



**Embedded  
Code Generation**  
*DEMO MODEL*

## H-Bridge Converter

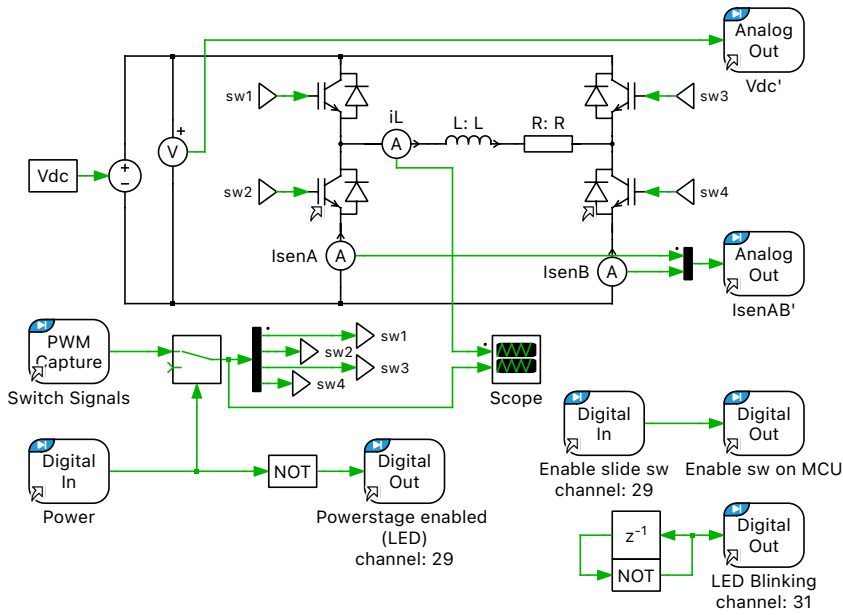
**Current control of an H-bridge converter with embedded code generation for TI C2000 MCUs**

Last updated in C2000 TSP 1.9.1

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**Figure 2: Power circuit of the H-Bridge with inductive load**

## Scaling Analog Outputs

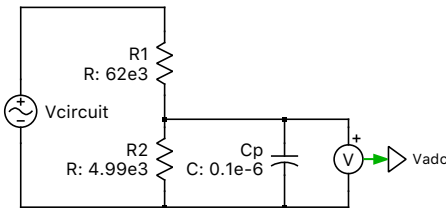
The analog input and output voltage ranges of the PLECS RT Box target are limited between  $-10\text{ V}$  and  $10\text{ V}$ , as set the **Target** tab of the **Coder options...** window.

However, since the Analog Out pins of the RT Box are connected to an embedded controller, these values are scaled and offset to be within  $0\text{ V}$  to  $3.3\text{ V}$ , to satisfy voltage limits of the MCU analog-to-digital converters (ADCs).

Since the plant model is based on a power circuit prototype as described in Section 4, the input voltage and the shunt currents are scaled according to the voltage and current sense circuits of the BOOSTXL-DRV8305EVM BoosterPack.

## Voltage Sensing

A similar voltage sensing circuit as described in [1] is shown in Figure 3.



**Figure 3: Schematic of a voltage sensing circuit**

The equations below show the response of the voltage sensing circuit. A capacitor,  $C_p$  can be selected to create a pole in the sensing circuit to attenuate the switching frequency ripple on the sensed voltage. The pole frequency is denoted as  $f_p$  below.

$$\frac{V_{adc}}{V_{circuit}} = \frac{R_2}{(R_1 + R_2) + sR_1R_2C_p}, \quad C_p = \frac{R_1 + R_2}{2\pi f_p R_1 R_2}$$

