an ST MC kit, meaning P-NUCLEO-IHM003.
 - *Inverter* if the ST board is a complete inverter board (Single board with both power and control electronics).

Figure 4. ST MC workbench – New project window

3.2.2 Motors

In the *Motors* step, the user selects the motor to use in the project. The user can select a *Generic Motor* or a *Profiled Motor*. The *Profiled Motors* are identified by an icon (Refer to the example in Figure 5). This step is not available in case the user selects as *Hardware* an ST MC kit (Refer to the example in Figure 9. *ST MC workbench – New project window – Kit*). The list provides a set of motors delivered with the application as well as the user motors.

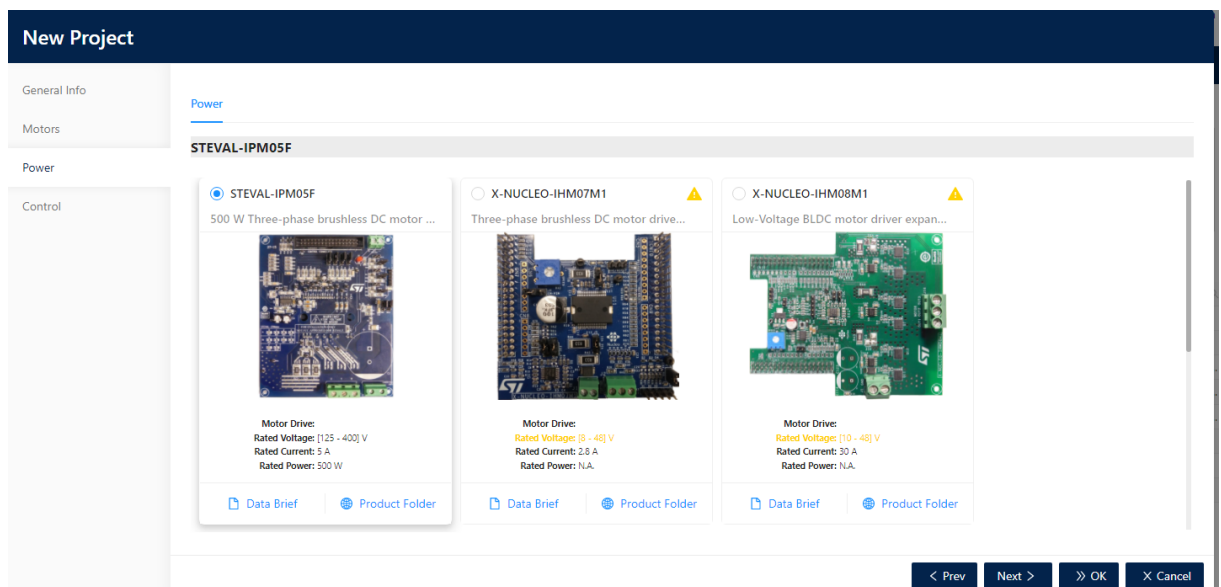
Figure 5. ST MC workbench – New project window – Motors



3.2.3 Power board

In the *Power* step, a list of available power boards is shown. The power boards are sorted by compatibility with the previously selected motor supply. A yellow warning triangle is shown if the board output power supply is not properly compatible with the motor.

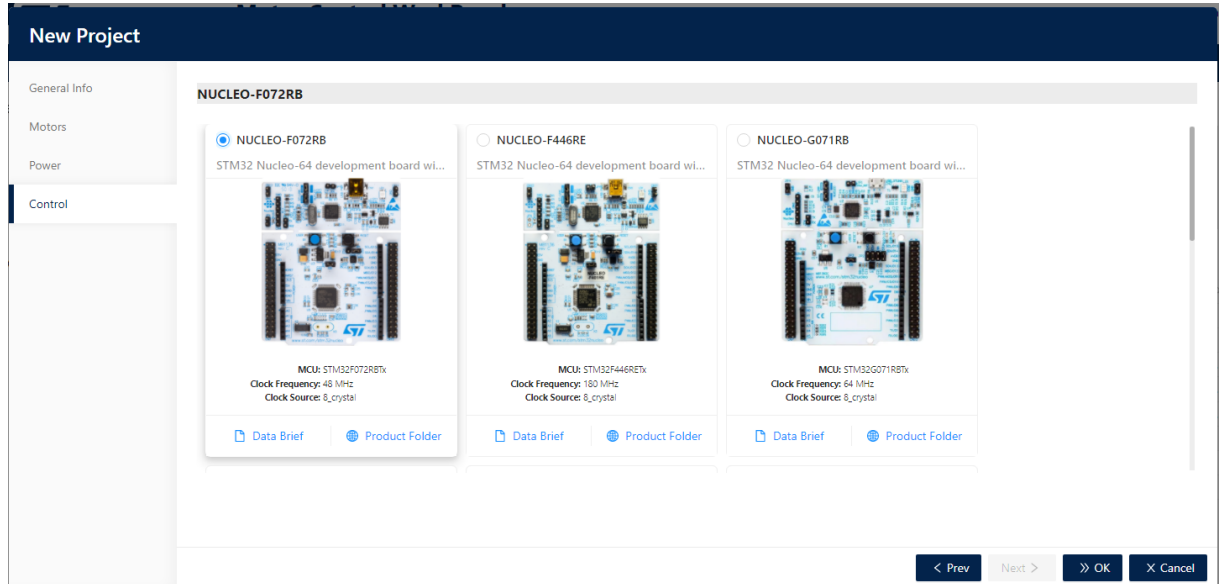
Figure 6. ST MC workbench – New project window – Power



3.2.4 Control board

In the *Control* step, a list of supported control boards is proposed. The list is sorted by compatibility with the selected power. An extra *Bridge* step is shown if the connectors for power and control are not compatible and require an adapter board.

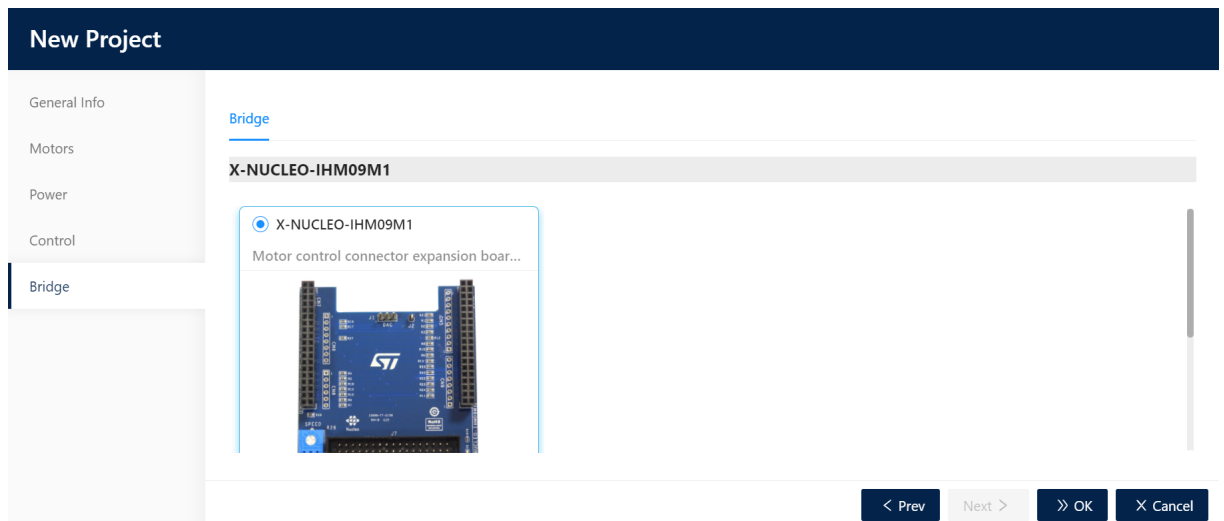
Figure 7. ST MC workbench – New project window – Control



3.2.5 Bridge

In the *Bridge* step, a list of available adapters is shown to be selected. The bridge selection allows the usage of boards (power and control) that are not directly connectable because they have different connectors, such as ST morpho or motor-control connectors.

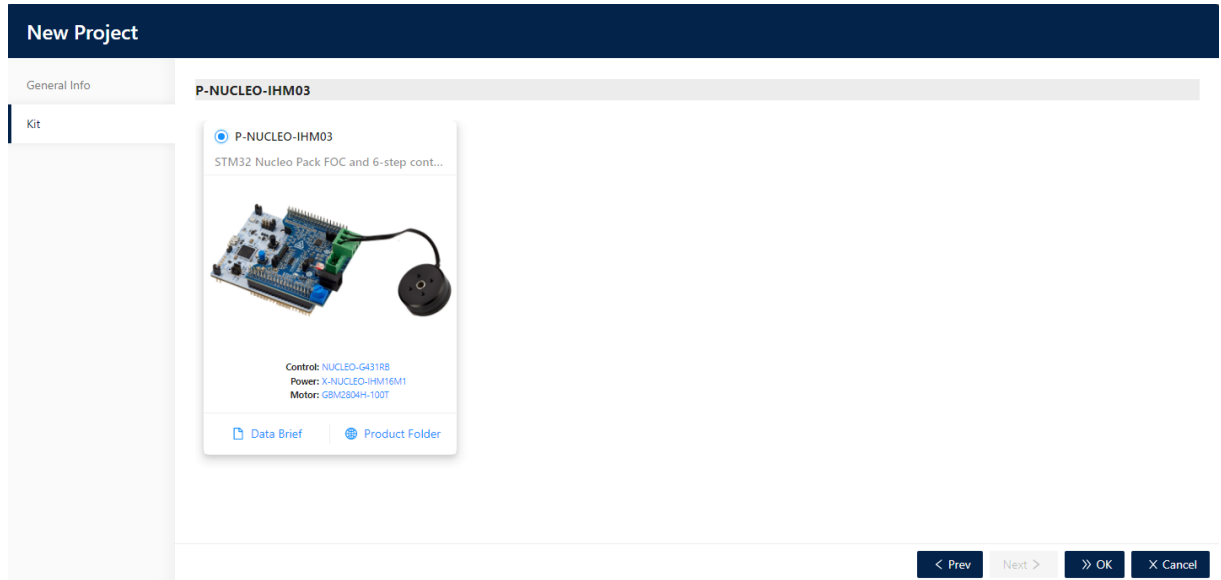
Figure 8. ST MC workbench – New project window – Bridge



3.2.6 Kit

The *Kit* step allows the selection of available supported kits. A kit is composed of a control board, a power board, and a motor.

