

Stepper Motors 10: Stall Detection

TI Precision Labs – Motor Drivers

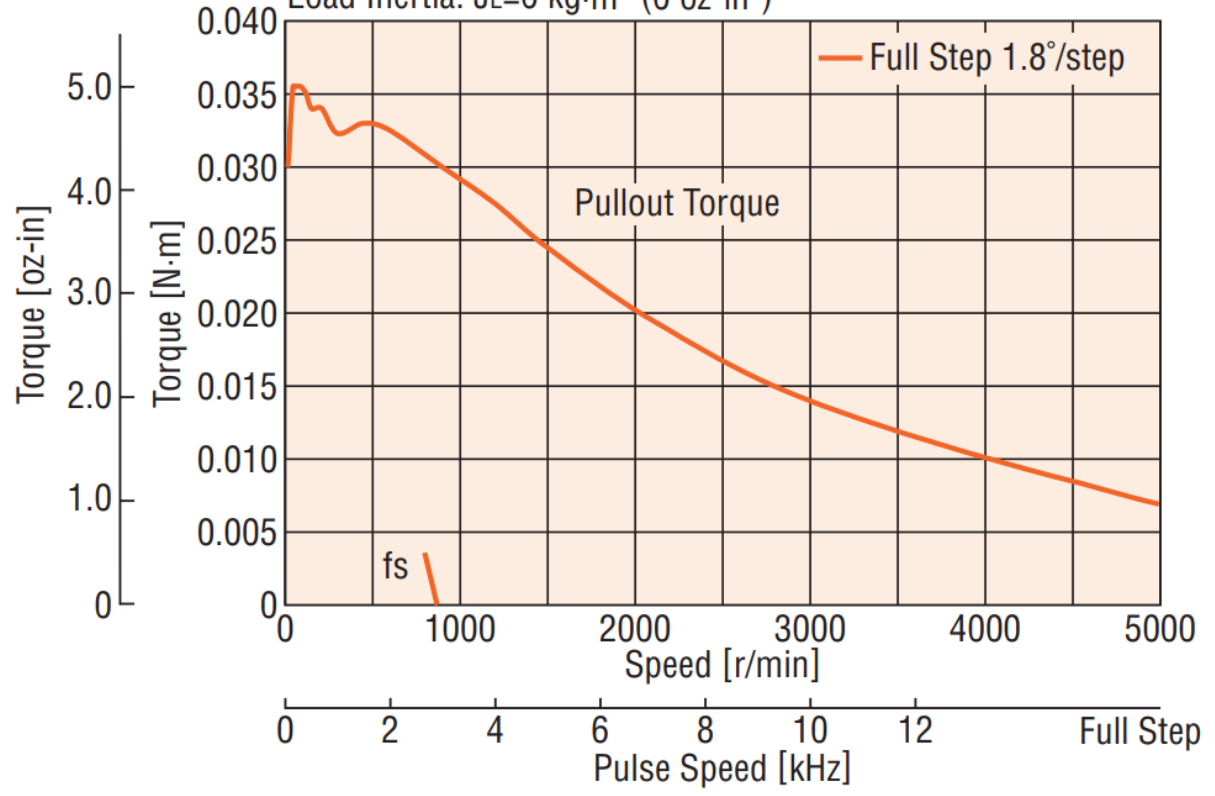
Presented and prepared by Pablo Armet

What is a stall condition?