The voltages are scaled with a gain of,

$$V_m.K = \frac{R_2}{R_1 + R_2} = \frac{4990}{62000 + 4990}$$

## Current Sensing

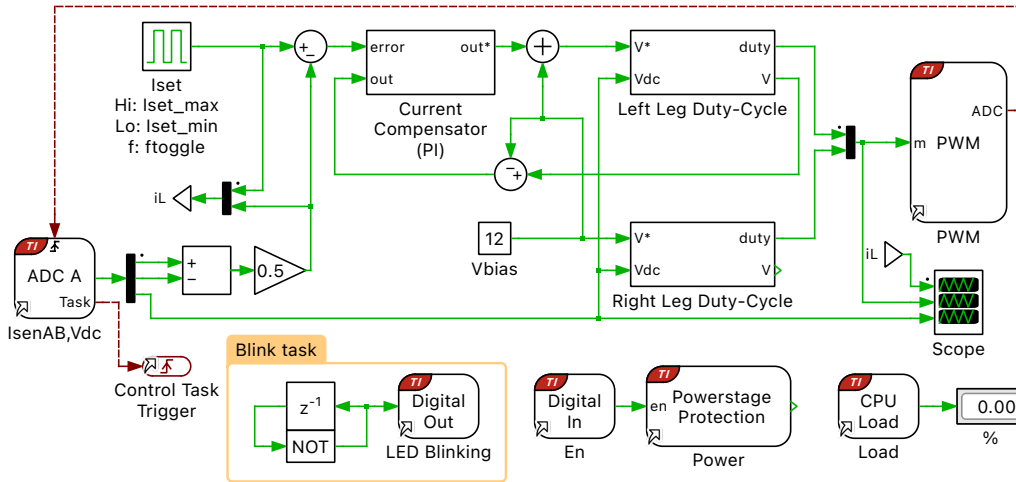
As described in [1], low-side shunt currents are sensed for both of the half bridges. These currents are sensed and amplified with a scaling factor of  $I_m \cdot K$  and offset with offset factor of  $I_m \cdot O$  using a current shunt amplifier.

$$I_m.K = 0.007 * 10$$

$$I_m.O = \frac{3.3}{2}$$

## 2.2 Controls

The controller subsystem is shown in Fig. 4. The “Right Leg Duty-Cycle” subsystem determines the duty cycle required to maintain an average of 12 V at the right leg H-bridge output while accounting for variations in the sensed input voltage,  $V_{dc}$ .



**Figure 4: Controller of the H-Bridge circuit**

The “Left Leg Duty-Cycle” subsystem determines the modulation index of left leg of the H-bridge based on a proportional-integral (PI) controller, as shown in Fig. 5. The sensed inductor current is compared to a setpoint that is toggled between  $-3$  A and  $3$  A. This error is used for current compensation by the digital PI controller, which is equipped with anti-windup logic.

A few of the concepts described in this Section 2.2, related to the controller development, are based on reference [3].

## Plant transfer function

To set the PI controller gain parameters a plant transfer function  $P(s)$  is needed.  $P(s)$  relates the change of the voltage across the inductor ( $L$ ) and resistor ( $R$ ),  $V_{RL}$  (the input variable), to the response of the inductor current  $I_L$  (the output variable):

$$P(s) = \frac{I_L}{V_{RL}} = \frac{1/R}{1 + sL/R} = \frac{K_1}{1 + sT_1}, \quad \text{where } K_1 := 1/R \text{ and } T_1 := L/R$$

## Time constants

For reducing the order of complex systems, it is often useful to distinguish between dominant time constants and small time constants. Typically, the dominant time constants are a part of the plant transfer function, while the control system introduces several small time constants (e.g. sensors, actuators, sampling, calculation delays, fast inner control loops).

If the largest small time-constant is at least 4 times smaller than the smallest dominant time constant, i.e.,

$$\min(T_{\text{dominant}}) \geq 4 \cdot \max(T_{\text{small}})$$

then it is possible to make an important simplification for modeling of the system, which is to define one equivalent small time constant which is the sum of all small time constants in the system.

If the controller sampling frequency ( $1/T_s$ ) is same as the switching frequency ( $1/T_{\text{sw}}$ ), the small time constants present in the H-bridge converter model for this specific implementation are:

- small time constant for control calculation,  $T_{\text{calc}}$ , is  $\frac{1}{2} T_{\text{sw}}$
- small time constant for PWM output generation,  $T_{\text{pwm}}$ , is  $\frac{1}{2} T_{\text{sw}}$
- small time constant for conversion of continuous parameters to discrete,  $T_{\text{sh}}$ , is  $\frac{1}{2} T_{\text{sw}}$  (explained in the section below)

The equivalent small time constant,  $T_{\Sigma}$ , is

$$T_{\Sigma} = T_{\text{calc}} + T_{\text{pwm}} + T_{\text{sh}}$$

$$D_{\Sigma}(s) = \frac{1}{1 + sT_{\Sigma}}$$

## Calculation of control parameters

The control parameters of the PI controller ( $K_p$  and  $K_i$ ) are calculated using the Magnitude Optimum Criterion. The system's open-loop transfer function  $H_{\text{OL}}(s)$  is given by the product of transfer functions from the controller, plant and time delays:

$$H_{\text{OL}}(s) = \frac{1 + sT_n}{sT_i} \cdot \frac{K_1}{1 + sT_1} \cdot \frac{1}{1 + sT_{\Sigma}}, \quad \text{where } K_p = \frac{T_n}{T_i} \text{ and } K_i = \frac{1}{T_i}$$