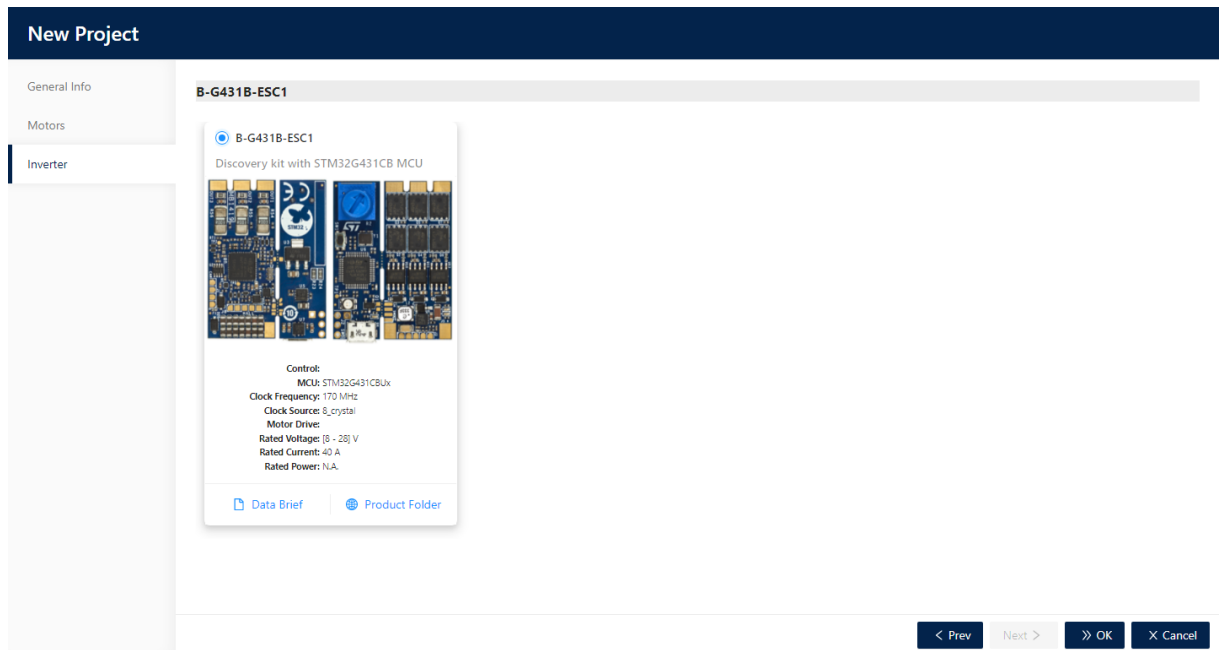
Figure 9. ST MC workbench – New project window – Kit



3.2.7 Inverter

The *Inverter* step allows the selection of available inverters. The inverter is a complete board, meaning a single board with both power and control parts.

Figure 10. ST MC workbench – New project window – Inverter

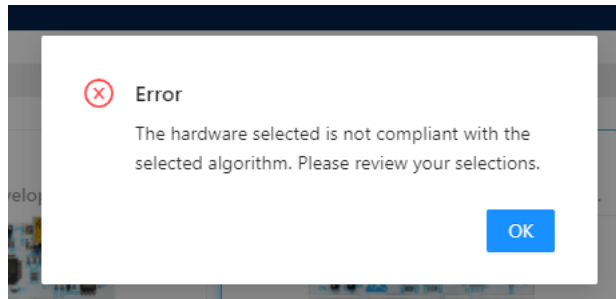


3.2.8 Creating the project

At the end of the new project wizard, the user can click on the *OK* button to create the project. All hardware must be explicitly selected by the user and depends on the hardware type field.

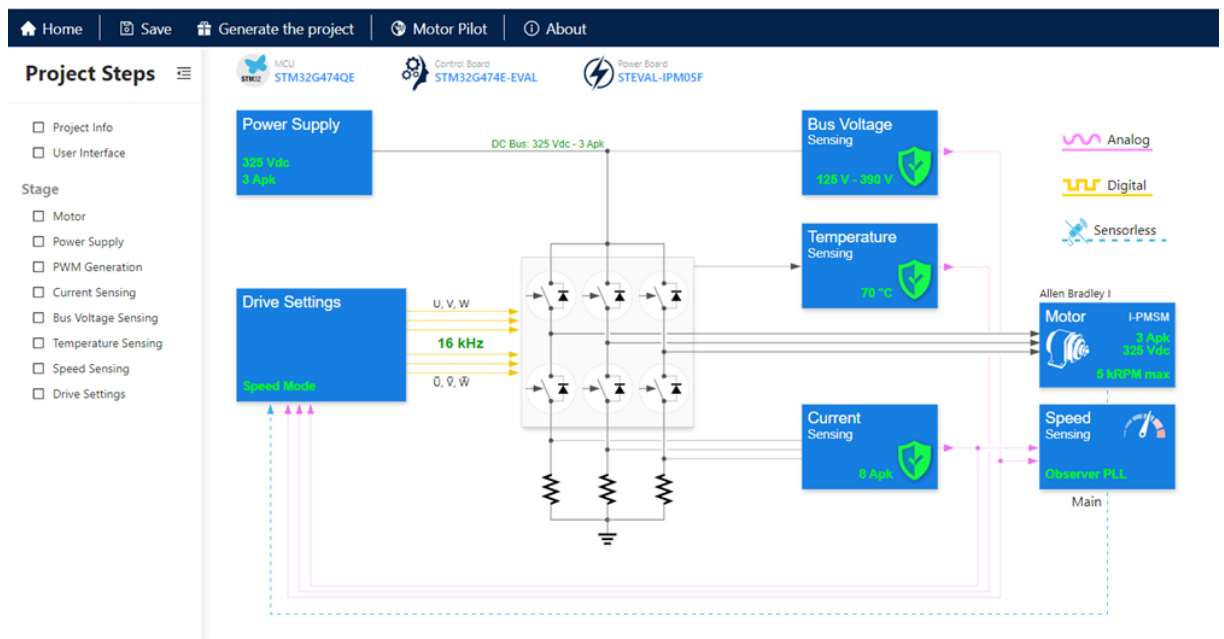
A post-selection procedure is executed to check if the configuration allows the creation of the project. If the user selection is not valid a dialog pops up to inform the user that the choices do not allow the project creation and ask to refine them (Figure 11).

Figure 11. ST MC workbench – New project creation error



Otherwise, the user selection is valid, a motorcontrol project is created, and the project view (Figure 12) is shown with all the information that depends on the selected boards and motor.

Figure 12. ST MC workbench – Project view



3.3 Loading an existing project

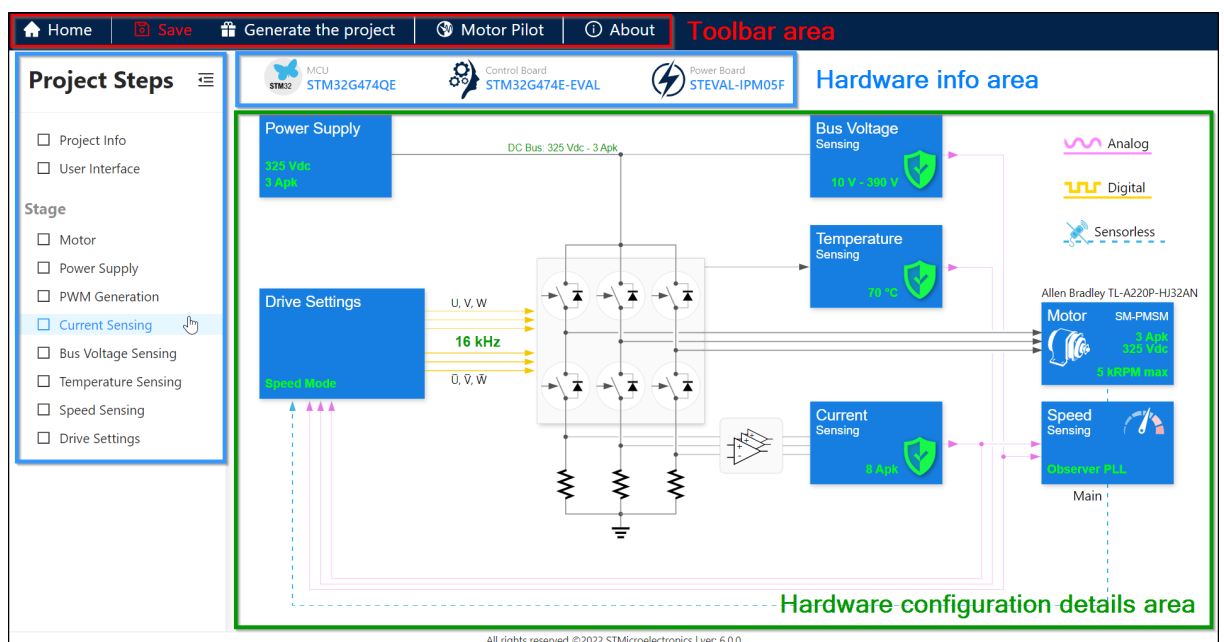
When clicking the *Load Project* button (Figure 2. ST MC workbench – GUI (Home view)), a system dialog window appears and the user can select the project file (.stwb6) to load. The loaded project appears in the *Project view* (Figure 12) where the user can refine it.

3.4 Project view

The project view is composed by:

- The toolbar area
- The hardware area info
- The Project Steps area to select the hardware part to parametrize:
 - The motor,
 - The power supply,
 - The PWM generation,
 - And other parameters.
- The hardware configuration details area. This is used to fine-tune the selected hardware functionality and view all the main info and protection at a first glance.