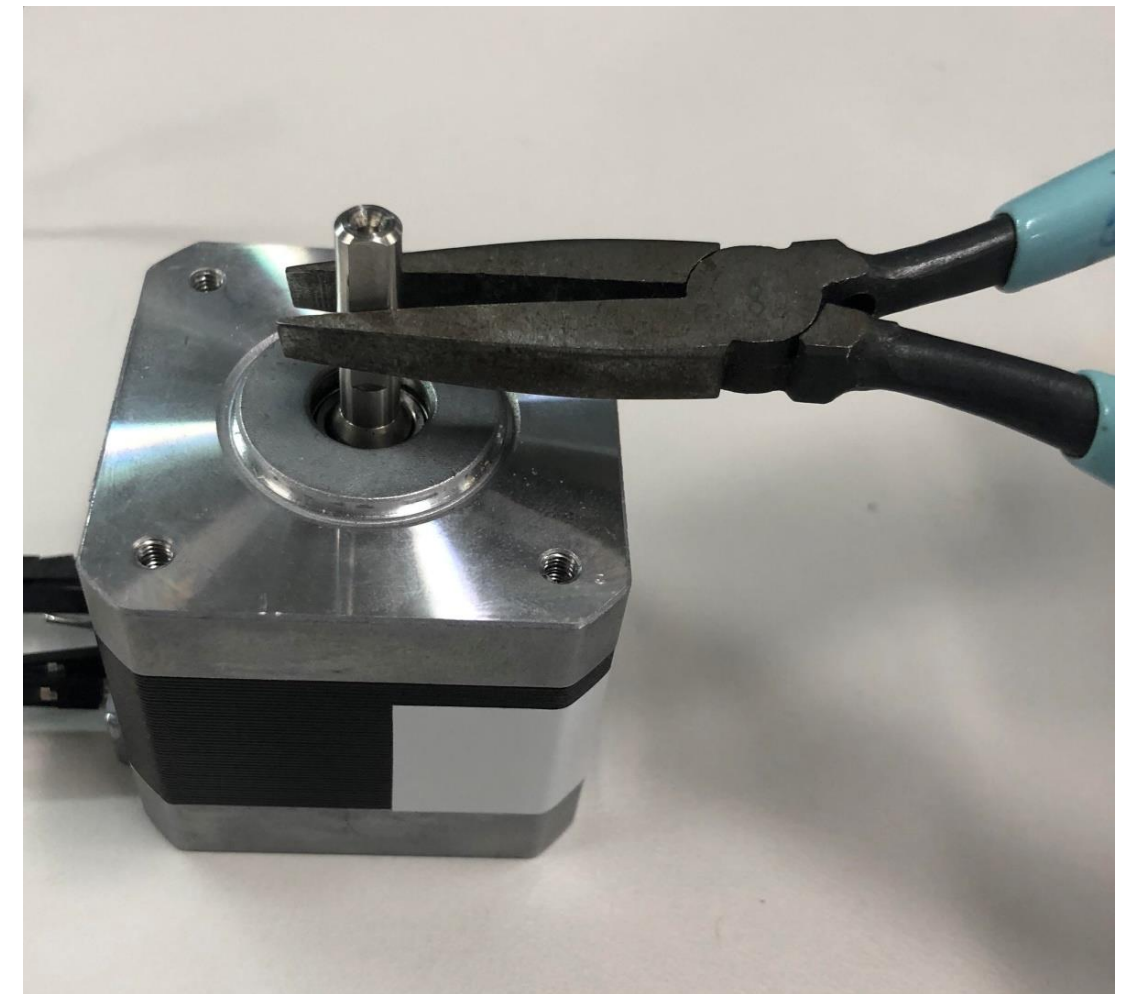
- Stall condition: load torque exceeds the motor's pull-out torque. [1]

PKP214D06

Bipolar Constant Current Driver Power Supply Voltage: 24 VDC
Current: 0.6 A/Phase (At 2-phase excitation)
Load Inertia: $J_L=0 \text{ kg}\cdot\text{m}^2$ (0 oz-in²)



Oriental Motor [2]



