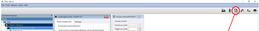
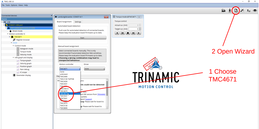
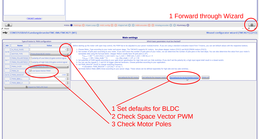
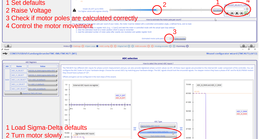

2 Open Wizard
1 Choose TMC4671


TMCL Wizard
1 Forward through Wizard

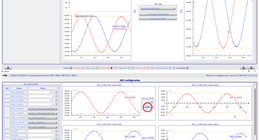
1 Set defaults for BLDC
2 Check Space Vector PWM
3 Check Motor Poles

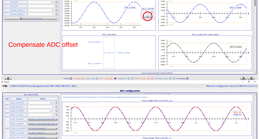

1 Set defaults
2 Raise Voltage
3 Check if motor poles are calculated correctly
4 Control the motor movement

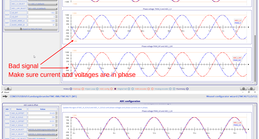
1 Load Sigma-Delta defaults
2 Turn motor slowly

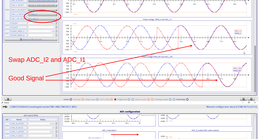

Compensate ADC offset

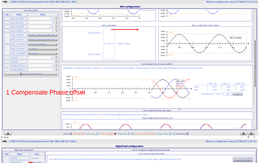
Bad signal
Make sure current and voltages are in phase


Swap ADC_I2 and ADC_I1
Good Signal


1 Compensate Phase offset


Change Encoder direction bit if necessary

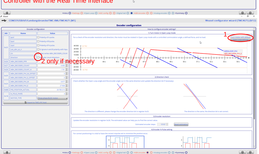

1 Change HALL_PHI_E_OFFSET if necessary.
Shift of 22000 is equal 180°

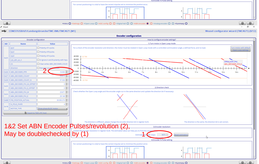

Set PID_FLUX_P and PID_TORQUE_P to 100
It is recommended to do Tuning of the Current
Controller with the Real Time Interface
1
2

2 only if necessary
1

1&2 Set ABN Encoder Pulses/revolution (2).
May be doublechecked by (1)
1
2

Compensate encoder offset with two options:
- Offset estimation (motor will move)
- with Hall sensors)
1
2


Offset estimation used


Offset estimation (motor will move)