Figure 13. ST MC workbench – Project view (Global view)



3.4.1 Toolbar area

The toolbar area is useful to control application navigation, project saving, and generation.

3.4.1.1 Home

Clicking provides the user with an easy way to close the current project and come back to the home view (Figure 2. ST MC workbench – GUI (Home view)). When not already saved, a confirmation window pops up (Figure 14) asking the user to save the current project or not, as well as to cancel the action, then go back to the hardware configuration window (Figure 13).

Figure 14. ST MC workbench – Close project confirmation window

Do you really want to close the current Project?

There are unsaved data that will be lost if you click yes

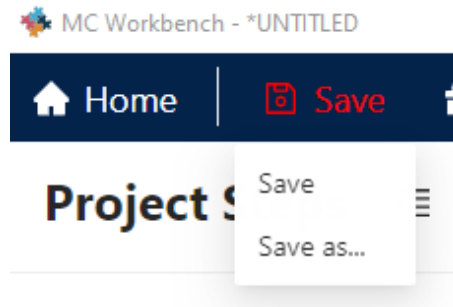
No

Yes

3.4.1.2 Save

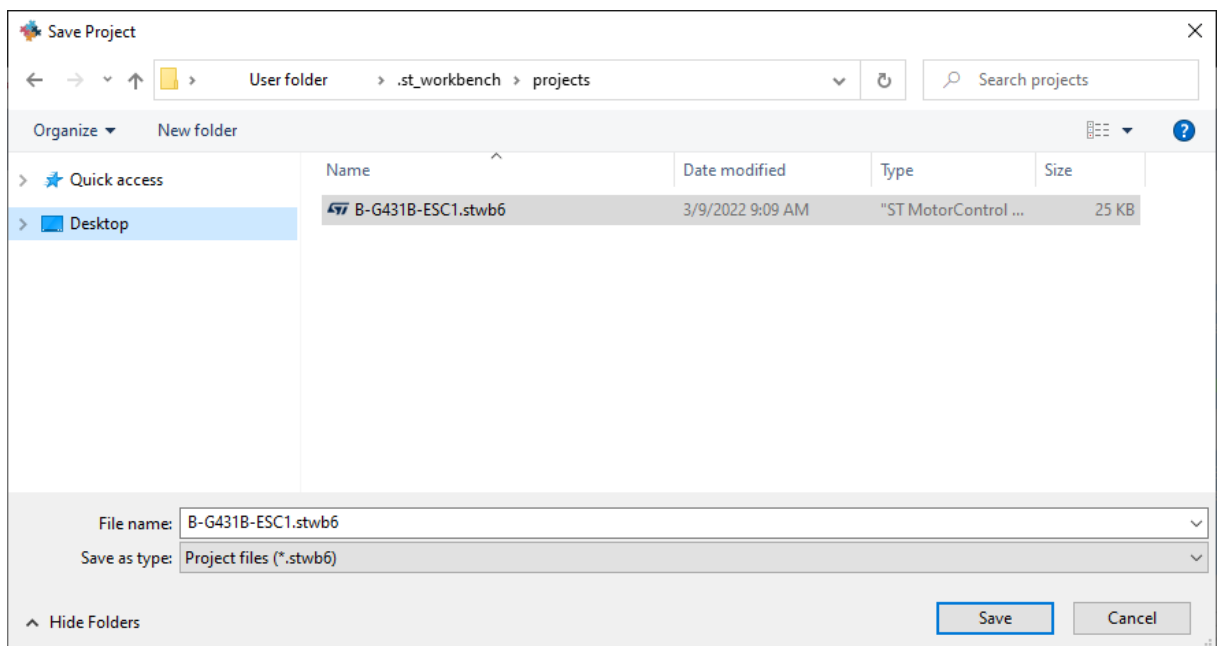
Click Save to open the Save menu.

Figure 15. ST MC workbench – Save menu



- **Save:** Saves the user's current project. When not already saved, a file manager window pops up to save the user's current project as a new one (Figure 16).
- **Save as...:** Saves the user project as a new file. A file manager window pops up to save the user project as a new one (Figure 16).

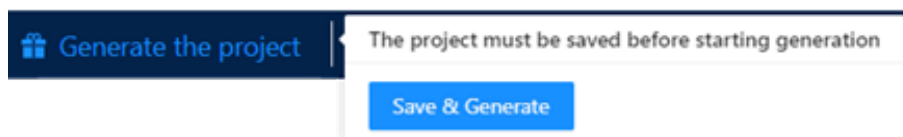
Figure 16. ST MC workbench – Project save as window



3.4.1.3 Generate the project

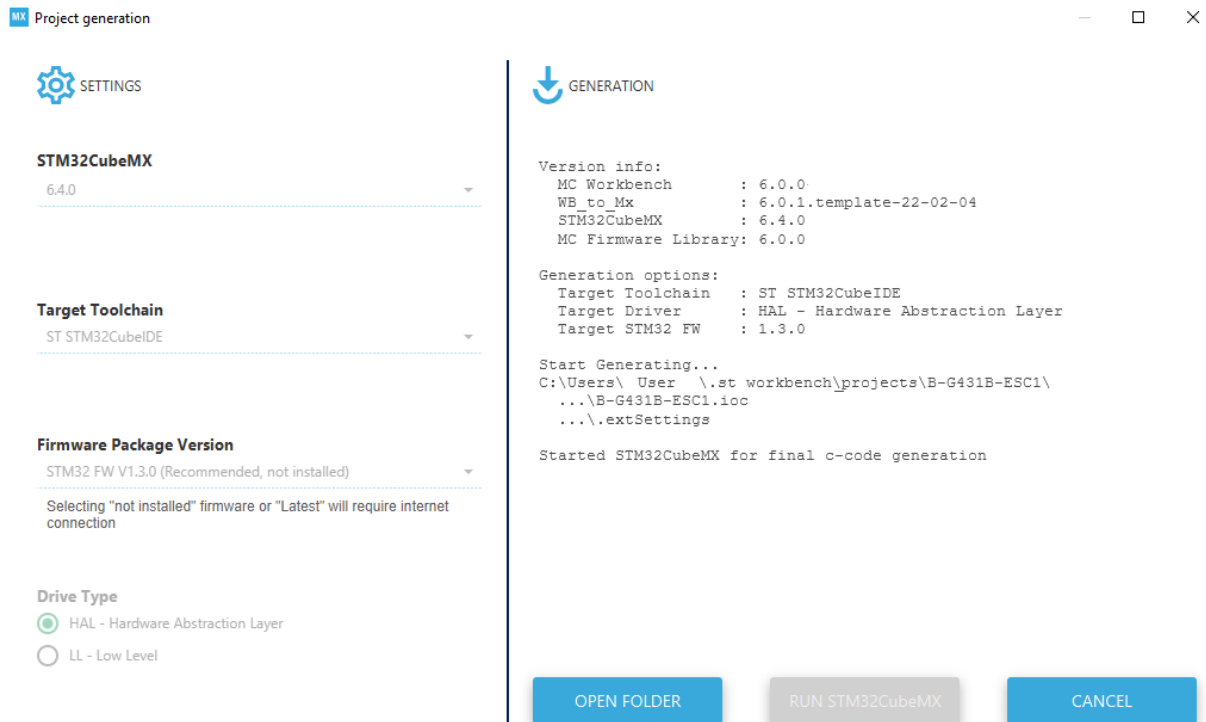
Clicking Generate the project generates the user application project files. If the project file is not already saved, an information window pops up to indicate that this project needs to be saved before to generate. Use the Save & Generate button to save and generate.

Figure 17. ST MC workbench – Save and generate



A window pops up (Figure 18) to allow the user to select the target toolchain, firmware package version, drive type, and generate the motor-control firmware application through the selected STM32CubeMX.

Figure 18. ST MC workbench – Project generation



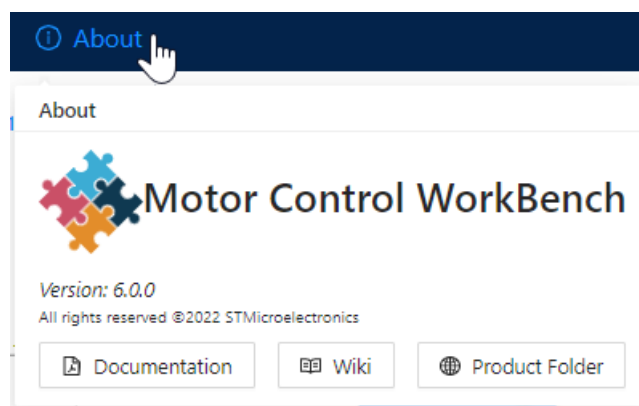
3.4.1.4 Motor Pilot

Clicking the *Motor Pilot* toolbar button launches the motor pilot application.

3.4.1.5 About

Clicking the *About* menu opens a window showing some application information and useful links.

Figure 19. ST MC workbench – About



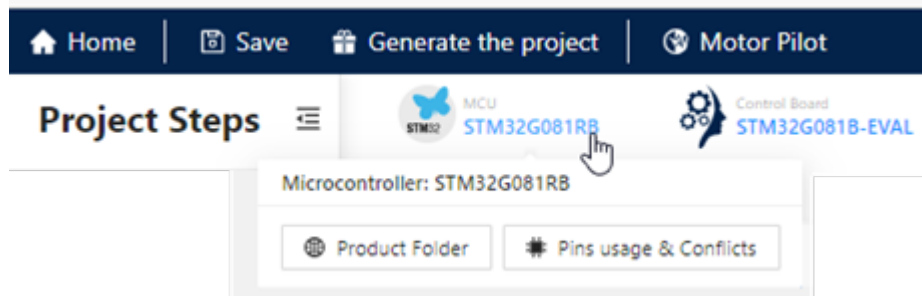
3.4.2 Hardware information area

Hardware information for the current project is presented in this area.