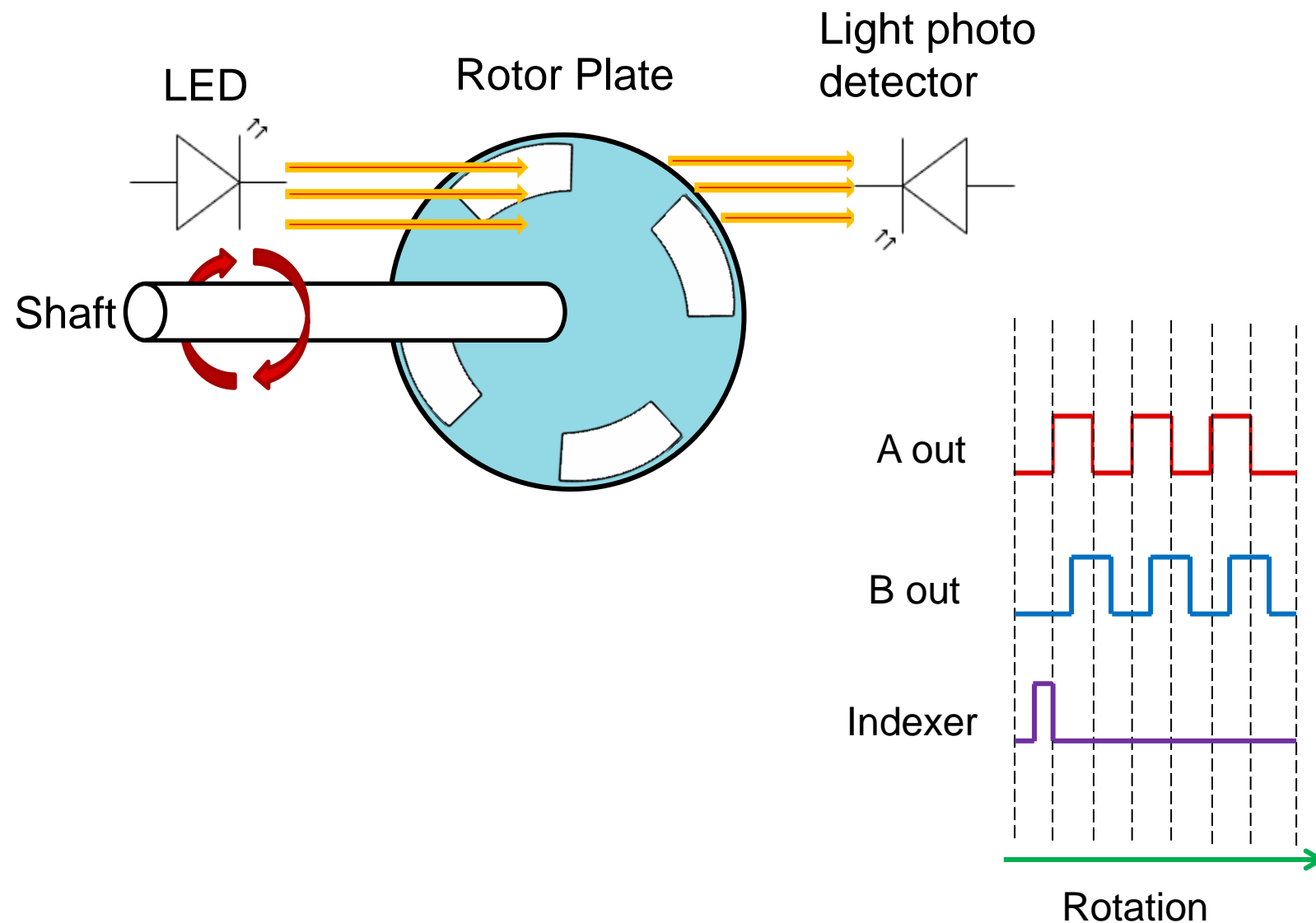
Need for sensor-less stall detection

- Lack of feedback in open-loop motor systems
- End-of-line travel and fixed mechanical stop detection
- Helps lessen the problems that occur when a motor continues to be driven though an obstacle such as:
 - Mechanical failures
 - Audible noise
- Replaces expensive motor position modules

Applications



Existing solution: encoder



- **Benefits:**
 - Multifunctional
 - Robust
- **Drawbacks:**
 - High cost
 - Increase in system area

Existing solution: sensor-less back-emf measurement

- Back-emf in stepper motors:

$$BEMF = -p * \Psi_m * \omega * \sin(p * \omega * t)$$

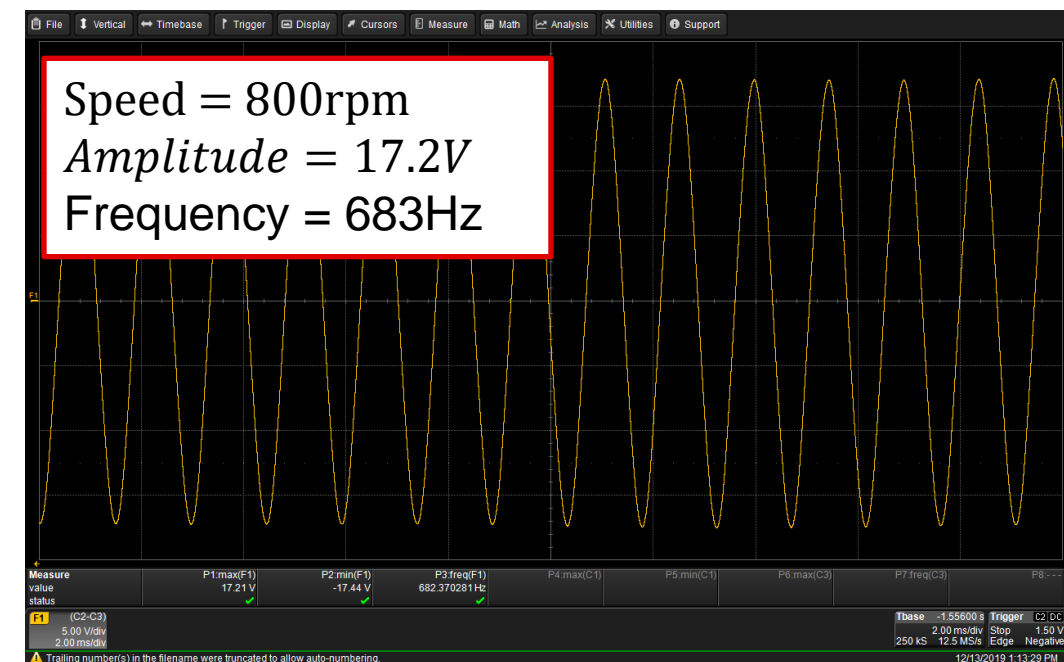
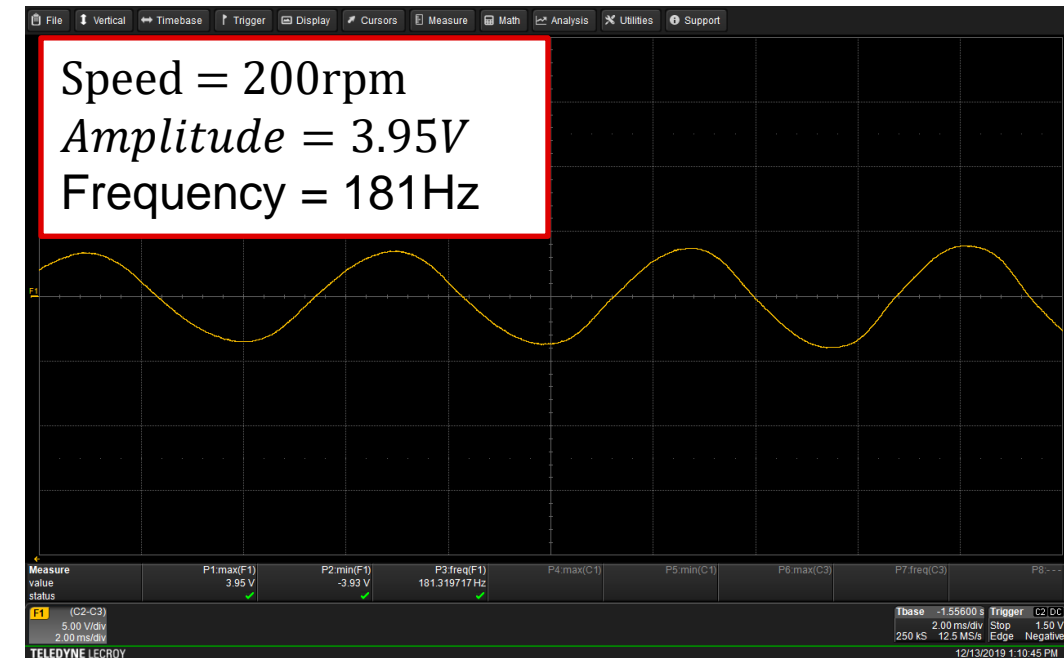
- p : number of pole pairs
- Ψ_m : maximum magnetic flux
- ω : motor angular speed

- Benefits:

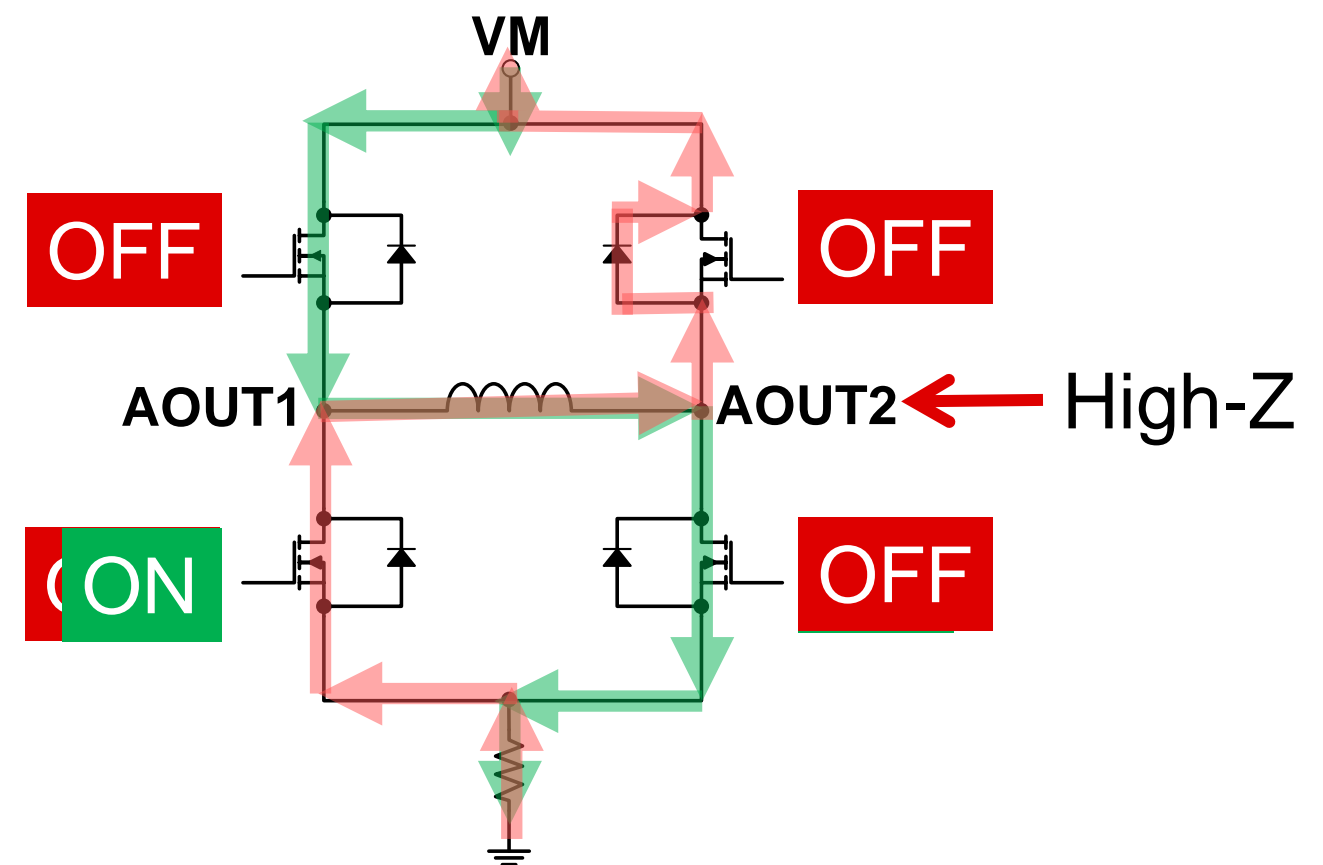
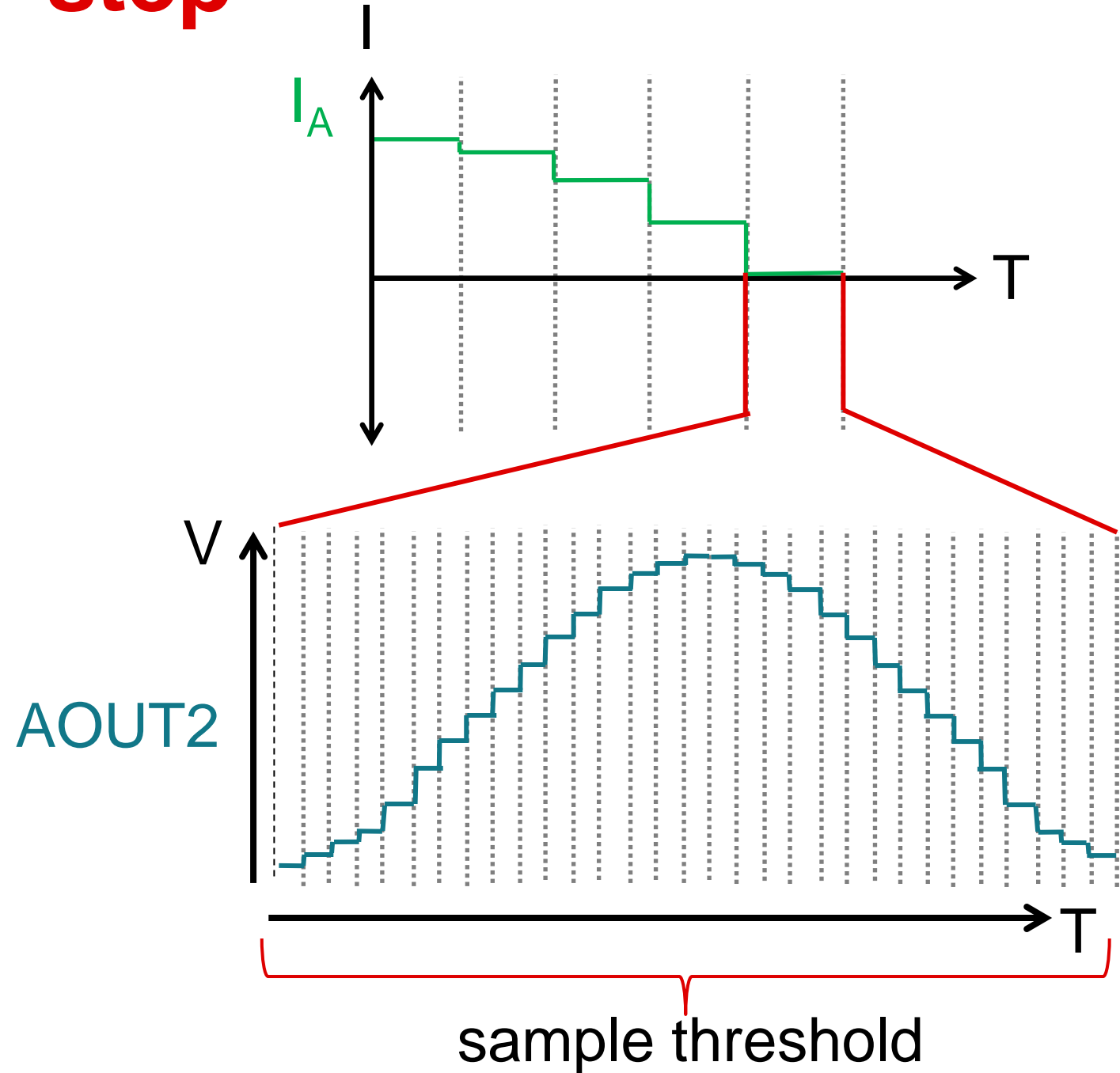
- Sensor-less solution
- Reduces design cost and size