The controller parameter  $T_n$  is chosen, such that the pole of the plant transfer function is canceled, i.e.  $T_n = T_1$ . After pole-zero cancellation, the closed-loop transfer function is a second order system. The remaining parameter  $T_i$  is calculated from setting the damping factor ( $\zeta$ ) of the second order system to  $1/\sqrt{2} = \zeta$ , resulting in  $T_i = 2K_1T_{\Sigma}$

## Transformation of continuous control parameters to discrete

The digital implementation of a PI regulator can be written as

$$y[k] = K_{\text{pz}} e[k] + K_{\text{iz}} \sum_{i=0}^k e[i]$$

If the sample time ( $T_s$ ) is sufficiently less than the smallest time constant of the PI regulator, i.e.

$$T_s \leq \frac{T_n}{2}$$

then the sum  $\sum_{i=0}^k e[i]$  can be approximated by an equivalent transfer function:

$$\sum e[i] \approx \frac{1 + sT_s/2}{sT_s}$$

With this, the following relationship between the continuous and discrete PI regulator can be obtained:

$$K_{pz} = \frac{T_n - T_s/2}{T_i}$$

$$K_{iz} = \frac{T_s}{T_i}$$

However, the sample & hold at the input of a digital regulator adds an additional delay which must be taken into account during the continuous time design:

$$SH(s) = \frac{1}{1 + sT_s/2}$$

## Anti-windup

When the actuator of a control system reaches its limits, or saturates, the plant ceases to respond to changes in the control output and the control system cannot reduce the control error. Under these conditions it is important to prevent integrators in the controller from reaching extreme values, referred to as windup. One approach to prevent windup is to keep the integrator,  $I$  in Fig. 5, at the same value as the saturated output,  $y'$ . This ensures that when the error (eventually) decreases below zero, changes in the integrator output ( $i$ ) will not be limited by controller saturation.

In saturation:

$$I = y'$$

$$\dot{i} = 0$$

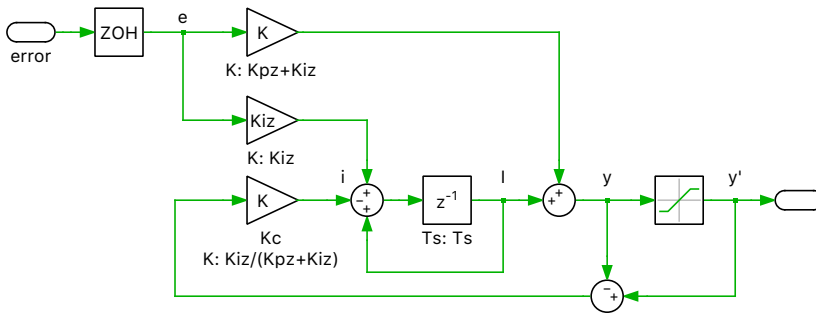
Therefore, the anti-wind up corrective gain ( $K_c$ ) can be calculated as:

$$\dot{i} = K_{iz} \cdot e - K_c(I + e(K_{pz} + K_{iz}) - y') = 0$$

$$\dot{i} = K_{iz} \cdot e - K_c(y' + e(K_{pz} + K_{iz}) - y') = 0$$

$$K_c = \frac{K_{iz}}{K_{pz} + K_{iz}}$$

The overall structure of the PI controller including anti-windup is given in Fig. 5.



**Figure 5: Proportional-Integral controller with anti-windup**

## Configuring TI C2000 Target library components

The controller in Fig. 4 contains several components from the TI C2000 Target library. The gate signals are generated by the PWM component, where the left and right leg duty cycles are inputs to the PWM block. The duty cycles are in the range of [0, 1] for generating gate signals. The **Carrier type**, **Carrier frequency** and **Dead time** parameters can be configured from the **Main** tab of the PWM block parameters window. Please note that the input to the ePWM module generates a complementary PWM pair, i.e. ePWMxA and ePWMxB will be opposite polarity excluding the dead time.



TI 28069 [6], TI 28379D [8], TI 28P550SJ9 [9], TI 28P650DK9 [10] LaunchPads, and the TI 28388D [13] controlCARD.