3.4.2.1 MCU pin usage and conflicts

Moving over  MCU a window pop-up is shown (Figure 20):

Figure 20. ST MC workbench – MCU




- *Product Folder*: Clicking it opens the product folder page for the MCU selected.
- *Pin usage & Conflicts*: To control the pin assignment of the MCU and receive feedback about the pin conflicts (Figure 21).

Figure 21. ST MC workbench – Pin usage & Conflicts

Pins usage & Conflicts

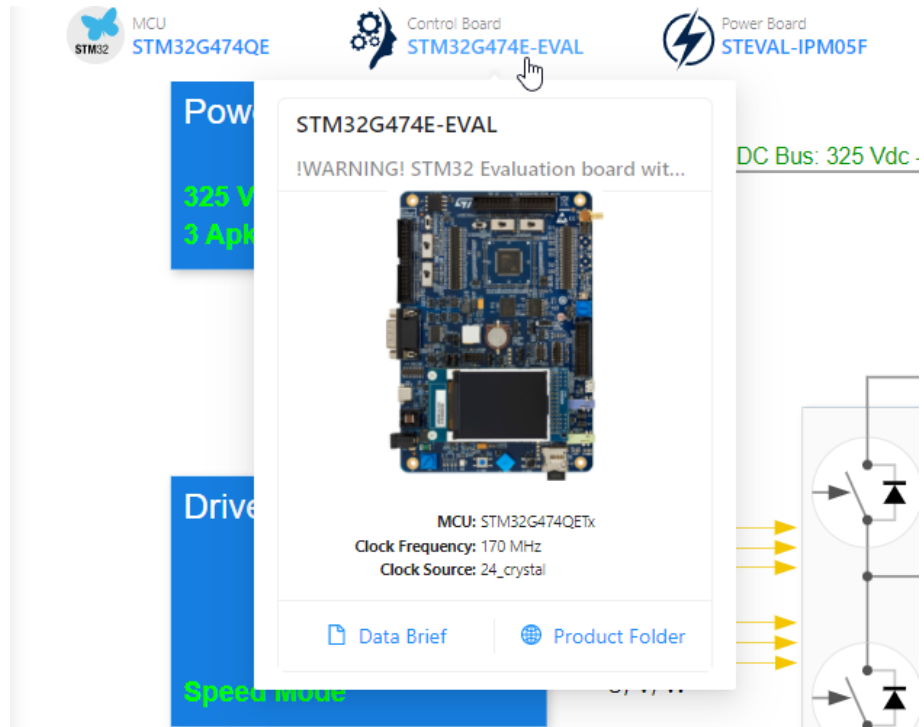
Conflicts	IP	Channel	Pin	Signal name
	USART3	TX	PC10	UART_TX
	USART3	RX	PC11	UART_RX
	ADC1	IN1	PA1	VBUS
	ADC1	IN3	PA3	TEMPERATURE_NTC
	TIM1	CH1	PA8	PWM_CHU_H
	TIM1	CH2	PA9	PWM_CHV_H
	TIM1	CH3	PA10	PWM_CHW_H
	TIM1	CH1N	PD2	PWM_CHU_L
	TIM1	CH2N	PD3	PWM_CHV_L
	TIM1	CH3N	PD4	PWM_CHW_L
	ADC1	IN2	PA2	CURRENT_AMPL_U
	ADC1	IN6	PA6	CURRENT_AMPL_V
	ADC1	IN11	PB10	CURRENT_AMPL_W
	TIM1	BK	PB12	OC_TRIGGER

3.4.2.2 Control Board


Moving over  *Control Board* a window pops up to give general information about the control board selected and it shows:

- *Data Brief* folder: Clicking it opens the relative data brief.
- *Product Folder*: Clicking it opens the relative product folder page.

Figure 22. ST MC workbench – Control board

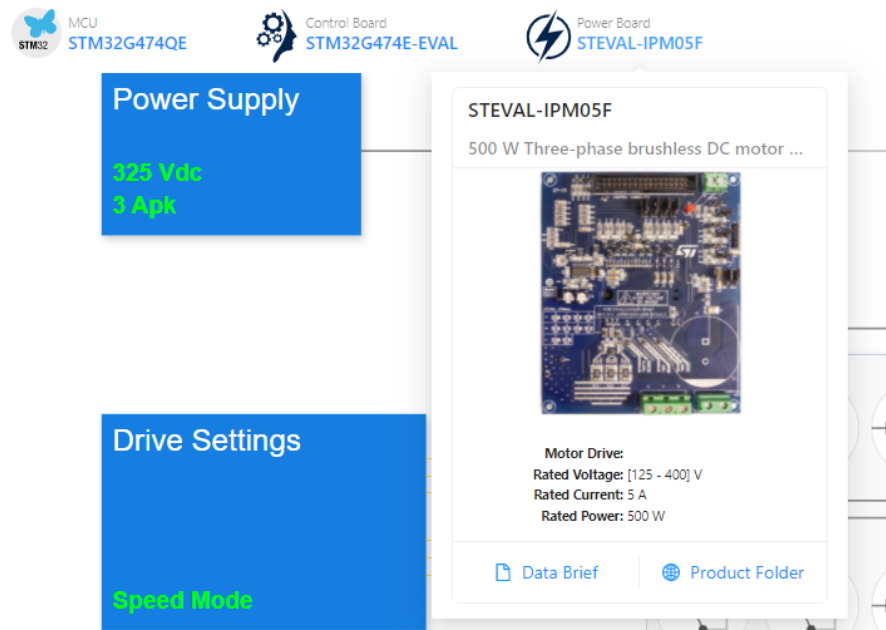


3.4.2.3 Power board

Moving over  *Power Board*, a window pops up, gives general information about the selected power board, and shows:

- *Data Brief* folder: Clicking it opens the relative data brief page.
- *Product Folder*: Clicking it opens the relative product folder page.

Figure 23. ST MC workbench – Power board



3.4.3 Project steps and hardware configuration details

All the hardware configurations alternatives depend on the hardware selected and are accessible from the wizard steps. The wizard steps are available from the left application pane (*Project Steps* area) as well as from the hardware configuration details area (main project view) by clicking the boxes. The information shown in the schematic is aligned with the wizard steps choices.

3.5 Project wizard

The project wizard is accessible from the left pane items or the relative main schematic view. Clicking one of these items displays the full wizard pops up and the relative step. The wizard is customized depending on the selected algorithm and in any case all the steps are available, and the user can move over all of them. The project wizard is the smart way to customize and configure the motor-control application for the hardware selected. Each wizard step contains several checks and info that help the user to make the right configurations. In case of errors, the wizard does not allow the project update and asks the user to fix the errors before applying the changes. In any case, if there are errors, the firmware project generation is not allowed.

The step sequence on the wizard has a special meaning: the values of a field on a step can depend only on fields on previous steps (and not for the forward steps). The field sequence dependency is also followed inside each step: it is from top to bottom and from left to right.

3.5.1 Product Info

This is a common step where the user can set the project description, to better identify the project, specifying project characteristics and extra-user information. The project description is also visible as a small pop-up icon in the recent project list (Area 2 in [Figure 2. ST MC workbench – GUI \(Home view\)](#)).

Figure 24. ST MC workbench – Project Info

3.5.2 User Interface

This is a common step where the user can configure the *Start and Stop button* and the *Motor Control Protocol (MCP)*, if these features are available for the selected hardware.

Figure 25. ST MC workbench – User interface

The user can change only the configurations that are available for the specific selected hardware. In the case shown in Figure 25, the Start/Stop is available only on the PC13 pin. If the hardware selected allows more possibilities a combo is available to allow the user to select the right pin to use. The Start/Stop feature can be disabled if the user does not want to use it.

3.5.3 Motor

This step is relative to the motor parameters. The default values are loaded from the selected motor during the creation of the project (Figure 5. ST MC workbench – New project window – Motors). The user can modify each motor parameter (Figure 26) and activate and configure the Hall sensor or quadrature encoder for the used motor (Figure 27).

Figure 26. ST MC workbench – Motor

FOC Wizard

Project Info
User Interface
Stage
Motor
Power Supply
PWM Generation
Current Sensing
Bus Voltage Sensing
Temperature Sensing
Speed Sensing
Drive Settings

Motor parameters

Motor magnetic structure: SM-PMSM
Pole Pairs: 7

Electrical parameters

Max current: 0.15 Apk
 Power board maximum rated current: 2.1 Apk
 Max DC Voltage: 12 V
 Power board supported voltage range: (7 - 45 Vdc)
 Rs: 5.29 Ω
 Ls: 1.058 mH
 B-Emf constant: 4.964 Vrms/kRPM

Mechanical parameters

Inertia: 0.291 μN·m·s²
 Friction: 0.937 μN·m·s
 Max. Application Speed: 1572 rpm

Off **Hall Effect**

Off **Quadrature Encoder**

< Prev Next > >> OK × Cancel

Figure 27. ST MC workbench – Motor – Hall effect – Quadrature encoder

Hall Effect

Sensors displacement: 120
 Placement electrical angle: 300

Quadrature Encoder

Pulses per mechanical revolution: 400
 Has index pin (Ch Z)

3.5.4 Power Supply

In this step, the *Max. application Current* and the *Bus Voltage* levels that are used by the application can be set. The values in this step must be the ones provided by the power supply and must be compatible with the power board and motor.

Figure 28. ST MC workbench – Power supply

FOC Wizard

Project Info

User Interface

Stage

Motor

Power Supply

PWM Generation

Current Sensing

Bus Voltage Sensing

Temperature Sensing

Speed Sensing

Drive Settings

Provide here below the Max Current and the Bus Voltage levels that will be used by this application.
Please note that these values have to be provided by your Power Supply and they have to be compatible with both PowerBoard and Motor

Max. application Current: A Up to 2.12 A

Bus Voltage: V from 7 V to 14.8 V

Power board Info:

- ✓ Maximum rated current: 2.12 Apk
- ✓ Supported voltage range: (7 - 45) Vdc

Motor Info:

- ✓ Max current: 5 Apk
- ✓ Max DC Voltage: 14.8 Vdc

< Prev Next > >> OK × Cancel

3.5.5 PWM Generation

In this step, the user can select the PWM driving topology available for the selected hardware, PWM frequency, modulation flags, and the MCU pin configuration for the topology used. For different driving topologies, different configurations are available.