- Drawbacks:

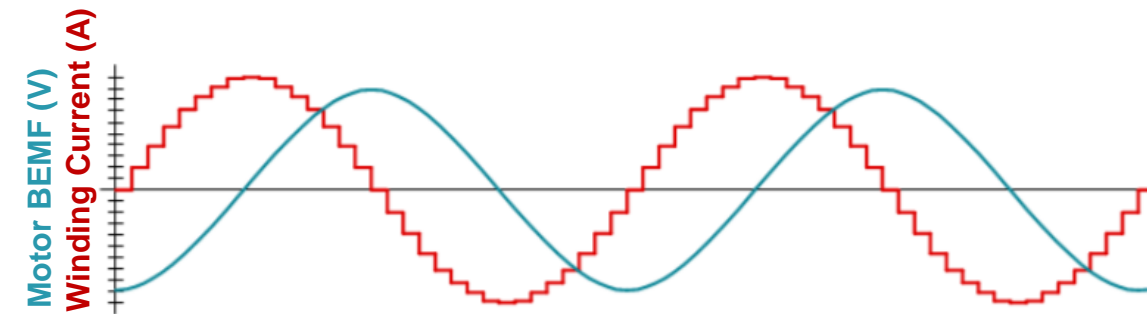
- Minimum motor running speed



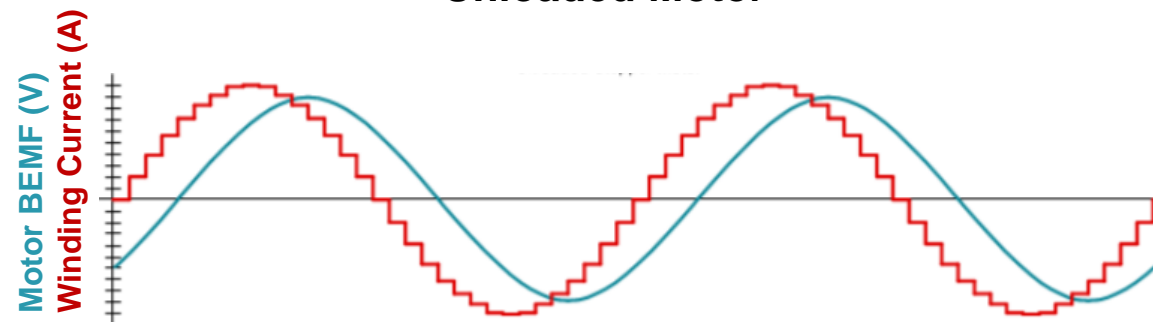
Direct back-emf measurement during zero current step