Additionally, the demo model allows for code generation for the TI 28377S [7] LaunchPad, as well as the TI 280039C [11] and TI 28379D [12] controlCARDs. To configure this, go to the **Model initialization commands** window from the **Simulation + Simulation Parameters... + Initializations** menu, and change the value of `board_type`, to select the desired board. You must also configure the corresponding **Target** and **Board** type in the **Coder Options** window accordingly.

Follow the instructions below to upload the “Controller” subsystem to a TI MCU.

- Connect the MCU to the host computer through a USB cable.
- From the **System** tab of the **Coder + Coder options...** window, select “Controller”.
- Next, from the **Target** tab, select the appropriate target from the dropdown menu. Then under the **General** sub-tab, select the desired **Build type**.
- Then, to Build and program the MCU directly from PLECS, choose either Run from Flash or Run from RAM as the **Build configuration** to program the MCU either to flash memory or to RAM respectively, then select LaunchPad as the **Board** type, and click **Build**.

If programmed correctly, the LED corresponding to GPIO “DO\_DSP\_LED” listed in the model initialization commands should blink.

For advanced users who are familiar with Code Composer Studio, there is an option to Generate code into CCS project. Locate the appropriate cg folder from the CCS project (refer to [14] for step-by-step instructions), enter its path into the **CCS project directory** field and click **Build**. The code of the “Controller” subsystem will be automatically generated. Then, proceed to build and debug the project as a normal CCS project.

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**Note** If using the RT Box LaunchPad Interface board, make sure that the **RST** jumper is open throughout the simulation.

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Prior to controlling a real power stage with the programmed MCU, it is highly recommended to first verify the behavior of the controller using a PLECS RT Box and perform a hardware-in-the-loop (HIL) test. A typical hardware configuration is shown in Fig. 7, where the evaluation board, a TI 28069 LaunchPad (the red board), is connected to the RT Box via an RT Box LaunchPad Interface (the green board).



**Figure 7: Hardware setup of the HIL verification**

Follow the instructions below to run a real-time model on the RT Box. Before building on the RT Box, ensure that you have already built the “Controller” subsystem on the appropriate TI MCU.



- From the **System** tab of the **Coder + Coder options...** window, select “Plant”. Click the **Target** tab and select a target device. Then click **Build** to deploy the model to the target RT Box.
- Once the model is uploaded, from the **External Mode** tab of the **Coder options...** window, **Connect** to the RT Box and **Activate autotriggering** to observe the test results in real-time.

If programmed correctly, the LED corresponding to “DO-31” of the RT Box LaunchPad Interface board should blink.

Toggle the switch “DI-29” on the RT Box LaunchPad Interface board from low to high to enable the MCU, as explained at the end of Section 2.2. When the power stage is enabled, the LED corresponding to “DO-29” of the LaunchPad interface board should turn on. Observe the real-time waveforms in the Scope of the “Plant” subsystem.

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**Note** At this stage, verify that the LED corresponding to “DO-29” on the RT Box LaunchPad Interface board is turned on.