3.5.5.1 **High and low side topology**

Figure 29 shows the step for high and low side driving topology.

Figure 29. ST MC workbench - PWM Generation - High and low side

The screenshot displays the 'FOC Wizard' interface with the 'PWM Generation' stage selected in the left-hand navigation menu. The main configuration area is divided into two sections: 'Config' and 'MCU pin mapping'.

Config Section:

- PWM Frequency:** 20000 Hz (range: from 2 kHz to 50 kHz)
- Driving topology:** U, V, W, Uneg, Vneg, Wneg
- SW dead-time:** 850 ns (range: from 700 ns to 1000 ns)
- PWM idle state low side:** Turn off
- PWM idle state high side:** Turn off
- dead-time:** 1000 ns
- Modulation flags:** Over modulation Discontinuous PWM

MCU pin mapping Section:

- Timer:** TIM1
- Ch. U:** PA8
- Ch. V:** PA9
- Ch. W:** PA10
- Active Polarity:** Active high
- Ch. U neg:** PA7
- Ch. V neg:** PB0
- Ch. W neg:** PB1
- Active Polarity:** Active low

At the bottom right of the wizard, there are four navigation buttons: '< Prev', 'Next >', '>> OK', and 'X Cancel'.

3.5.5.2 High side and three-enable topology

Figure 30 shows the step for the high side and three-enables driving topology.

Figure 30. ST MC workbench – PWM generation – High side and three enables

The screenshot shows the 'FOC Wizard' interface with the 'PWM Generation' stage selected. The left sidebar lists various configuration stages: Project Info, User Interface, Stage, Motor, Power Supply, PWM Generation (selected), Current Sensing, Bus Voltage Sensing, Temperature Sensing, Speed Sensing, and Drive Settings. The main area is divided into two sections: 'Config' and 'MCU pin mapping'.
Config section:
 - PWM Frequency: 30000 Hz (range: from 2 kHz to 50 kHz)
 - Driving topology: U, V, W, enU, enV, enW
 - dead-time: 550 ns
 - Modulation flags: Over modulation Discontinuous PWM
MCU pin mapping section:
 - Timer: TIM1
 - Ch. U: PA8
 - Ch. V: PA9
 - Ch. W: PA10
 - Active Polarity: Active high
 - Enable Ch. U: GPIO_Output (PB13)
 - Enable Ch. V: GPIO_Output (PB14)
 - Enable Ch. W: GPIO_Output (PB15)
 - Active Polarity: Active high
 At the bottom right, there are four navigation buttons: '< Prev', 'Next >', '>> OK', and 'X Cancel'.

3.5.6 Current Sensing

In this step, the user can select the available current reading topology and amplification (Figure 31). Depending on topology, amplification, and gain, the user is prompted with the relative fields to set and MCU Pin for that configuration, a schema shows the configuration graphically selected. The information on the step depends also on the selected algorithm (FOC or 6-step).

3.5.6.1 FOC 3-shunt external amplification

In this Current Sensing topology, the user can set the regulator execution time, T-Rise, and T-Noise. The current amplification in this case is done on the power board. Figure 31 shows the configuration.

Figure 31. ST MC workbench – Current sensing – FOC 3-shunt external amplification

The screenshot shows the 'FOC Wizard' interface with the 'Current Sensing' tab selected. The configuration is as follows:

- Regulator execution time:** 63 μ s (1 PWM)
- Current reading topology:** Three Shunt Resistors
- Amplification:** External OpAmps (selected)
- Shunt Resistor:** 100 mOhm
- Gain:** 2.1
- T-rise:** 1500 ns
- T-Noise:** 2000 ns
- Readable current range:** [-7.857 A, +7.857 A]

MCU pin mapping:

- ADC: ADC1 / ADC2
- Channel U: ADC1_IN8 (PC2)
- Channel V: ADC1_IN9 / ADC2_IN9 (PC3)
- Channel W: ADC2_IN6 (PC0)
- Sampling time: 153 ns (6.5 adc clk)
- Max Modulation: 98 %

The diagram on the right illustrates the hardware setup. It shows three shunt resistors connected to the U, V, and W phases. Each shunt resistor is connected to an external op-amp with a gain of x2.1. The outputs of these amplifiers are labeled 'Ampl. U', 'Ampl. V', and 'Ampl. W'. These signals are connected to the ADC inputs: 'Ampl. U' to ADC1_IN8, 'Ampl. V' to ADC1_IN9, and 'Ampl. W' to ADC2_IN6. The ADCs are labeled ADC1 and ADC2.

3.5.6.2 FOC 3-shunt internal amplification - Internal Gain

In this Current Sensing topology, the user can set the regulator execution time, the internal PGA gain factor, the T-Rise and T-Noise. In this case, the current amplification is done using an internal MCU operational amplifier. Figure 32 shows the configuration.

Figure 32. ST MC workbench – Current sensing – FOC 3-shunt internal amplification – Internal gain

The screenshot shows the 'FOC Wizard' interface for 'Current Sensing' configuration. The 'Current Sensing' section is active, showing the following settings:

- Regulator execution time: 63 μ s (1 PWM)
- Current reading topology: Three Shunt Resistors
- Amplification: Internal OpAmps
- Gain type: Internal PGA
- Sensing Type: Single Ended
- Shunt Resistor: 100 mOhm
- Internal PGA Gain: 4 (1.65 V)
- T-rise: 2550 ns
- T-Noise: 2000 ns
- Readable current range: [-4.72 A, 4.71 A] \approx \pm 4.71 A

The 'MCU pin mapping' section shows the following configuration:

- OpAmp: OPAMP1 / OPAMP2
- Channel U: OPAMP1_VINP (PA1)
- Channel V: OPAMP1_VINP / OPAMP2_VINP (PA7)
- Channel W: OPAMP2_VINP (PD14)
- ADC: ADC1 / ADC2
- OpAmp1 Out: ADC1_IN3 (PA2)
- OpAmp2 Out: ADC2_IN3 (PA6)
- Sampling time: 153 ns (6.5 adc clk)
- Max Modulation: 96%

The 'Over Current Protection' toggle is currently turned 'On'. The right side of the interface displays a schematic diagram of the internal MCU operational amplifiers (OPAMP1 and OPAMP2) and ADCs (ADC1 and ADC2). The diagram shows the internal PGA gain of x3.5 and the connection of the shunt resistors to the op-amp inputs. The pins are labeled A1, A2, D14, A6, and A7.

3.5.6.3 FOC 3-shunt internal amplification - External gain

In this current-sensing topology, the user can set the regulator execution time, and the T-Rise and T-Noise. In this case, the current amplification is done using an internal MCU operational amplifier. The gain depends on the gain net in the control board. Figure 33 shows the configuration.

Figure 33. ST MC workbench – Current sensing – FOC 3-shunt internal amplification – External gain

The screenshot displays the 'FOC Wizard' software interface, specifically the 'Current Sensing' configuration page. The interface is divided into a left sidebar with navigation options and a main configuration area.

Current Sensing Configuration:

- Regulator execution time: 63 μ s (1 PWM)
- Current reading topology: Three Shunt Resistors
- Amplification: Internal OpAmps
- Gain type: External gain net
- Sensing Type: Single Ended
- Shunt Resistor: 100 mOhm
- Gain: 3.5
- T-rise: 2550 ns
- T-Noise: 2000 ns
- Readable current range: [-4.72 A, 4.71 A] \pm 4.71 A

MCU pin mapping:

- OpAmp: OPAMP1 / OPAMP2
- Channel U Inv.: OPAMP1_VINM (PA3)
- Channel V Inv.: OPAMP1_VINM (PA3) / OPAMP2_VINM (PA5)
- Channel W Inv.: OPAMP2_VINM (PA5)
- Channel U: OPAMP1_VINP (PA1)
- Channel V: OPAMP1_VINP / OPAMP2_VINP (PA7)
- Channel W: OPAMP2_VINP (PD14)
- ADC: ADC1 / ADC2
- OpAmp1 Out: ADC1_IN3 (PA2)
- OpAmp2 Out: ADC2_IN3 (PA6)
- Sampling time: 153 ns (6.5 adc clk)
- Max Modulation: 96 %

MCU Pin Mapping Diagram:

The diagram illustrates the hardware connections for current sensing. It shows three shunt resistors connected to the U, W, and V phases. The U-phase shunt is connected to pins A1 and A2. The W-phase shunt is connected to pins D14 and A5. The V-phase shunt is connected to pins A7 and A6. Each shunt is connected to an internal op-amp (OPAMP1 and OPAMP2) configured with a gain of 3.5. The outputs of these op-amps are connected to ADC1_IN3 (PA2) and ADC2_IN3 (PA6) respectively. The diagram also shows the connection of the shunt resistors to the motor phases U, W, and V.

3.5.6.4 6-step current mode

This is only available for the 6-step algorithm and the user can enable or disable the current mode. The current mode can be enabled only if the feature is available for the selected hardware (Figure 34). By default, the current mode is disabled (Figure 35).