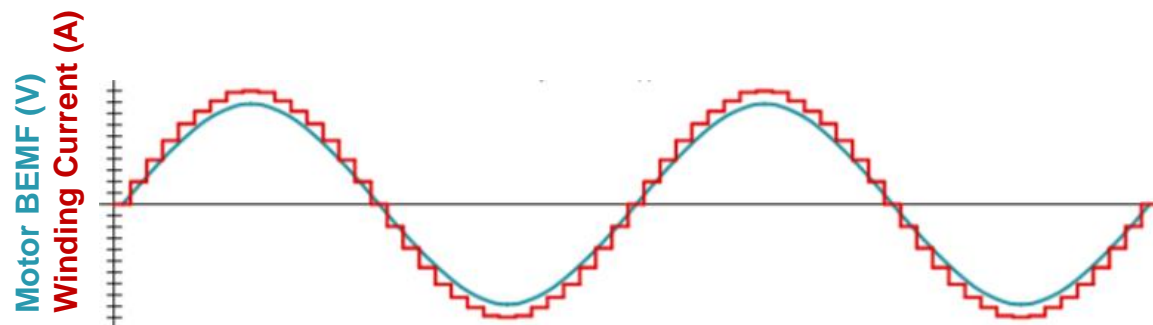
Indirect back-emf measurement



Unloaded Motor



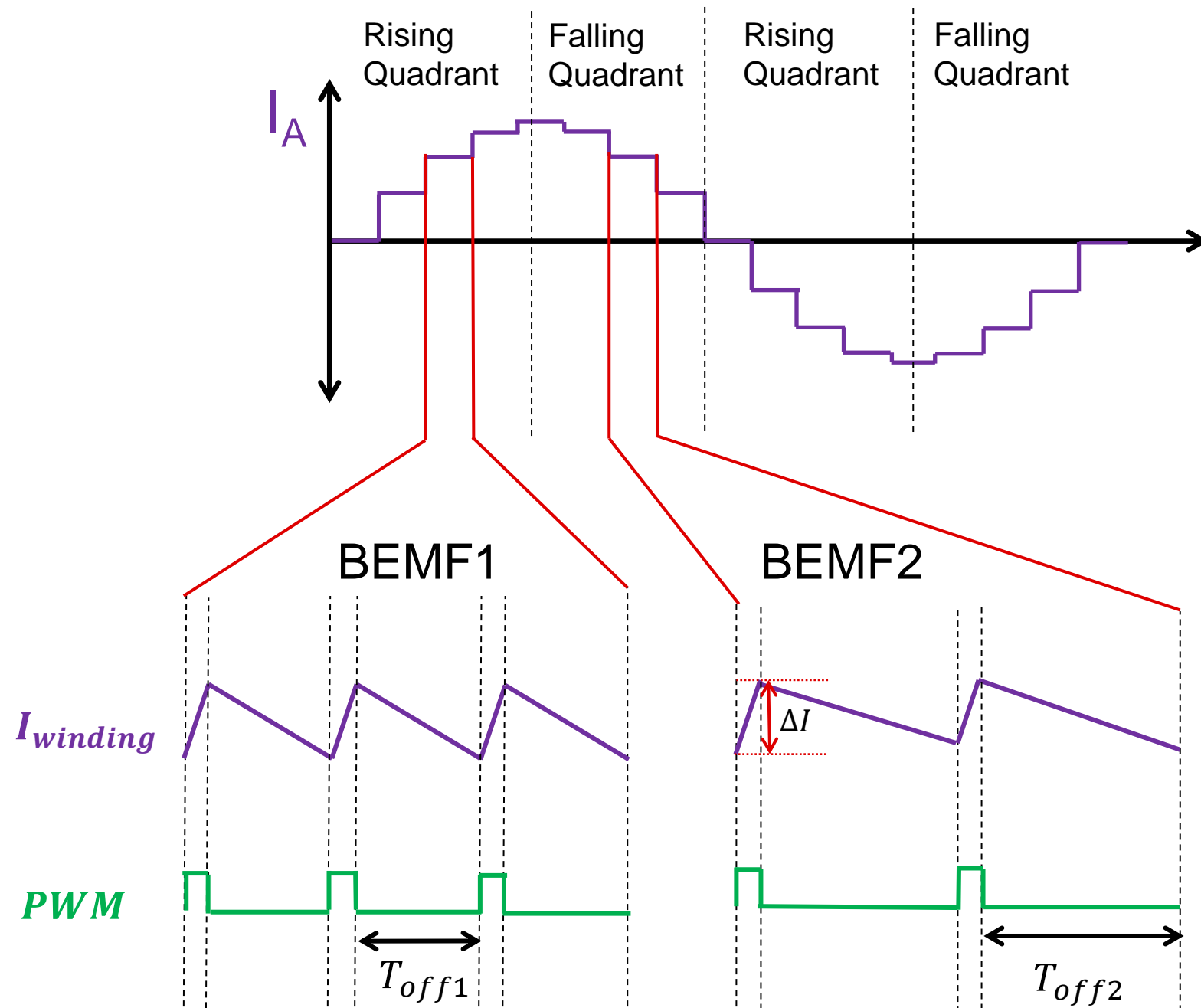
Partially Loaded Motor



Loaded Motor

- Benefits:
 - Constant back-emf monitoring.
- Drawbacks:
 - Current regulation waveform dependencies on supply voltage, motor current, and motor resistance

TI solution: fixed current ripple method



$$T_{off} = \frac{L * \Delta I}{I * R - BEMF}$$

$$\frac{1}{T_{off1}} - \frac{1}{T_{off2}} = \frac{\Delta BEMF}{L * \Delta I}$$

$$\Delta BEMF = BEMF2 - BEMF1$$

Normal operation: $\Delta BEMF > 0$

Stall Condition: $\Delta BEMF = 0$

Summary

	Advantages	Disadvantages
Encoder	<ul style="list-style-type: none">• Precise motor position monitoring• Can work at very low speeds	<ul style="list-style-type: none">• Higher cost• Larger system area size
Direct back-emf measurement	<ul style="list-style-type: none">• Reduce design system cost and size	<ul style="list-style-type: none">• Minimum motor speed required• Does not work in full-step mode.
Indirect back-emf measurement	<ul style="list-style-type: none">• Reduce system cost and size• Works for all micro-step settings	<ul style="list-style-type: none">• Minimum motor speed required• Can be affected by supply voltage, motor current, and motor resistance variations

To find more stepper driver technical resources and search products, visit <http://www.ti.com/motor-drivers/stepper-driver/overview.html>

Resources

- [1] Acarnley, Paul P. *Stepping motors: a guide to theory and practice*. 4th ed., Institution of Engineering and Technology, 2007.
- [2] “[PKP Series Product Catalog](#)”, orientalmotor.com



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