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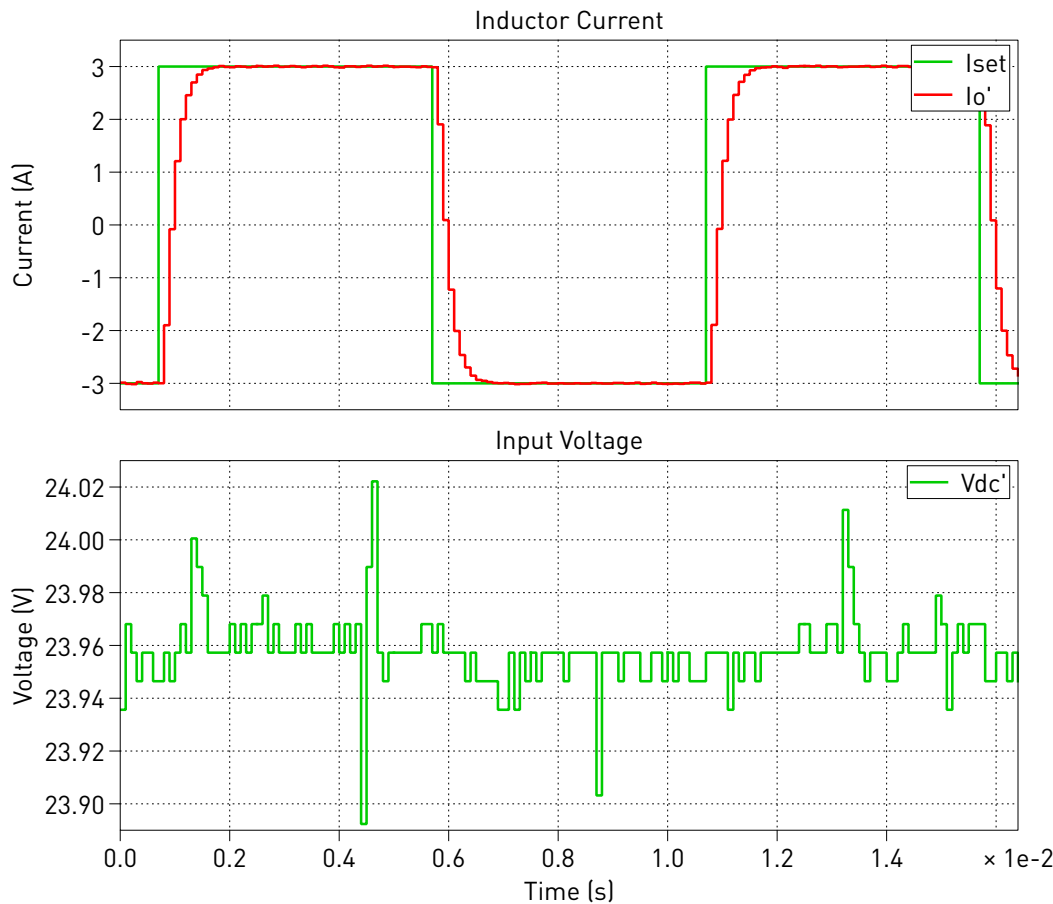
Toggling the switch “DI-29” on the RT Box LaunchPad Interface board from high to low should disable all the gating signals. “DO-29” of the LaunchPad Interface board should turn off. Toggling “DI-29” back to high will enable the PWM outputs once again.

In order to tune the parameters of the control program in the MCU and observe any intermediate values, follow the instructions below to connect to the external mode of the TI MCU.

- First, **Disconnect** the “Plant” subsystem from the **External Mode** of the PLECS RT Box, if connected.
- Then, from the **System** menu on the left hand side of the **Coder + Coder options...** window, select “Controller”.
- Next, from the **External Mode** tab, select the appropriate **Target device** and click **Connect**.
- Then, **Activate autotriggering** to observe the test results in the “Controller” subsystem Scope.

The inductor current measurements can be viewed using the scope found in the “Plant” subsystem as well as the scope in the “Controller” subsystem. The inductor current reference is toggled between  $-3\text{ A}$  and  $3\text{ A}$  using the “Iset” (Pulse Generator) component of the “Controller” subsystem. These reference values can be changed on the fly, in real-time, since the “Iset” component has been added to the “Exceptions” list found in the **Parameter Inlining** tab of the **Coder options...** window, prior to building the model.

The step response of the inductor current in real-time is shown in Fig. 8.