Figure 34. ST MC workbench – 6-step – Current mode

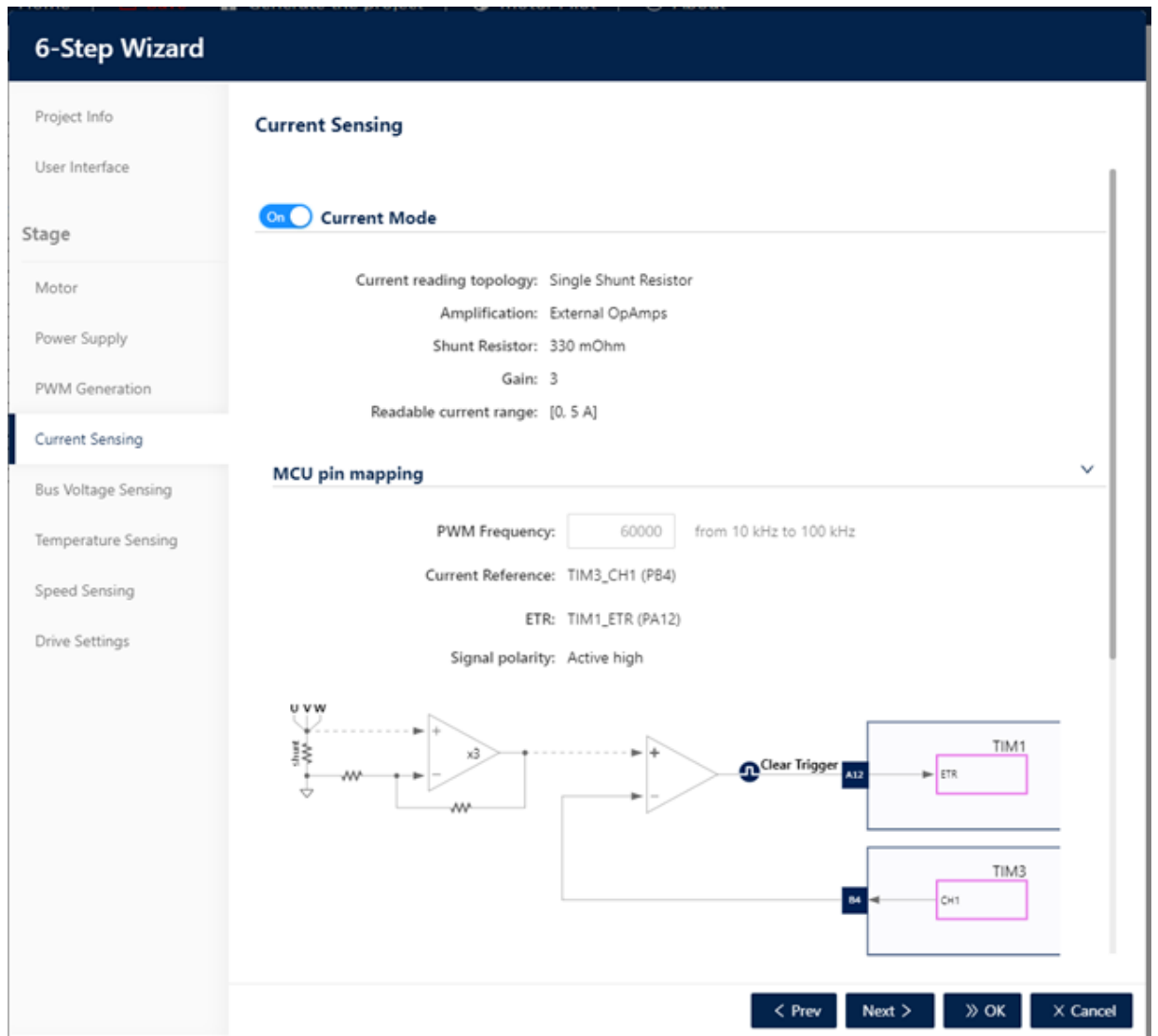
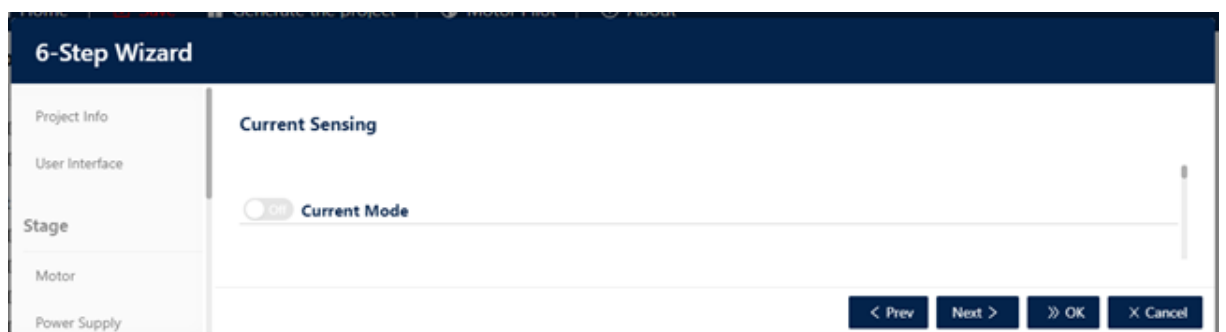


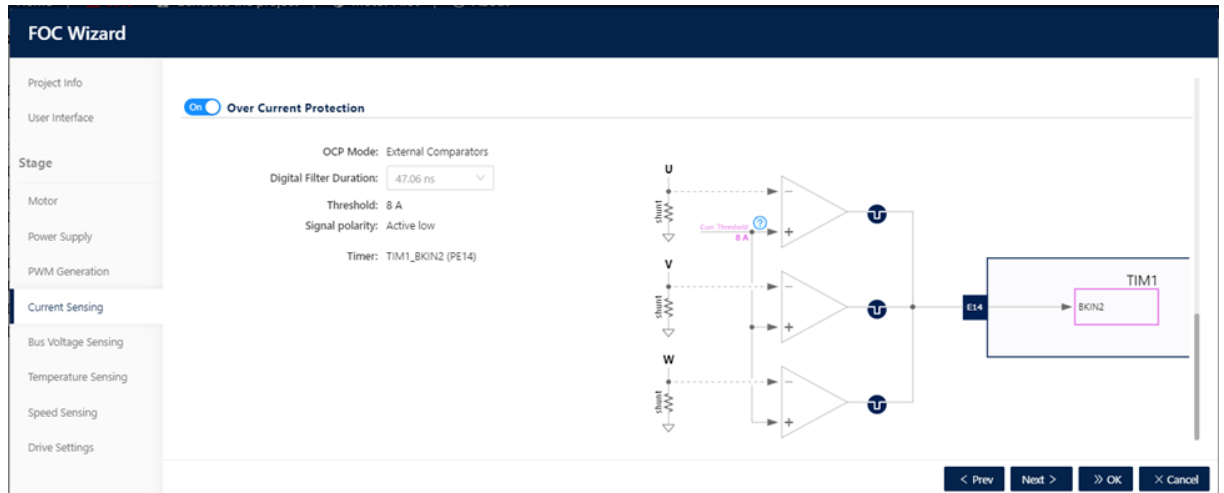
Figure 35. ST MC workbench – 6-step – Current mode disabled



3.5.6.5 Over-current protection

From the Current Sensing step, the user can enable and configure also the over-current protection (OCP) shown in Figure 36 the settings depend on the available OCP mode for the selected hardware. A generic schema will show the hardware connections between signals and the MCU.

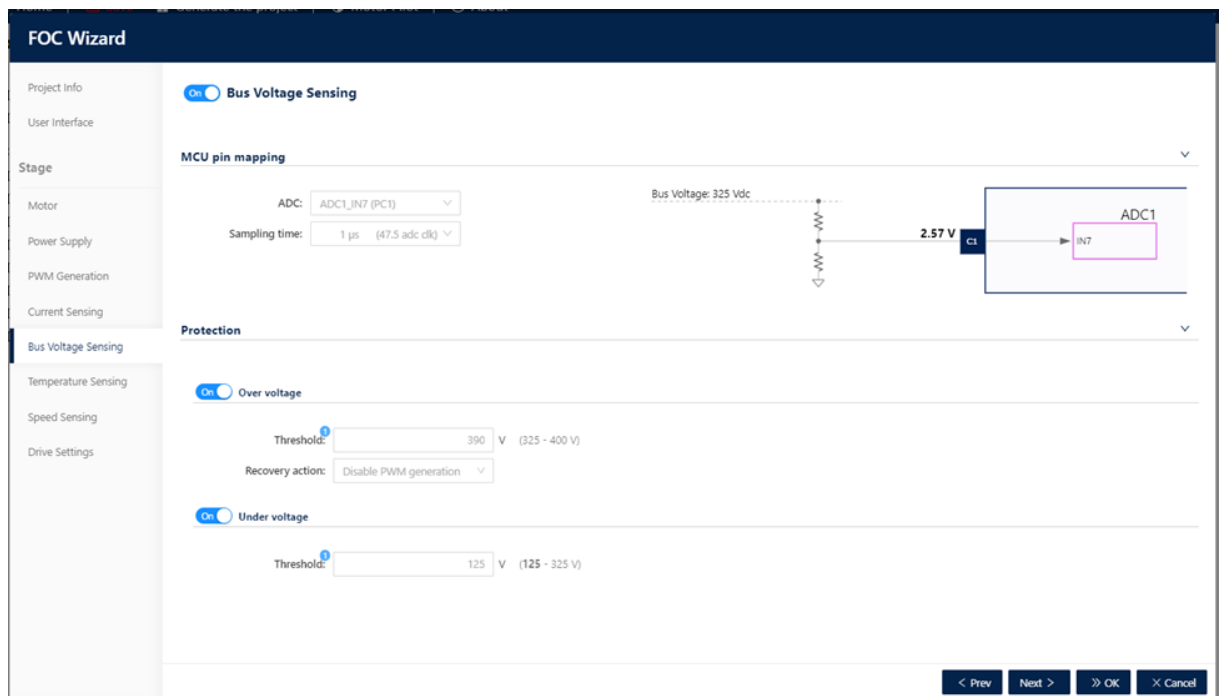
Figure 36. ST MC workbench – Current sensing – Over-current protection



3.5.7 Bus voltage sensing

In the *Bus Voltage Sensing* step, the user can configure the sensing of bus voltage if available for the hardware specified, and the relative Over Voltage and/or Under Voltage protection.

Figure 37. ST MC workbench – Bus voltage sensing



3.5.8 Temperature sensing

In the *Temperature Sensing* step, the user can configure the sensing of temperature if available for the specified hardware and the relative Over Temperature protection.

Figure 38. ST MC workbench – Temperature sensing

3.5.9 Speed-sensing

In the *Speed-Sensing* step, the user can select the speed sensing to use. There are different speed sensing modes that are available for both main and auxiliary sensors. The auxiliary sensor is optional and disabled by default. The speed sensing modes depend on the selected algorithm (FOC or 6-step).

3.5.9.1 FOC observer with PLL (Sensorless)

This speed sensing mode is the default for the main sensor and is always available.

Figure 39. ST MC workbench – Speed-sensing – Observer PLL

The screenshot shows the 'FOC Wizard' interface with the 'Speed Sensing' stage selected. The 'Speed Sensor Mode' is set to 'Observer + PLL (Sensorless)'. The 'Max Num. Errors before fault' is set to 3. Under the 'Observer + PLL (Sensorless)' section, the following parameters are configured: Variance Threshold: 25 %, Average speed depth for speed loop: 64, Average speed depth for observer equations: 64, B-emf consistency tolerance: 100 %, and B-emf consistency gain: 100 %. The 'Sensorless speed feedback' checkbox is checked. Under the 'Observer and PLL' section, 'Auto Calculate' is checked, and the parameters are: G1: -24453, G2: 24351, P: 665 / 16384 0.04059, and I: 29 / 65536 0.00044. Navigation buttons for 'Prev', 'Next', 'OK', and 'Cancel' are visible at the bottom right.

3.5.9.2 FOC observer with Cordic (Sensorless)

This speed sensing mode is always available.

Figure 40. ST MC workbench – Speed-sensing – Observer Cordic

The screenshot shows the 'FOC Wizard' interface with the 'Speed Sensing' stage selected. The 'Speed Sensor Mode' is set to 'Observer + Cordic (Sensorless)'. The 'Max Num. Errors before fault' is set to 3. Under the 'Observer + Cordic (Sensorless)' section, the following parameters are configured: Variance Threshold: 25 %, Average speed FIFO depth for speed loop: 64, Average speed FIFO depth for observer equations: 64, B-emf consistency tolerance: 100 %, B-emf consistency gain: 100 %, B-emf quality factor: 0.018, and Maximum application acceleration: 6000 rpm/s. The 'Sensorless speed feedback' checkbox is checked. Under the 'Observer' section, 'Auto Calculate' is checked, and the parameters are: G1: -24453 and G2: 24351. Navigation buttons for 'Prev', 'Next', 'OK', and 'Cancel' are visible at the bottom right.

3.5.9.3 FOC quadrature encoder

This speed-sensor mode depends on hardware availability and motor capability. The motor must have the sensor enabled and the feature must be supported by the hardware.

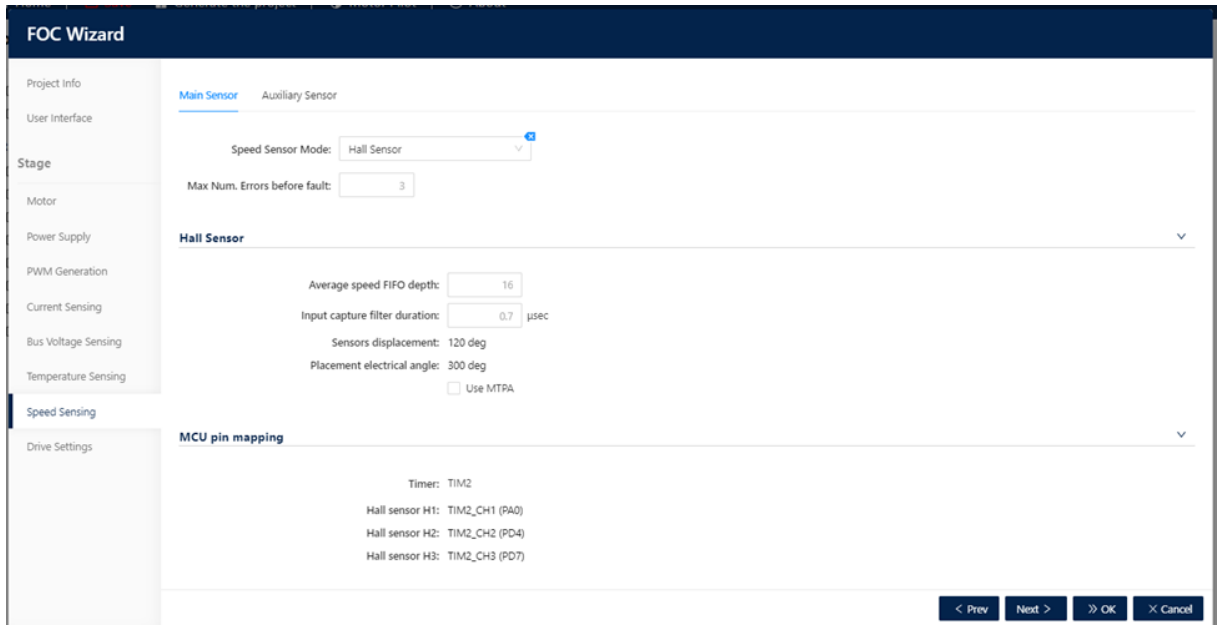
Figure 41. ST MC workbench – Speed-sensing – Quadrature encoder

The screenshot shows the 'FOC Wizard' interface with the 'Speed Sensing' stage selected. The 'Main Sensor' tab is active, and the 'Speed Sensor Mode' is set to 'Quadrature Encoder'. The 'Max Num. Errors before fault' is set to 3. The 'Quadrature Encoder' section includes settings for 'Average speed FIFO depth' (16), 'Input capture filter duration' (0.7 µsec), and 'Pulse per mechanical revolution' (400). There are also checkboxes for 'Reverse counting direction' and 'Use encoder alignment'. The 'Start-up parameters' section shows 'Duration' (700 ms), 'Alignment electrical angle' (90 deg), and 'Final current ramp value' (2.95 A). The 'MCU pin mapping' section shows 'Timer: TIM2', 'Encoder A: TIM2_CH1 (PA0)', and 'Encoder B: TIM2_CH2 (PD4)'. Navigation buttons for '< Prev', 'Next >', '>> OK', and 'X Cancel' are at the bottom right.

3.5.9.4 Hall sensor

This speed sensor mode depends on hardware availability and motor capability. The sensor must be enabled for the motor and the hardware must support the feature. This speed sensor mode can be used in FOC and 6-step algorithms.

Figure 42. ST MC workbench – Speed-sensing – Hall sensor



3.5.9.5 FOC sensor-less start-up parameters

The settings of the sensor-less start-up parameters are available only if the main sensor selected is sensorless (Observer with PLL or observer with Cordic).

Figure 43. ST MC workbench – Speed-sensing – Sensor-less start-up parameters

FOC Wizard

Main Sensor: Auxiliary Sensor: **Sensorless start-up parameters**

Start-up profile

Initial electrical angle: 0 deg On-the-fly start-up: Off

	Duration (ms)	Speed target (rpm)	Current target (A)
Phase 1:	1000	0	2.95
Phase 2:	3996	1998	2.95
Phase 3:	0	1998	2.95
Phase 4:	0	1998	2.95
Phase 5:	0	1998	2.95

Execute sensor-less algorithm starting from phase: 2

Start-up exit condition

Start-up speed threshold: 1798 rpm

Consecutive correct measures: 2

Estimated limits for the speed band tolerance

Lower limit: 93.75 %

Upper limit: 106.25 %

Rev-up to FOC switch-over

Duration: 25 ms

Speed target (rpm) vs Time (ms) graph: Shows speed target (red line) and current target (blue line) over time. The speed target starts at 0, reaches 1798 rpm at 1000 ms, and then continues to rise. The current target starts at 0, reaches 2.95 A at 1000 ms, and remains constant until 5000 ms. A horizontal dashed red line indicates the 'Start-up speed threshold' at 1798 rpm.

< Prev Next > >> OK X Cancel

3.5.9.6 6-step sensor-less ADC

Sensor-less ADC is a specific speed-sensing mode for the 6-step algorithm.

Figure 44. ST MC workbench – 6-step sensor-less ADC

The screenshot shows the '6-Step Wizard' interface in the ST MC workbench. The 'Main Sensor' tab is active, showing 'Sensorless start-up parameters'. The 'Speed Sensor Mode' is set to 'Sensorless - ADC' and 'Max Num. Errors before fault' is set to 3. The 'Sensorless - ADC' section includes a 'Reset to default' button and the following parameters: Average speed FIFO depth (8), Threshold [V] (Bemf rising) (0.15 V), Threshold [V] (Bemf falling) (0.15 V), Sampling point (90 % of PWM cycle), and Step change to Bemf zero crossing delay (30 electrical degrees). The timer is set to TIM4. The 'MCU pin mapping' section shows Bemf Phase U (ADC1_IN9 (PC3)), Bemf Phase V (ADC1_IN15 (PB0)), Bemf Phase W (ADC2_IN4 (PA7)), Bemf divider (GPIO_Output (PC9)), and Sampling time (1 μs (47.5 adc clk)). Navigation buttons for '< Prev', 'Next >', '>> OK', and 'X Cancel' are at the bottom right.

3.5.9.7 6-step sensorless start-up parameters

The 6-step algorithm has specific *Sensorless Start-up parameters* settings, available if the selected speed-sensing mode is sensor-less-ADC.