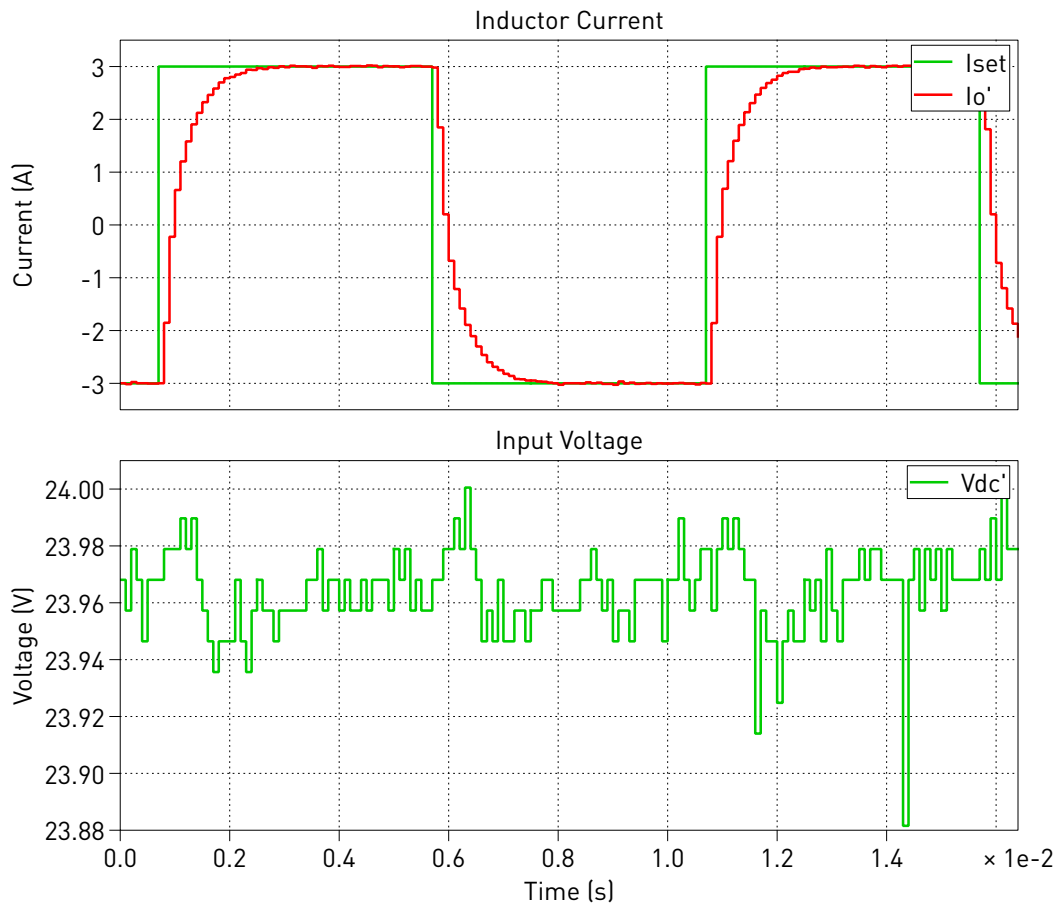
**Figure 8: Inductor current and input voltage measurements in real-time using the PLECS RT Box 1**

A trigger control for a desired **Trigger channel** can be set from the **External Mode** tab.

## 4 Power Circuit Prototype

A hardware prototype of the power circuit, comprising two phases of a BOOSTXL-DRV8305EVM BoosterPack [1] connected to an external RL load, is used to verify the circuit. The GPIOs listed in the demo model for the 28069 LaunchPad are fully compatible with the BoosterPack.

After deploying the code and connecting to the 28069 LaunchPad target, as described in 3, the current and voltage measurements can be viewed using the scope found in the “Controller” subsystem, as shown in Fig. 9.



**Figure 9: Inductor current and input voltage measurements of the power circuit prototype**

Notice how the real-time simulation results using the PLECS RT Box match the results with the hardware prototype.

## 5 Conclusion

This model demonstrates an H-bridge converter with a discrete current controller that supports embedded code generation for TI C2000 MCUs. It can be run in both offline mode, as well as in real-time. The model has also been verified with a power circuit prototype. The model also demonstrates the **Parameter Inlining** feature using a current controller reference that can be changed in real-time.

## References

- [1] TI DRV8305N 3-Phase Motor Drive BoosterPack Evaluation Module  
URL: <http://www.ti.com/tool/BOOSTXL-DRV8305EVM>.
- [2] J. Allmeling, and N. Felderer, "Sub cycle average models with integrated diodes for real-time simulation of power converters," *IEEE Southern Power Electronics Conference (SPEC)*, 2017.
- [3] Conception de Systèmes automatiques, Hansruedi Bühler, Presses Polytechniques Romandes, Lausanne 1988, ISBN 2-88074-149-1
- [4] TI C2000 F280039C LaunchPad development kit,  
URL: <http://www.ti.com/tool/LAUNCHXL-F280039C>.

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- [9] TI C2000 F28P550SJ9 LaunchPad development kit,  
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- [11] TI C2000 F280039C controlCARD evaluation module,  
URL: <https://www.ti.com/tool/TMDSCNCD280039C>.
- [12] TI C2000 F28379D controlCARD development kit,  
URL: <https://www.ti.com/tool/TMDSCNCD28379D>.
- [13] TI C2000 F28388D controlCARD evaluation module,  
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- [14] PLECS TI C2000 Target Support User Manual,  
URL: <https://www.plexim.com/download/documentation>.

## Revision History:

C2000 TSP 1.1	First release
C2000 TSP 1.3.1	Turn on Assertions in the two IGBT Half Bridge power modules
C2000 TSP 1.4.5	Updated the web links
C2000 TSP 1.5.1	Added support for 28388D and 28379D controlCARD targets, and minimized the usage of double-precision math in the controller
C2000 TSP 1.6.1	Added support for 280039C LaunchPad and controlCARD targets, and auto-pin selection
C2000 TSP 1.9.1	Added support for 28P550SJ9 LaunchPad target

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