Figure 45. ST MC workbench – 6-step – Sensor-less – Start-up parameters

6-Step Wizard

Project Info

User Interface

Stage

Motor

Power Supply

PWM Generation

Current Sensing

Bus Voltage Sensing

Temperature Sensing

Speed Sensing

Drive Settings

Main Sensor Sensorless start-up parameters

Start-up profile

Initial electrical angle: deg

	Duration (ms)	Speed target (rpm)	Current target (A)
Phase 1:	<input type="text" value="200"/>	<input type="text" value="0"/>	<input type="text" value="0.32"/>
Phase 2:	<input type="text" value="1000"/>	<input type="text" value="600"/>	<input type="text" value="0.32"/>
Phase 3:	<input type="text" value="500"/>	<input type="text" value="600"/>	<input type="text" value="0.32"/>
Phase 4:	<input type="text" value="0"/>	<input type="text" value="0"/>	<input type="text" value="0.32"/>
Phase 5:	<input type="text" value="0"/>	<input type="text" value="0"/>	<input type="text" value="0.32"/>

Execute sensor-less algorithm starting from phase:

Start-up exit condition

Start-up speed threshold: rpm

Consecutive correct measures:

Estimated limits for the speed band tolerance

Lower limit: %

Upper limit: %

< Prev
Next >
>> OK
X Cancel

3.5.10 Drive settings

In the *Drive Settings* step, the user can configure the current regulator as one of the following three control modes.

3.5.10.1 Speed control

This *Drive Settings* mode is always available.

Figure 46. ST MC workbench – Drive settings – Speed control

FOC Wizard

Project Info

User Interface

Stage

- Motor
- Power Supply
- PWM Generation
- Current Sensing
- Bus Voltage Sensing
- Temperature Sensing
- Speed Sensing
- Drive Settings**

Current regulator

Execution time: 63 μ s

Control mode: Speed control

Use MTPA

Feed forward

Auto Calculate Torque/Flux Kp & Ki

Cut-off frequency: 3000 rad/s

Torque (Iq) current regulator

Target: from speed regulator

P: 3012 / 2048 1.4707

I: 241 / 16384 0.01471

Flux (Id) current regulator

Target: 0 A

P: 1506 / 2048 0.73535

I: 241 / 16384 0.01471

Speed regulator

Execution rate: 1 ms

Target speed: 1798 rpm

P: 2816 / 256 11

I: 427 / 16384 0.02606

Auto Calculate Kp & Ki

Flux weakening regulator Off

Block Diagram:

The diagram illustrates the control loop for speed control. It starts with a target speed of 1798 rpm. This target is compared with the actual speed (indicated by a negative feedback arrow) at a summing junction. The resulting error signal is processed by a Speed regulator (PI controller) with a proportional gain of 11 and an integral gain of 0.0261. The output of the speed regulator is the torque reference (Iq), which is compared with the actual Iq current at another summing junction. The error signal is then processed by a Torque (Iq) current regulator (PI controller) with a proportional gain of 1.47 and an integral gain of 0.0147. The output of the torque regulator is the flux reference (Id), which is compared with the actual Id current at a third summing junction. The error signal is processed by a Flux (Id) current regulator (PI controller) with a proportional gain of 0.735 and an integral gain of 0.0147. The output of the flux regulator is the Id current reference, which is compared with the actual Id current at a fourth summing junction. The error signal is processed by a Flux weakening regulator (currently off).

Navigation: < Prev Next > >> OK X Cancel

3.5.10.2 Torque control

This Drive Settings mode is always available.

Figure 47. ST MC workbench – Drive Settings – Torque control

FOC Wizard

Project Info

User Interface

Stage

Motor

Power Supply

PWM Generation

Current Sensing

Bus Voltage Sensing

Temperature Sensing

Speed Sensing

Drive Settings

Current regulator

Execution time: 63 μ s

Control mode: Torque control

Use MTPA

Feed forward

Auto Calculate Torque/Flux Kp & Ki

Cut-off frequency: 3000 rad/s

Torque (Iq) current regulator

Target: 0 A

P: 3012 / 2048 1.4707

I: 241 / 16384 0.01471

Flux (Id) current regulator

Target: 0 A

P: 1506 / 2048 0.73535

I: 241 / 16384 0.01471

Torque (Iq) current regulator diagram:

0 A input to a summing junction (Σ). The output goes to a Proportional (P) block with gain 1.47. The output of the P block goes to an Integral (I) block with gain 0.0147. The output of the I block goes to a second summing junction (Σ).

Flux (Id) current regulator diagram:

0 A input to a summing junction (Σ). The output goes to a Proportional (P) block with gain 0.735. The output of the P block goes to an Integral (I) block with gain 0.0147. The output of the I block goes to a second summing junction (Σ).

< Prev Next > >> OK X Cancel

3.5.10.3 Position control

This *Drive Settings* mode is available only if the quadrature encoder is selected as the main speed-sensing sensor.

Figure 48. ST MC workbench – Drive settings – Position control

FOC Wizard

Project Info
User Interface
Stage
Motor
Power Supply
PWM Generation
Current Sensing
Bus Voltage Sensing
Temperature Sensing
Speed Sensing
Drive Settings

Current regulator

Execution time: 63 μ s
Control mode: Position control

Use MTPA
 Feed forward
 Auto Calculate Torque/Flux Kp & Ki
Cut-off frequency: 3000 rad/s

Torque (Iq) current regulator

Target: from position regulator
P: 3012 / 2048 1.4707
I: 241 / 16384 0.01471

Flux (Id) current regulator

Target: 0 A
P: 1506 / 2048 0.73535
I: 241 / 16384 0.01471

Position regulator

Execution rate: 1 ms
P: 10000 / 1024 9.76563
I: 1000 / 32768 0.03052
D: 1000 / 16 62.5

Flux weakening regulator Off

Position regulator block diagram:
 - Input: Σ
 - P gain: 9.77
 - I gain: 0.0305
 - D gain: 62.5
 - Output: Σ

Torque (Iq) current regulator block diagram:
 - Input: Σ
 - P gain: 1.47
 - I gain: 0.0147
 - Output: Σ

Flux (Id) current regulator block diagram:
 - Input: 0 A
 - P gain: 0.735
 - I gain: 0.0147
 - Output: Σ

< Prev Next > >> OK X Cancel

Revision history

Table 2. Document revision history

Date	Revision	Changes
27-Apr-2022	1	Initial release.

Contents

1	General information	2
2	Related documents	3
3	ST motor-control workbench	4
3.1	Editing field behavior	4
3.2	New project wizard	5
3.2.1	General Info	6
3.2.2	Motors	7
3.2.3	Power board	7
3.2.4	Control board	8
3.2.5	Bridge	8
3.2.6	Kit	9
3.2.7	Inverter	9
3.2.8	Creating the project	9
3.3	Loading an existing project	10
3.4	Project view	11
3.4.1	Toolbar area	11
3.4.2	Hardware information area	13
3.4.3	Project steps and hardware configuration details	16
3.5	Project wizard	16
3.5.1	Product Info	17
3.5.2	User Interface	18
3.5.3	Motor	19
3.5.4	Power Supply	20
3.5.5	PWM Generation	20
3.5.6	Current Sensing	22
3.5.7	Bus voltage sensing	27
3.5.8	Temperature sensing	28
3.5.9	Speed-sensing	28
3.5.10	Drive settings	34
	Revision history	38
	List of tables	40
	List of figures	41

List of tables

Table 1.	Reference documentation	3
Table 2.	Document revision history	38

List of figures

Figure 1.	ST MC workbench – Icon	4
Figure 2.	ST MC workbench – GUI (Home view)	4
Figure 3.	ST MC workbench – Editing field	4
Figure 4.	ST MC workbench – New project window	6
Figure 5.	ST MC workbench – New project window – Motors	7
Figure 6.	ST MC workbench – New project window – Power	7
Figure 7.	ST MC workbench – New project window – Control	8
Figure 8.	ST MC workbench – New project window – Bridge	8
Figure 9.	ST MC workbench – New project window – Kit	9
Figure 10.	ST MC workbench – New project window – Inverter	9
Figure 11.	ST MC workbench – New project creation error	10
Figure 12.	ST MC workbench – Project view	10
Figure 13.	ST MC workbench – Project view (Global view)	11
Figure 14.	ST MC workbench – Close project confirmation window	11
Figure 15.	ST MC workbench – Save menu	12
Figure 16.	ST MC workbench – Project save as window	12
Figure 17.	ST MC workbench – Save and generate	12
Figure 18.	ST MC workbench – Project generation	13
Figure 19.	ST MC workbench – About	13
Figure 20.	ST MC workbench – MCU	14
Figure 21.	ST MC workbench – Pin usage & Conflicts	14
Figure 22.	ST MC workbench – Control board	15
Figure 23.	ST MC workbench – Power board	16
Figure 24.	ST MC workbench – Project Info	17
Figure 25.	ST MC workbench – User interface	18
Figure 26.	ST MC workbench – Motor	19
Figure 27.	ST MC workbench – Motor – Hall effect – Quadrature encoder	19
Figure 28.	ST MC workbench – Power supply	20
Figure 29.	ST MC workbench - PWM Generation - High and low side	21
Figure 30.	ST MC workbench – PWM generation – High side and three enables	22
Figure 31.	ST MC workbench – Current sensing – FOC 3-shunt external amplification	23
Figure 32.	ST MC workbench – Current sensing – FOC 3-shunt internal amplification – Internal gain	24
Figure 33.	ST MC workbench – Current sensing – FOC 3-shunt internal amplification – External gain	25
Figure 34.	ST MC workbench – 6-step – Current mode	26
Figure 35.	ST MC workbench – 6-step – Current mode disabled	26
Figure 36.	ST MC workbench – Current sensing – Over-current protection	27
Figure 37.	ST MC workbench – Bus voltage sensing	27
Figure 38.	ST MC workbench – Temperature sensing	28
Figure 39.	ST MC workbench – Speed-sensing – Observer PLL	29
Figure 40.	ST MC workbench – Speed-sensing – Observer Cordic	29
Figure 41.	ST MC workbench – Speed-sensing – Quadrature encoder	30
Figure 42.	ST MC workbench – Speed-sensing – Hall sensor	31
Figure 43.	ST MC workbench – Speed-sensing – Sensor-less start-up parameters	32
Figure 44.	ST MC workbench – 6-step sensor-less ADC	33
Figure 45.	ST MC workbench – 6-step – Sensor-less – Start-up parameters	34
Figure 46.	ST MC workbench – Drive settings – Speed control	35
Figure 47.	ST MC workbench – Drive Settings – Torque control	36
Figure 48.	ST MC workbench – Drive settings – Position control	37

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